GDAŃSK UNIVERSITY OF TECHNOLOGY

Subject card

Subject name and code	Robotics, PG_00064813		
Field of study	Mechanical Engineering		
Date of commencement of studies	February 2027	Academic year of realisation of subject	2026/2027
Education level	second-cycle studies	Subject group	Obligatory subject group in the field of study Subject group related to scientific research in the field of study
Mode of study	Full-time studies	Mode of delivery	at the university
Year of study	1	Language of instruction	Polish
Semester of study	1	ECTS credits	2.0
Learning profile	general academic profile	Assessment form	assessment
Conducting unit	Institute of Mechanics and Machine Design -> Faculty of Mechanical Engineering and Ship Technology -> Faculties of Gdańsk University of Technology		
Name and surname of lecturer (lecturers)	Subject supervisor	dr inż. Michał Mazur	
	Teachers		

Lesson types

Lesson type	Lecture	Tutorial	Laboratory	Project	Seminar	SUM
Number of study hours	15.0	0.0	15.0	0.0	0.0	30

E-learning hours included: 0.0

Learning activity and number of study hours

Learning activity	Participation in didactic classes included in study plan	Participation in consultation hours	Self-study	SUM
Number of study hours	30	5.0	15.0	50

Subject objectives

Expanding knowledge about robots and manipulators. Some specific issues relating to the actors, sensors and control systems.

Learning outcomes

Course outcome	Subject outcome	Method of verification
[K7_K11] is aware of importance of professional acting, the need for critical verification of acquired knowledge and consulting experts opinion in case of facing difficulties with individual problem solving	is aware of importance of professional acting, the need for critical verification of acquired knowledge and consulting experts opinion in case of facing difficulties with individual problem solving when using robotic systems	[SK1] Assessment of group work skills [SK2] Assessment of progress of work [SK3] Assessment of ability to organize work [SK4] Assessment of communication skills, including language correctness [SK5] Assessment of ability to solve problems that arise in practice
[K7_W01] explains and describes, on the basis of general knowledge of the scientific disciplines forming the theoretical basis of Mechanics and Mechanical Engineering, the structure and principles of operation of mechanical systems and processes	explains and describes, on the basis of general knowledge of the scientific disciplines forming the theoretical basis of Mechanics and Mechanical Engineering, the structure and principles of operation of robots and robotic systems	[SW1] Assessment of factual knowledge
[K7_W12] identifies and interprets the main developmental trends and significant new achievements in the field of engineering and technical sciences and disciplines relevant to the course of study	identifies and interprets the main developmental trends and significant new achievements in the field of engineering and technical sciences and disciplines relevant to the course of robotics	[SW2] Assessment of knowledge contained in presentation [SW3] Assessment of knowledge contained in written work and projects

<table>
<tr><td>Subject contents</td><td>Course content – lecture

LECTURE: 1 Introduction 2 Modern trends in the development of two industrial robots 3 Sensors 4 Signal Conditioning 5 Tactile and haptic sensors 6 Methods of localization of mobile robots 7 Effectors 8 Elements of power supply systems 9 Drive chain elements used in robots 10 Tools for robot programming and simulation

Laboratory: 1 Programming delta type robot task for ABB IRB360 robot 2 Programming collaborative robot tasks for HCR3a robot using OnRobot vision system 3 Programming of industrial robot movements with force sensor feedback for Nachi NC04 robot</td></tr>
<tr><td>Prerequisites and co-requisites</td><td>Basics of mathematics, mechanics and automation, the ability to program engineering calculations.</td></tr>
<tr><td>Assessment methods and criteria</td><td><table>
<tr><th>Subject passing criteria</th><th>Passing threshold</th><th>Percentage of the final grade</th></tr>
<tr><td>Midterm colloquium</td><td>50.0%</td><td>60.0%</td></tr>
<tr><td>Team projects</td><td>50.0%</td><td>40.0%</td></tr>
</table></td></tr>
<tr><td>Recommended reading</td><td><table>
<tr><td>Basic literature</td><td>Craig J., J., Wprowadzenie do robotyki. Mechanika i sterowanie, WNT, Warszawa 1993 Honczarenko J., Roboty przemysłowe. Budowa i zastosowanie, WNT, Warszawa 2002 Jarzębowska E., Podstawy dynamiki mechanizmów i manipulatorów, Oficyna Wydawnicza Politechniki Warszawskiej, Warszawa 1998 Morecki A., Knapczyk J., Podstawy robotyki. Teoria i elementy manipulatorów i robotów, WNT, Warszawa 1993 Morecki A., Knapczyk J., Kędzior K., Teoria mechanizmów i manipulatorów, WNT, Warszawa 2002 Vidyasagar M., Spong Mark W.: Dynamika i sterowanie robotów. WNT, Warszawa 1997</td></tr>
<tr><td>Supplementary literature</td><td>Dulęba I., Metody i algorytmy planowania ruchu robotów mobilnych i manipulacyjnych, Akademicka Oficyna Wydawnicza EXIT, Warszawa 2001 Giergiel M. J., Hendzel Z., Żylski W.: Modelowanie i sterowanie mobilnych robotów kołowych. PWN, Warszawa 2002 Tchoń K., Mazur A., Dulęba I., Hossa R., Muszyński R.: Manipulatory i Roboty Mobilne. Modele, planowanie ruchu, sterowanie. Warszawa: Akademicka Oficyna Wydawnicza PLJ 2000</td></tr>
<tr><td>eResources addresses</td><td></td></tr>
</table></td></tr>
<tr><td>Example issues/ example questions/ tasks being completed</td><td>What is a sensor? Advantages and disadvantages of digital sensors? Advantages and disadvantages of analog sensors? Discuss conditioning. Haptic systems.Robots development trends. Advantages and disadvantages of ultrasonic sensors for distance measurement. List the location methods. Techniques for measuring distance. Advantages and disadvantages of monolithic architecture. Advantages and disadvantages of distributed architecture. Robust programming - fault detection techniques. Application of real-time systems in robot control. What is SLAM? What do we use quaternions for? Discuss Spherical Linear Interpolation Applications of dual quaternions. What is ROS? Discuss MoveIT Discuss 2D Navigation in a ROS environment Discuss the control of the qaudrocopeter What is Zero Moment Point?</td></tr>
<tr><td>Practical activites within the subject</td><td>Not applicable</td></tr>
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