

CIT478

=====

1. The process by which an operator specifies only the task and the robot manages itself to complete it is called

Full autonomy

Supervisory

--->> Task-level autonomy

Teleoperation

2. All of the following are locomotion methods for robots except

--->> running

skating

snaking

flying

3. The performance measure characterizes how successful an agent is. It is usually
an objective measure

--->> a subjective measure

neutral

none of the above

4. What is the name of the First installed industrial robot invented in 1961 by George Devol?

Palletizer

Famulus

Elektro

--->> Unimate

5. The study of motion can be divided into two namely

Whatsapp: 08089722160 or click here for TMA assistance

Practice E-exams & Chat with course mates on noungeeks.net

mechanics and dynamics

--->> kinematics and dynamics

none of the options

6. The science and technology of machines that see

Sensing

--->> Vision

NLP

none of the options

7. An operation involving an Effector is called

Actuator

--->> Action

Sequence

Percept

8. _____ refers to the opposite case in which required joint values are calculated for given end effector values, as done in path planning

inverse mechanics

--->> inverse kinematics

inverse dynamics

none of the options

9. GIGO stands for

Gamble in, Gamble out

--->> Garbage In, Garbage Out

Good in, Good out

none of the options

Join group: T.me/NOUNSTUDENTSFORUM
CLICK TO DOWNLOAD MORE TMA PQ

Task-level autonomy

Supervisory

--->> Teleoperation

Full autonomy

Whatsapp: 08089722160 or click here for TMA assistance

Practice E-exams & Chat with course mates on noungeeks.net