

SAGI RAMA KRISHNAM RAJU ENGINEERING COLLEGE (AUTONOMOUS)

(Affiliated to JNTUK, Kakinada), (Recognized by AICTE, New Delhi) UG Programmes CE,CSE,ECE,EEE,IT & ME are Accredited by NBA, Accredited by NAAC with A⁺ CHINNA AMIRAM (P.O):: BHIMAVARAM :: W.G.Dt., A.P., INDIA :: PIN: 534 204

Estd:1980

Regula	Regulation: R20IV / IV - B.Tech. I - Semester												
	MECHAN	ICAL EN	IGIN	EERI	NG								
	SCHEME OF INSTRUCTION & EXAMINATION (With effect from 2020-21 admitted Batch onwards)												
Course CodeCourse NameCatego ryCrLTPInt. MarksExt.Tot Marks													
B20HS4101	Universal Human Values-2: Understanding Harmony	HS	3	3	0	0	30	70	100				
#PE-III	Professional Elective -III	PE	3	3	0	0	30	70	100				
#PE-IV	Professional Elective -IV	PE	3	3	0	0	30	70	100				
#PE-V	Professional Elective -V	PE	3	3	0	0	30	70	100				
#OE-III	Open Elective-III	OE	3	3	0	0	30	70	100				
#OE-IV	Open Elective-IV	OE	3	3	0	0	30	70	100				
B20ME4113	MATLAB (Skill Oriented Course)	SOC	2	1	0	2		50	50				
B20ME4114	B20ME4114 Industrial/Research Internship 2 Months						GE	50	50				
	Latu. 1700	TOTAL	23	19	0	2	180	520	700				

	Course Code	Course						
	B20ME4101	Finite Element Analysis						
#PE-III	B20ME4102	Production Planning and Control						
	B20ME4103	Industrial Robotics						
	B20ME4104	MOOCs –III						
	B20ME4105	Quality Control and Assurance						
#PE-IV	B20ME4106	Control Systems						
#F L-1 V	B20ME4107	Unconventional Machining Processes						
	B20ME4108	MOOCs –IV						
	B20ME4109	Automobile Engineering						
#PE-V	B20ME4110	Additive Manufacturing						
#FE-V	B20ME4111	Power Plant Engineering						
	B20ME4112	MOOCs –V						
#OE-III &	Student has to st	udy one Open Elective each from OE-III & IV offered by CE or						
#OE-IV	CSE or ECE or I	or EEE or IT or S&H from the list enclosed.						

C	ode	Category	L	Т	Р	C	I.M	E.M	Exam					
B20H	20HS4101 HS 3 3 30 70													
	UNIVERSAL HUMAN VALUES-2: UNDERSTANDING HARMONY (Common to AIDS, CSBS, CSE, IT & ME)													
Course	Course Objectives:													
Cours	•	To enable students appreciate the essential complementarity between 'Values' and 'Skills' to ensure												
1.	sustain	sustained happiness and prosperity which are the core aspirations of all human beings.												
2.		o understand the harmony in the human being, family, society and nature/existence o facilitate the development of a Holistic perspective among students towards life, profession												
3.	and ha		n a correct	underst	anding o	f the Hun	nan realit	y and the	rest of existence.					
Cours	se Outc	omes: At the end	l of the cou	rse, stud	lents will	be able to)							
S.No			<u>. or the cou</u>	Outco					Knowledge Level					
1.	Identi	fy the importance	e of human	values a	nd skills	for sustain	ned happi	ness	K2					
2.	Under	stand how to bala	ance profes	sion and	l persona	happines	s/ goals.		K2					
3.		ss the <mark>ir commitn</mark> relationship and			they have	e understo	od (huma	in values,	К2					
4.	-	in the significar ing interaction w		t, mutu	ally satis	fying hu	nan beha	avio <mark>r a</mark> nd	K2					
5.		op/ propose appr ny in professiona		U		anagemen	t patterns	to create	К3					
					LLABUS									
	 Course Introduction - Need, Basic Guidelines, Content and Process for Value Education Purpose and motivation for the course, recapitulation from Universal Human Values-I Self- Exploration–what is it? - Its content and process; 'Natural Acceptance' and Experiential Validation- as the process for self-exploration Continuous Happiness and Prosperity- A look at basic Human Aspirations Right understanding, Relationship and Physical Facility- the basic requirements for fulfillment of aspirations of every human being with their correct priority Understanding Happiness and Prosperity correctly- A critical appraisal of the current scenario Method to fulfil the above human aspirations: understanding and living in harmony at various levels. 													
	UNIT-II (08 Hrs) Understanding the Body as an instrument of 'I' (I being the doer, seer and enjoyer) Understanding the characteristics and activities of 'I' and harmony in 'I' Understanding the													

	harmony of I with the Body: Sanyam and Health; correct appraisal of Physical needs,
	meaning of Prosperity in detail; Programs to ensure Sanyam and Health.
UNIT-II (08 Hrs)	
UNIT-IV (08 Hrs)	among the four orders of nature recyclability and self regulation in nature Understanding
UNIT-V (08 Hrs)	people friendly and eco-friendly production systems, c. Ability to identify and develop appropriate technologies and management patterns for above production systems. Case studies of typical holistic technologies, management models and production systems Strategy for transition from the present state to Universal Human Order: a. At the level of individual: as socially and ecologically responsible engineers, technologists and managers b. At the level of society: as mutually enriching institutions and organizations
Textbool	۲S:
	uman Values and Professional Ethics by R R Gaur, R Sangal, G P Bagaria, Excel Books, New elhi, 2010
Reference	e Books:
1. Je	evan Vidya: Ek Parichaya, A Nagaraj, Jeevan Vidya Prakashan, Amarkantak, 1999.
	uman Values, A.N. Tripathi, New Age Intl. Publishers, New Delhi, 2004.
	ne Story of Stuff (Book).
4. TI	ne Story of My Experiments with Truth
	nall is Beautiful E. F Schumacher by Mohandas Karamchand Gandhi
6. Sl	ow is Beautiful Cecile Andrews
7. E	conomy of Permanence J C Kumarappa

8.	Bharat Mein Angreji Raj Pandit Sunderlal
9.	Rediscovering India by Dharampal Hind Swaraj or Indian Home
10.	Rule by Mohandas K. Gandhi
11.	India Wins Freedom Vivekananda Maulana Abdul Kalam Azad 12Romain Rolland (English)



Cour	se Code	Category	L	Т	Р	C	I.M	E.M	Exam
B20 N	ME4101	PE	3			3	30	70	3 Hrs.
				rofessio	MENT A nal Elect For ME)	ANALYS ive -III)	IS		
Cours	se Object	ives:							
1. 2.	systems,	de students wi the implementa students how t	ation of the	ese princ	iples, and	l its conne	ections to	CAD.	ement analysis
Cours	no Outoo	nes: At the end	of the cor	rea stud	onte will	ba abla t	2		
S.No		nes. At the end		Outco			5		Knowledge Level
1.		and the fundan problem using		-			nalysis an	d Solve the	К3
2.	analysis	and the Company of the State							K4
3.		Trusses and B							K4
4.	and app Element	2D structural ly the principl Analysis.	es of Nun	nerical I	ntegratio	n and its	applicatio	on to Finite	K4
5.		Axisymmetri s. Estd. 1980	c solids	by apply	ying the	concept	s of Fini	te Element	K4
				SY	LLABU	5			
UNI (10 F	T-I ma Irs) nu Ty	troduction: stre ane stress and ethod Finite E mbering, interp pes of bounda ement Method.	plane stra lement M polation fu	ain cond ethod: I nctions, I	litions, T Discretiza local and	The potent tion, Ty global co	tial energ pes of ele pordinates,	y approach; ements, banc convergence	Rayleigh-Ritz d width, node requirements,
	 UNIT-II (10 Hrs) One Dimensional Bar Problems: 1-D bar element - shape functions – Stiffness matrix and load vector– assembly of Matrices – Treatment of boundary conditions One dimensional quadratic element – Temperature Effects. 								
UNI7 (10 H	Trusses: Introduction; Plane trusses; shape functions – Stiffness matrix and load vector– G-III assembly of Matrices – Treatment of boundary conditions; simple problems on trusses.								

UNI7 (10 H	constant strain triangle Element - treatment of boundary conditions 2D four noded iso
UNI (8 H	formulation. Finite element modeling - triangular element. Problem modeling and boundary
Textl	pooks:
1.	Introduction to Finite Elements in Engineering, Chandrupatla, Ashok and Belegundu, Prentice – Hall.
Refer	rence Books:
1.	The Finite Element Method by O.C. Zienkiewicz, Tata McGraw Hill Company Ltd.
2.	The Finite Element Methods in Engineering by Rao, S.S.
3.	Concepts and Applications of Finite Element Analysis by Cook, R.D.
4.	Applied Finite Element Analysis by Segerland, L.J.
e-Res	sources:
1.	https://nptel.ac.in/courses/112104193
2.	https://nptel.ac.in/courses/112104116
3.	https://nptel.ac.in/courses/112104205



Cour	Irse Code Category L T P C I.M E.M											
B20 N	AE4102	PE	3			3	30	70	3 Hrs.			
		Р	RODUCI				TROL					
			(P	rofessio	nal Elect	ive -III)						
				(1	For ME)							
Cours	se Object											
1.	To develop an ability to apply PPC concepts in a various area like marketing, accounting, finance, engineering, personnel management, logistics, etc.											
2.		nine several c and inventory	-	perations	Manage	ement pla	nning to	pics includi	ng production			
3.	To aquir	e knowledge to	make MI	RP, MRI	P-II by us	sing Mode	ern Produ	ction plannir	ng software for			
5.	production	on of product w	ith availab	le resour	rces.							
Cours	se Outcor	nes: At the end	of course.	, students	s will be	able to						
S.No				Outco	ome				Knowledge Level			
1.		and different ty on planning an		duction	systems a	and the int	ernal orga	anization of	К2			
2.	-	forecasts in tive and qualitation			g and so	ervice see	ctors usin	ng selected	K3			
3.		and t <mark>he impo</mark> rta		unction (of invent	ory and to	be able 1	to a <mark>ppl</mark> y for	К3			
4.		outing procedung policies and				lule and l	oading aı	nd interpret	К3			
5.		t dispatching g and control.	procedure	and app	plications	of com	puters in	production	К3			
				SY	LLABUS	5						
UNI (10H	T-I ele	roduction: Def ements of produ d control depar	ction cont	-			-					
	NIT-II Forecasting – Importance of forecasting –types of forecasting, their uses – general principles of forecasting – forecasting techniques – qualitative methods and quantitative methods.											
	NIT-III 10 Hrs)Inventory management – functions of inventories – relevant inventory costs – ABC analysis – VED analysis – EOQ model – Inventory control systems – P–Systems and Q- Systems Introduction to MRP I,MRP II, ERP, LOB (Line of Balance).											

	Routing –definition – routing procedure –route sheets – bill of material – factors affecting								
UNIT									
(10 H									
	Line Balancing, aggregate planning, chase planning, expediting, controlling aspects.								
TINIT	Dispatching – activities of dispatcher – dispatching procedure – follow up – definition –								
UNIT	reason for existence of functions – types of follow up, applications of computer in								
(10 H	rs) production planning and control.								
Textbo	ooks:								
1.	Elements of Production Planning and Control / Samuel Eilon/Universal Book Corp.								
2.	Manufacturing, Planning and Control/Partik Jonsson Stig- Arne Mattsson/Tata McGraw Hill								
Refere	ence Books:								
1.	Inventory Control Theory and Practice / Martin K. Starr and David W.Miller/Prentice-Hall								
2.	Production Planning and Control/Mukhopadyay/PHI.								
3.	Production Control A Quantitative Approach / John E.Biegel/Prentice-Hall								
4.	Production Control / Franklin G Moore & Ronald Jablonski/Mc-GrawHill								
5.	Production and Operations Management/Shailendra Kale/McGraw-Hill								
6.	Production and Operations Management/Ajay K Garg/McGraw-Hill								
e-Reso	purces:								
1.	https://nptel.ac.in/courses/112107143								
2.	https://archive.nptel.ac.in/courses/110/105/110105095								
	ENGINEERING COLLEGE								
	Estd. 1980 AUTONOMOUS								



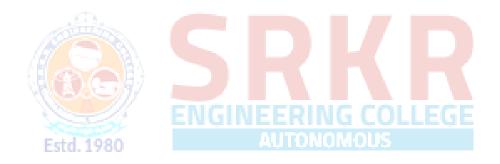
B20ME4103 PE 3 3 30 70 3 Hrs. INDUSTRIAL ROBOTICS (Professional Elective -III) (For ME) Course Objectives: 1 This course helps the students to understand robot frame assignment and transformations 3 Students can learn developing dynamic model and control for robot 5 Students can learn developing dynamic model and control for robot Course Outcomes: At the end of the course, students will be able to Course Outcomes: At the end of the course, students of robot, configurations of robot and applications of robot. Implement the matrix transformations for robot Students can learn dunderstand the concept of Euler angles. A understand basic components of robot, terminology used in robot, work space of robot, configurations of robot and applications of robot. K3 Implement the matrix transformations for robot manipulator using Denavit Hartenberg notation, solve the problem of inverse kinematic of robot, and derive Jacobian matrix of robot manipulator K3 Students escond order dynamic systems, develop linear control for the robot, disadvantages, Robot-components, deg	Cours	se Code	Category	L	Т	P	C	I.M	E.M	Exam			
(Professional Elective -III) (For ME) Course Objectives: 1. This course is designed to equip the students with basic understanding of working of robot 2. This course helps the students to understand robot frame assignment and transformations 3. Students will learn kinematics of robot 4. Students can formulate joint trajectory planning for robot Students can learn developing dynamic model and control for robot Course Outcomes: At the end of the course, students will be able to Students can learn developing dynamic model and control for robot. Indext control for probot Course outcomes: At the end of the course, students will be able to Students can learn developing dynamic model and control for robot. Indext control for bot and applications of robot. Indext control for bot on an applications of robot. Row Outcome Indext control for bot on applications of robot. Implement the matrix transformations for representing the rigid body, for relative motions of frame and understand the concept of Euler angles. Implement the problem of inverse kinematic of robot, and derive Jacobian matrix of robot manipulator using Dena	B20N	IE4103	PE	3			3	30	70	3 Hrs.			
(Professional Elective -III) (For ME) Course Objectives: 1. This course is designed to equip the students with basic understanding of working of robot 2. This course helps the students to understand robot frame assignment and transformations 3. Students will learn kinematics of robot 4. Students can formulate joint trajectory planning for robot Students can learn developing dynamic model and control for robot Course Outcomes: At the end of the course, students will be able to Students can learn developing dynamic model and control for robot. Indext control for probot Course outcomes: At the end of the course, students will be able to Students can learn developing dynamic model and control for robot. Indext control for bot and applications of robot. Indext control for bot on an applications of robot. Row Outcome Indext control for bot on applications of robot. Implement the matrix transformations for representing the rigid body, for relative motions of frame and understand the concept of Euler angles. Implement the problem of inverse kinematic of robot, and derive Jacobian matrix of robot manipulator using Dena													
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Course Objectives: 1. This course is designed to equip the students with basic understanding of working of robot 2. This course helps the students to understand robot frame assignment and transformations 3. Students will learn kinematics of robot 4. Students can formulate joint trajectory planning for robot 5. Students can formulate joint trajectory planning for robot Course Outcomes: At the end of the course, students will be able to Students can formulate joint trajectory planning for robot, configurations of robot, and applications of robot. 2. Implement the matrix transformations for robot and applications of robot. K12 3. Implement the matrix transformations for robot analipulator using Denavit-Hartenberg notation, solve the problem of inverse kinematic of robot, and derive Jacobian matrix of robot manipulator K3 4. Implement proper joint trajectory for robot joint and analyze the dynamics robot manipulator using Lagrange method. K3 5. Students of robotics: Robot and apply Lypunov method for stability of nonlinear systems K4 SYLLABUS Fundamentals of robotics: Robot and robotics, classification of robotics, advantages and disadvantages, Robot-components, degrees of freedom, joints, coordinates, workspace, applications. Sensors: potentiometers, enco				(P			ive -III)						
1. This course is designed to equip the students with basic understanding of working of robot 2. This course helps the students to understand robot frame assignment and transformations 3. Students will learn kinematics of robot 4. Students can formulate joint trajectory planning for robot 5. Students can learn developing dynamic model and control for robot Course Outcomes: At the end of the course, students will be able to Source Outcomes: At the end of the course, students will be able to Source Outcomes: At the end of the course, students will be able to Source Outcomes: At the end of the course, students of robot, errainology used in robot, work space of robot, configurations of robot and applications of robot. 1. Understand basic components of robot manipulator using Denavit-Hartenberg netative motions of frame and understand the concept of Euler angles. K3 2. Implement the matrix transformations for robot manipulator using Denavit-Hartenberg notation, solve the problem of inverse kinematic of robot, and derive Jacobian matrix of robot manipulator K3 4. Implement proper joint trajectory for robot joint and analyze the dynamics robot manipulator using Denavit-Hartenberg K3 5. Evelop the forward kinematic systems, develop linear control for the robot, develop model base control of robot and apply Lypunov method for stability of nonlinear systems	~				(H	For ME)							
2. This course helps the students to understand robot frame assignment and transformations 3. Students will learn kinematics of robot 4. Students can formulate joint trajectory planning for robot 5. Students can learn developing dynamic model and control for robot Course Outcomes: At the end of the course, students will be able to Course Outcomes: At the end of the course, students will be able to 1. Understand basic components of robot, terminology used in robot, work space of robot, configurations of robot and applications of robot. K2 2. Implement the matrix transformations for representing the rigid body, for relative motions of frame and understand the concept of Euler angles. K3 3. Develop the forward kinematics for robot manipulator using Denavit-Hartenberg notation, solve the problem of inverse kinematic of robot, and derive Jacobian matrix of robot manipulator using Lagrange method. K3 4. Implement proper joint trajectory for robot joint and analyze the dynamics robot develop model base control of robot and apply Lypunov method for stability of nonlinear systems K4 SYLLABUS UNIT-II Robot components, degrees of freedom, joints, coordinates, workspace, applications. Sensors: potentiometers, encoders. Actuators: Characteristics of actuation system and comparison of actuating systems UNIT-II <td></td> <td>v</td> <th></th> <th></th> <th></th> <th></th> <td></td> <td></td> <th>0 11</th> <td></td>		v							0 11				
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4. Students can formulate joint trajectory planning for robot 5. Students can learn developing dynamic model and control for robot Course Outcomes: At the end of the course, students will be able to S.No Course Outcomes: At the end of the course, students will be able to S.No Knowledge Level 1. Understand basic components of robot, terminology used in robot, work space of robot, configurations of robot and applications of robot. K2 2. Implement the matrix transformations for representing the rigid body, for relative motions of frame and understand the concept of Euler angles. K3 3. Develop the forward kinematics for robot manipulator using Denavit-Hartenberg notation, solve the problem of inverse kinematic of robot, and derive Jacobian matrix of robot manipulator K3 4. Implement proper joint trajectory for robot joint and analyze the dynamics robot develop model base control of robot and apply Lypunov method for stability of nonlinear systems K4 5. develop model base control of robot and apply Lypunov method for stability of applications. K4 SYLLABUS VINIT-II Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. Stot position analysis: Matrix transformations, Homogen													
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1. robot, configurations of robot and applications of robot. K2 2. Implement the matrix transformations for representing the rigid body, for relative motions of frame and understand the concept of Euler angles. K3 3. Develop the forward kinematics for robot manipulator using Denavit-Hartenberg notation, solve the problem of inverse kinematic of robot, and derive Jacobian matrix of robot manipulator K3 4. Implement proper joint trajectory for robot joint and analyze the dynamics robot manipulator using Lagrange method. K3 5. Analyze second order dynamic systems, develop linear control for the robot, develop model base control of robot and apply Lypunov method for stability of nonlinear systems K4 SYLLABUS UNIT-II (10 Hrs) Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. UNIT-II (10 Hrs) Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. UNIT-III In Plenetition analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. Fundamentals of robotics: Claracteristics of actuation system and comparison of actuating systems UNIT-III Robot position analysis: Matrix transformations, Homogene	S.No				Outc	ome				U			
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3. Develop the forward kinematics for robot manipulator using Denavit-Hartenberg notation, solve the problem of inverse kinematic of robot, and derive Jacobian matrix of robot manipulator K3 4. Implement proper joint trajectory for robot joint and analyze the dynamics robot manipulator using Lagrange method. K3 5. Analyze second order dynamic systems, develop linear control for the robot, develop model base control of robot and apply Lypunov method for stability of nonlinear systems K4 SYLLABUS Fundamentals of robotics: Robot and robotics, classification of robotics, advantages and disadvantages, Robot-components, degrees of freedom, joints, coordinates, workspace, applications. Sensors: potentiometers, encoders. Actuators: Characteristics of actuation system and comparison of actuating systems UNIT-II (10 Hrs) Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler angles UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple	2.	Implen	nent the matri	x transfor	mations	for rep	resenting			К3			
3. notation, solve the problem of inverse kinematic of robot, and derive Jacobian matrix of robot manipulator K3 4. Implement proper joint trajectory for robot joint and analyze the dynamics robot manipulator using Lagrange method. K3 5. Analyze second order dynamic systems, develop linear control for the robot, develop model base control of robot and apply Lypunov method for stability of nonlinear systems K4 SYLLABUS UNIT-I (10 Hrs) Fundamentals of robotics: Robot and robotics, classification of actuating systems UNIT-II (10 Hrs) Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple													
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4. manipulator using Lagrange method. K3 5. Analyze second order dynamic systems, develop linear control for the robot, develop model base control of robot and apply Lypunov method for stability of nonlinear systems K4 SYLLABUS UNIT-I (10 Hrs) Fundamentals of robotics: Robot and robotics, classification of robotics, advantages and disadvantages, Robot-components, degrees of freedom, joints, coordinates, workspace, applications. Sensors: potentiometers, encoders. Actuators: Characteristics of actuation system and comparison of actuating systems UNIT-II (10 Hrs) Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler angles UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple		matrix	of robot manip	ulator				ULL	EGE				
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nonlinear systems SYLLABUS SYLLABUS Fundamentals of robotics: Robot and robotics, classification of robotics, advantages and disadvantages, Robot-components, degrees of freedom, joints, coordinates, workspace, applications. Gensors: potentiometers, encoders. Actuators: Characteristics of actuation system and comparison of actuating systems UNIT-II (10 Hrs) Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler angles UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple		-		-		s, develo	p linear c	ontrol for	the robot,				
SYLLABUS UNIT-I (10 Hrs) Fundamentals of robotics: Robot and robotics, classification of robotics, advantages and disadvantages, Robot-components, degrees of freedom, joints, coordinates, workspace, applications. Sensors: potentiometers, encoders. Sensors: potentiometers, encoders. Actuators: Characteristics of actuation system and comparison of actuating systems UNIT-II Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler angles UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple	5.	develo	p model base c	ontrol of r	obot and	l apply L	ypunov m	ethod for	stability of	K4			
UNIT-I (10 Hrs)Fundamentals of robotics: Robot and robotics, classification of robotics, advantages and disadvantages, Robot-components, degrees of freedom, joints, coordinates, workspace, applications. Sensors: potentiometers, encoders. Actuators: Characteristics of actuation system and comparison of actuating systemsUNIT-II (10 Hrs)Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler anglesUNIT-III (10 Hrs)Denavit-Hartenberg representation of forward kinematic equations of robots: simple		nonline	ear systems										
UNIT-I (10 Hrs)Fundamentals of robotics: Robot and robotics, classification of robotics, advantages and disadvantages, Robot-components, degrees of freedom, joints, coordinates, workspace, applications. Sensors: potentiometers, encoders. Actuators: Characteristics of actuation system and comparison of actuating systemsUNIT-II (10 Hrs)Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler anglesUNIT-III (10 Hrs)Denavit-Hartenberg representation of forward kinematic equations of robots: simple													
UNIT-I (10 Hrs)disadvantages, Robot-components, degrees of freedom, joints, coordinates, workspace, applications. Sensors: potentiometers, encoders. Actuators: Characteristics of actuation system and comparison of actuating systemsUNIT-II (10 Hrs)Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler anglesUNIT-III UNIT-IIIDenavit-Hartenberg representation of forward kinematic equations of robots: simple													
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Actuators: Characteristics of actuation system and comparison of actuating systems UNIT-II (10 Hrs) Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler angles UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple	(10 H	rs) ⁻	-		,								
UNIT-II Robot position analysis: Matrix transformations, Homogeneous transformations of matrix, Representations of transformations. (10 Hrs) Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler angles UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple			-					•	£				
UNIT-II Representations of transformations. (10 Hrs) Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler angles UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple		A	cuators: Chara	acteristics (or actual	ion syste	in and con	iparison o	of actuating s	ystems			
UNIT-II Representations of transformations. (10 Hrs) Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler angles UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple		D	hat nosition a	nalveie. M	latriv tra	neformet	ions Hor	OGANAOU	transformat	ions of matrix			
(10 Hrs) Forward and Inverse Kinematic Equations: Orientation-RPY angles, Euler angles UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple			-	•		insionnal	10113, 11011	ogeneous	s i ansi offilat	ions of maula,			
UNIT-III Denavit-Hartenberg representation of forward kinematic equations of robots: simple	(10 H												
						1			6, 2010	0			
	UNIT	-III D	enavit-Hartenl	berg repre	esentatio	n of for	ward kin	ematic e	uations of	robots: simple			
									-	Ť			

		Differential Motions and Velocities: Differential relationships, Jacobian, Differential						
		motions of frame, Differential changes between frames.						
		Trajectory planning: Joint space versus Cartesian space, Joint space trajectory planning						
UNIT	Γ -ΙV	Third-order polynomial trajectory planning, Linear segments with parabolic blends						
(10 E	Irs)	Dynamic analysis of robot: Introduction to Lagrangian method, dynamic equation of 2-						
		DOF robot manipulator (RR and RP).						
		Control of manipulators: Feedback and closed loop control, Second order linear systems,						
UNI	Γ-V	Control of second order systems, control-law partitioning						
(10 H	Hrs)	Nonlinear control of manipulators: Nonlinear and time varying systems, Lypunov						
		stability analysis.						
Text I	Books	:						
1.		oduction to Robotics: Analysis, Control, Applications by Saeed B Niku						
2.	Intr	oduction to Robotics: Mechanics and Control by J J Craig						
Refer	ence]	Books:						
1.	Intr	oduction to Robotics by SK Saha, The McGrah Hill Company						
	D - 1	Robotics / Fu K S/ McGraw Hill						
2.	KO	solies / Fu K S/ McGraw Hill						
2. 3.	-	ustrial Robotics /Groover M P /Pearson Edu.						
	Ind	ustrial Robotics /Groover M P /Pearson Edu.						
3.	Ind ource	ustrial Robotics /Groover M P /Pearson Edu.						
3. e-Res	Ind ource	ustrial Robotics /Groover M P /Pearson Edu. s:						

Estd. 1980

Course Code	Category	L	Т	Р	С	I.M	E.M	Exam				
B20ME4104	PE				3	30	70	3 Hrs.				
			MO	OOCs-III								
			(F	For ME)								
MOOCs-III course should belong to the B.Tech. Programme and that course should not be studied earlier. Students should select a course from SWAYAM/ NPTEL with minimum 12 weeks of duration.												

The percentage obtained for the candidate in MOOCs will be mapped to the grade table given in the Academic Regulations.



Cour	se Code	Category	L	Т	Р	С	I.M	E.M	Exam	
B20 N	ME4105	PE	3			3	30	70	3 Hrs.	
		Q	UALITY				RANCE			
			(P		nal Elect	tive -IV)				
2				(1	For ME)					
Cours	se Object		6.1	•				6.0.11		
1.	The overall objective of the course is to teach the basic principles of Quality mar which includes Taguchi' loss function, Deming's philosophy.									
2.		rstand the purp			_		-			
2. 3.		rstand the diffe				1 1				
<u> </u>		me familiar wit								
т.	10 0000			cuious of	i statistic	ai process	control			
Cours	se Outcoi	nes: At the end	l of the cou	irse, stud	lents will	be able to				
									Knowledge	
S.No				Outco	ome				Level	
1	Apply	pply the fundamentals in interpreting the concepts like Quality Costs,								
1.	Deming	g's Philosophy							K3	
2.	Constru	truct and analyze control charts for Variables for the purpose of							WO	
2.	-	ing the process			1				K3	
3.		ict and analy	ze contro	l charts	for At	tributes f	for the p	purpose of	K3	
	1	ingthe process	- E		IFFR	ING C	D H			
4.		Caguchi loss fur			-			Capability	K3	
5.	Apply c	lifferent sampli	ing plans f	or the pu	irpose of	inspection	n.		K3	
				CV.	LLABU	C				
	0	uality control	in Dong				unality a	uality accur	anaa quality	
UNI (10H	T-I qu	Quality control in Perspective: Introduction to quality, quality assurance control, examples of off-line and on-line quality control techniques; quality quality of conformance and quality of performance; quality characteristics								
	an	and attributes, growth of quality control, Deming's Philosophy, Introd								
	si	gma concept.								
			0 77 1	11 ~*		-	1 77 -	<u> </u>	1 1	
UNI' (10 H	I'-II Irs) St	Control charts for Variables: Shewart's norm bowl, X and R charts, X and σ charts, Statistical control of processes, group control chart, X chart with linear trend, warning limits.								
		ontrol charts	s for At	tributes	s: Defe	ct and d	efective,	fraction d	lefective and	
UNI	1	percent								
(10 H		efective, p- ch	art, 100p	-chart,	np-chart	, c-chart,	u-chart,	ku-chart, de	emerit control	

UNIT-IV (10 Hrs)Process capability analysis: Determination of process capability, PCR, Talloss function, smaller the better type and larger the better type of product specific Design specifications and tolerances for sub-assemblies, setting tolerance intermediate steps in Production.										
		Acceptance sampling plans: Single, double, multiple and sequential sampling plans,								
UNI	T-V	OC curve, rectifying inspection, AOQ, AOQL, ASN and ATI, Use of Dodge Romig								
(10 F		Tables,								
	,	Design of single and sequential sampling plans.								
Textb	ooks:									
1.	Stati	stical Quality Control by E.L.Grant and Leavenworth, McGraw Hill								
2.	Qual	ity control and application by Bertrand.L.Hansen and P.M.Ghare, PHI								
Refer	ence l	Books:								
1.	Intro	duction to Statistical Quality Control by D.C.Montgomery, Wiley								
2.	Prin	ciples of Quality control by Jerry Banks, John Wiley								
3.	Qual	ity control hand book by Juran, McGrawHill								
		.0.								
e-Res	ource	s:								
1.	http	s://nptel.ac.in/courses/110105088								
2.	http	s://onlinecourses.nptel.ac.in/noc20_mg18/preview								
		Estd. 1980 ENGINEERING COLLEGE								



С	Code	Category	L	Т	Р	С	I.M	E.M	Exam			
B20N	AE4106	PE	3			3	30	70	3 Hrs.			
	CONTROL SYSTEMS (Professional Elective -IV)											
				(F	For ME)							
Cours	se Obje	ctives:										
1.		To introduce basic principles of control systems and to develop mathematical models for physical systems.										
2.		niliarize students d test signals.	s on basic	concept	ts of fee	dback cha	aracteristi	cs of contro	l systems for			
3.		niliarize students ncy domain techn	-	zing and	l finding	stability	of contro	l systems us	sing time and			
Cours	se Outc	omes: At the end	l of the cou	urse, stud	ents will	be able to)					
S.No				Outco					Knowledge Level			
1.	Under using	fer function	K3									
2.	Prepare mathematical models for physical systems using fundamental principles of mathematics and control systems.								К3			
3.	Devel	op and Analyze	state space	models			<u></u>		K3			
4.		ute and discover gher order contro					error of f	ïrst, second	K3			
5.	Calcu	late the stability	of a syster	n using F	Routh-Hu	rwitz and	Nyquist c	riterion	K3			
						-						
T TN T T							1	T 1 1				
UNI (08 H		Introduction: Control	•				•	s, Feedback	and its effects.			
(00 1	115)		I, DIOCK D	lagrann a	nu signa	FIOW OI	ipns.					
	INIT-II 10 Hrs)Mathematical Modelling of Physical Systems: Modelling of mechanical system elements, Equations of mechanical and electrical systems, Electr mechanical systems.											
	 (10 Hrs) State-variable analysis: State variables, State-Transition Matrix, State UNIT-III Relationship between state equations and high order differentiation of the state equations and transfer functions, Characteristic equations and Eigen vectors. 							ial equations,				
UNIT (08 H	l'-IV Hrs)	Time Response control systems, nputs, Time dom	Order of a	system,	response	of first a	nd second	l order system	-			

UNI (10 I		 Stability of control systems: Stability, Characteristic equation, Routh-Hurwitz criterion for determining stability of linear control systems. Frequency-domain Analysis of Control Systems: Nyquist stability criterion (simple problems). 								
Text	Books	y•								
1.	1	trol Systems by A. Nagoor Kani, RBA Publications.								
2.	_	omatic Control Systems by Benjamin C Kuo								
3.	Adv	anced Control Theory by A. Nagoor Kani, RBA Publications.								
Refer	ence]	Books:								
1.	Con	trol Systems Engineering by Nagrath/Gopal, New Age International.								
2.	Con	trol systems principles and design by M Gopal, Tata Mcgraw-Hill.								
3.	Con	trol systems A K Jairath, CBS problems and solutions series.								
e-Res	ource	s:								
1.	https	s://www.tutorialspoint.com/control_systems/control_systems_introduction.html								
2.	https	s://onlinecourses.nptel.ac.in/noc19_de04/preview								

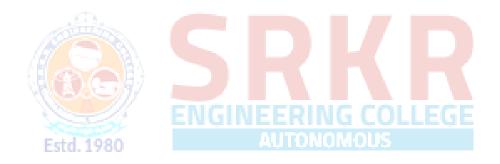


Cour	rse Cod	e Category	L	Т	P	C	I.M	E.M	Exam		
B20N	ME4107	PE	3			3	30	70	3 Hrs.		
UNCONVENTIONAL MACHINING PROCESSES											
(Professional Elective -IV)											
				(For ME)						
Cour	•	ectives:									
1.		To impart the student the knowledge of unconventional machining methods and their applications.									
2.		To acquaint the student with the knowledge of different Mechanical energy based unconventional machining methods.									
3.		uaint the stude				of Thern	nal and	Thermo-ele	ctrical energy		
4.	-	oart the studen		-		nt Electro	o-Chemio	cal and Ch	emical energy		
Cour	rse Out	comes: At the er	nd of the c	course, s	tudents	will be ab	le to				
S.No	Outcome								Knowledge Level		
1.		gui <mark>sh the type</mark> ations.	es of unc	onventi	onal ma	chining p	processes	and their	К3		
2.		ibe the unconve s applications.	entional r	nachinir	ng proce	ss using	Mechani	cal energy	К3		
3.		be the process applications	of uncor	vention	al mach	ining usi	ng Thern	nal energy	K3		
4		be the process and its applica		vention	al mach	ining usi	ng Thern	no electric	К3		
5.		be the process memical energy a				ining usir	ng electro	o-chemical	К3		
	-										
		, , ,						1 ~~~	1.01 .1		
UNI (06 I	Hrs)	Introduction–N modern machir Applications.					-				
	Abrasive Jet Machining, Water Jet Machining and Abrasive Water Jet Machine: Basic principles- equipment-process variables- and mechanics of metal removal- MRR- application and limitations. UNIT-II (10 Hrs) Ultrasonic machining - Elements of the process – mechanics of metal removal- process parameters – economic considerations – applications and limitations – recent developments.										

		Electric Discharge Machining-Power Circuits – Mechanics of metal removal –								
UNIT	-III	Processparameters – selection of tool electrode and dielectric fluids – flushing –								
(10 H	Hrs)	applications –Wire EDM – principle – applications.								
		applications – whe EDM – principle – applications.								
UNIT	Г -IV	Electron Beam Machining (EBM) -Laser Beam Machining (LBM) –Plasma								
(10 H	Hrs)	Arc Machining (PAM) - Principles – Equipment – Process Parameters –								
(20 2		Applications. Magnetic abrasive finishing – Electro stream drilling machining.								
		Electro-Chemical Machining Processes: Principles of ECM -equipment - MRR								
UNI	Г-V	-process parameter -electrochemical grinding - electro chemical honing process.								
(10 H	Hrs)	Chemical machining –principle–etchants –maskants– maskant application								
		methods –process parameter – MRR – applications.								
	•									
Textb	ooks									
1.	Adv	anced Machining Processes/VKJain/Allied Publishers								
2.	Mod	ern Machining Processes-P. C.Pandey, H. S.Shan								
Refer	ence	Books:								
1	Man	ufacturing Engineering and Technology By Serope Kalpak Jain, Pearson Publications,								
1.	2001									
2.	Man	ufacturing Engineering & Technology, Kalpak Jain								
3.	Unc	onventional Manufacturing Processes, Singh M. K								
e-Res	ource	s: (A) (A)								
1.	<u>NPT</u>	EL :: Mechanical Engineering - Manufacturing Processes II								
n	<u>NPT</u>	EL :: Mechanical Engineering - NOC:Non Traditional Abrasive Machining Processes-								
2.	Ultra	asonic, Abrasive Jet and Abrasive Water Jet Machining								

Course Code	Category	L	Т	Р	С	I.M	E.M	Exam		
B20ME4108	PE				3	30	70	3 Hrs.		
MOOCs-IV										
			(F	For ME)						
MOOCs-IV cou	rse should be	long to th	ne B.Tec	h. Progra	imme and	d that cou	rse should	not be studied		
earlier. Students should select a course from SWAYAM/ NPTEL with minimum 12 weeks of duration.										
T 1	1	1. 1		000	11 1	1 / 1	1 / 1 1	· · · .		

The percentage obtained for the candidate in MOOCs will be mapped to the grade table given in the Academic Regulations.



se Code	Category	L	Т	Р	C	I.M	E.M	Exam		
AE4109	PE	3			3	30	70	3 Hrs.		
AUTOMOBILE ENGINEERING										
(Professional Elective-V)										
(For ME)										
Course Objectives:										
To understand about various steering systems, steering linkages, Transmission system, steering										
0	1	U U								
						-				
				s, wheel	s and tyr	es and pr	ovides the i	nformation on		
	1			• • •						
To under	stand upcoming	g technolo	gy of hyl	orid elect	ric vehicle	es.				
0.1	A1 1	6.1			1 11 .					
se Outcon	nes: At the end	of the cou	irse, stud	ents will	be able to)		T 7 1 1		
			Outco	ome				Knowledge		
Illustrate	the Automobi	la lavout	upor of	Conging	a and the	r anhanata		Level K3		
								KJ		
			ng princ	ipies of c	nuten, gea	ubox, un		K3		
		of Steer	ing geor	netry in	automob	ile and co	an compare			
		ig meenun	ionii, ouoj				es sused on	K3		
	- E-1-1-000	of brake	s. electr			c systems	s. pollution			
	-		,			j	· · ·	K3		
Identify	technological	updates in	Hybrid	Vehicles	and the	need of tr	ouble shoot	14.0		
and main	ntenance in Au	tomotive V	/ehicles.					K3		
1										
	-	-	-			n-line' a	nd 'V' type	e, Multi-Valve		
rs)						D' 1 D	· a			
Fu	-	-					gines: Conve	entional, CRDI		
and	d Dual fuel Eng	gines, Eng	ine Cooli	ing and L	ubrication	1.				
Cl	utches: princir	ole. Types:	cone cl	utch. sin	gle plate	clutch. dia	phragm clut	ch. multi plate		
		• •				, alt	T	-, prace		
Ge	-					or Mecha	nism, Tvpes:	Sliding mesh.		
							• •	•		
(rs)		•	,	r J	, ,	· - •		,		
	-		rive: Dri	ive Shaft	, Types	of Propel	ler shafts, F	inal drive and		
	Differential, Power transmission: Front, Rear and Four wheel drive.									
	IE4109 Se Objecti To make To introd gear boxe To introd introd <td< th=""><th>Image: AE4109 PE AE4100 Automobil stand about vales and power stand upcoming AE4100 Automobil stand upcoming Automobil stand upcoming Automobil stand upcoming</th><th>ME4109PE3AUTOAuto<</th><th>AE4109PE3AUTOMOBII(Profession<td colspan<="" th=""><th>AE4109PE3AUTOMOBILE ENGE (Professional Elect (Professional Elect (For ME))AUTOMOBILE ENGE (Professional Elect (For ME))Se Objectives:To make students familiar with the constructional dd To understand about various steering To introduce students to the rear axles and types of s To introduce students to braking systems, wheels various aspects of vehicle maintenance.To understand upcoming technology of hybrid elect se Outcomes: At the end of the course, students will OutcomeIllustrate the Automobile layout, types of IC engine Illustrate various types and working principles of c final drive systems.Illustrate key elements of Steering geometry in various types of steering mechanism, suspension s their construction.Illustrate the concepts of brakes, electrical and control methods and norms.Identify technological updates in Hybrid Vehicles and maintenance in Automotive Vehicles.T-1 InsyIntroduction to Automobile, Automobile L automobile engines, engine parts, Classifi Engines, Super Charging/Turbo charging, Ain Fuel Systems: Petrol Engines: Carbureted ar and Dual fuel Engines, Engine Cooling and LT-1 Constant mesh, Synchromesh, and Epicyo Torque converter. Drive shaft and Final Drive: Drive Shaft</br></th><th>AE4109PE33AUTOMOBILE ENGINEERIN (Professional Elective-V) (For ME)(For ME)se Objectives:To make students familiar with the constructional details of cl To understand about various steering systems, steering link gear boxes and power steeringTo introduce students to the rear axles and types of suspension To introduce students to braking systems, wheels and type various aspects of vehicle maintenance. To understand upcoming technology of hybrid electric vehicleOutcomes: At the end of the course, students will be able to OutcomeIllustrate the Automobile layout, types of IC engines and theil Illustrate various types and working principles of clutch, get final drive systems.Illustrate key elements of Steering geometry in automobiv various types of steering mechanism, suspension systems, v their construction.Illustrate the concepts of brakes, electrical and electroni control methods and norms.Identify technological updates in Hybrid Vehicles and the r and maintenance in Automotive Vehicles.FI-II IrsoIntroduction to Automobile, Automobile Layout, Ch automobile engines, engine parts, Classification: "I Engines, Super Charging/Turbo charging, Air filters. Fuel Systems: Petrol Engines: Carbureted and MPFI, and Dual fuel Engines, Engine Cooling and LubricationGearbox: Construction and Working Principle, Select Constant mesh, Synchromesh, and Epicyclical, Or Torque converter. Drive shaft and Final Drive: Drive Shaft, Types</th><th>Itel 109 PE 3 3 30 AUTOMOBILE ENGINEERING (Professional Elective-V) (For ME) se Objectives: To make students familiar with the constructional details of chassis and To understand about various steering systems, steering linkages, Tra gear boxes and power steering To introduce students to the rear axles and types of suspension systems To understand upcoming technology of hybrid electric vehicles. Outcome: Illustrate the Automobile layout, types of IC engines and their subsystet Illustrate the Automobile layout, types of IC engines and their subsystet Illustrate various types and working principles of clutch, gearbox, driv final drive systems. Illustrate key elements of Steering geometry in automobile and ca various types of steering mechanism, suspension systems, wheels, thir their construction. Illustrate the concepts of brakes, electrical and electronic system control methods and norms. 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SYLLABUS Introduction to Automobile, Automobile Layout, Chassis and body, Power automobile engincs, engine parts, Cll</th></td></th></td></th></td<>	Image: AE4109 PE AE4100 Automobil stand about vales and power stand upcoming AE4100 Automobil stand upcoming Automobil stand upcoming Automobil stand upcoming	ME4109PE3AUTOAuto<	AE4109PE3AUTOMOBII(Profession <td colspan<="" th=""><th>AE4109PE3AUTOMOBILE ENGE (Professional Elect (Professional Elect (For ME))AUTOMOBILE ENGE (Professional Elect (For ME))Se Objectives:To make students familiar with the constructional dd To understand about various steering To introduce students to the rear axles and types of s To introduce students to braking systems, wheels various aspects of vehicle maintenance.To understand upcoming technology of hybrid elect se Outcomes: At the end of the course, students will OutcomeIllustrate the Automobile layout, types of IC engine Illustrate various types and working principles of c final drive systems.Illustrate key elements of Steering geometry in various types of steering mechanism, suspension s their construction.Illustrate the concepts of brakes, electrical and control methods and norms.Identify technological updates in Hybrid Vehicles and maintenance in Automotive Vehicles.T-1 InsyIntroduction to Automobile, Automobile L automobile engines, engine parts, Classifi Engines, Super Charging/Turbo charging, Ain Fuel Systems: Petrol Engines: Carbureted ar and Dual fuel Engines, Engine Cooling and LT-1 Constant mesh, Synchromesh, and Epicyo Torque converter. 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UNIT- (10 Hr	Steering Mechanism and its Elements. Steering gear box and its types Steering gear ratio						
UNIT- (10 Hr							
UNIT (10 Hr	Hybrid Vehicles: History and Introduction of Hybrid Vehicles, Components in hybrid vehicles, Classification of hybrid topologies- Drivetrain structure, Degree of hybridization, Nature of the power source, Advantages and Disadvantages, Applications, Basic components of electric vehicles, Types of motors, types of batteries. Trouble shooting and Maintenance: Engine and Vehicle Troubles: Diagnostic Information, Symptom descriptions and their Causes and Remedies, Maintenance - Periodic, Preventive and Break down						
Textbo							
	Automotive Mechanics (10/e) - William H. Crouse and Donald L. Anglin, Tata McGraw-Hill						
	Publishing Company Limited, ISBN: 0-07-059054-0.						
2	Automobile Engineering – KK Jain/ RB Asthana, Tata McGraw-Hill Publishing Company Limited, ISBN: 0-07-044529-X.						
1	Internal Combustion Engines and Air Pollution- E.F. Obert, Harper & Row International Publishers Inc., ISBN: 0-06-350561-4.						
4.]	Electric and Hybrid Vehicles, Tom Denton, Taylor & Francis,2018.						
	nce Books:						
	Automotive Mechanics – S. Srinivasan, Tata McGraw-Hill Publishing company Limited, ISBN: 0-07-044941-6						
2.	Internal Combustion Engines – Heywood, John, B. McGraw-Hill Publications Limited.						
1	Automotive Engines- S Srinivasan, Tata McGraw-Hill Publishing Company Limited, ISBN: 0- 07-040265-5.						
4.]	Hybrid Vehicles and the future of personal transportation, Allen Fuhs, CRC Press, 2011.						
e-Resou	irces:						
1.	https://nptel.ac.in/courses/107/106/107106088/						
2.	https://nptel.ac.in/courses/108/103/108103009/						
3.	https://www.theengineerspost.com/category/automobile-engg						

Cour	se Code	Category	L	Т	P	C	I.M	E.M	Exam			
B20 N	ME4110	PE	3			3	30	70	3 Hrs.			
					IANUFA onal Elec	CTURIN tive-V)	G					
				(1	For ME)							
	se Object											
1.		e course is designed to develop fundamental knowledge on Additive Manufacturing dy the Liquid based, solid based, and powder based rapid prototyping techniques										
2.						sed rapid p	prototypin	g techniques				
3.	Learn too	ols used for Ad	ditive Man	ufacturi	ng							
Com		ange At the and	of the ear		anto m:11	ha ahla 4a						
Cours S.No	se Outcor	nes: At the end	of the cot	Outco		be able to			Vnowladza			
3.INO				Outco	ome				Knowledge Level			
1.	Underst	and the worl	zing prin	ciples a	and proc	ecc nara	meters (of additive	K2			
1.		turing processe	0 1	cipies a	ind prot	css para			182			
2.		e various liquid		based ad	ditive ma	nufacturi	ng proces	ses	К3			
3.		various pow					• •		K3			
		ng Treatment				Ĭ	7 8					
4.	Develop	the CAD mod	els for rapi	id protot	yping				K3			
5.	Use the	too <mark>ls</mark> of AM Pr	oduction						K3			
			/ 2	NICIN		INC (-7 I I					
		X			LLABUS	<u></u>		LUL				
UNI (10F	T-I Be Irs) De	enefits of AM, anufacturing Pr	Distinctio ocess Cha Preparatio	on Betw in (Eight n of CAl	een AM Steps) D Models	and CNG S - STL Fi	C Machir ile, STL F	ing, General	classification, lized Additive			
	A	lditive Manufa	acturing P	rocesses	5:							
UNI' (10 I	Li F-II Ma Irs) So (L	 Liquid Based AM: Stereolithography (SL) – Apparatus, Working Principle, Process Modeling, Process Parameter, advantages, limitations & Applications. Solid Based AM: Fused Deposition Modelling (FDM), Laminated object Manufacturin, (LOM), Ultrasonic AM- Working Principle, materials, Processes modeling, products advantages, limitations, and applications 										
UNI7 (10 F	F-III ap Irs) Po Di	am Melting - plications, and st Processing	Working I limitations Treatmen	Principle 5. t in AM	, Process	es Model	ing, mate Removal	rials, product , Improve - s	ering, Electron ts, advantages, urface quality, and Thermal			

	Reverse Engineering: Basic concept- Digitization techniques – Model Reconstruction –							
UNI								
(10 I	Materials for AM: Polymers, Thermoplastics and Thermosetting Polymers, Metals,							
	Ceramics and Composites							
	Rapid Tooling: Introduction, Conventional v/s RT, Classification – Direct and Indirect,							
UNI	T-V Differentiate, Direct Methods - Laminated Tooling, DMLS, Indirect Methods- RTV Tools,							
(10 I	Trs) 3D Keltool, Applications							
	Application Areas for ANI: Automotive, Aerospace, Medical Modeling, Reverse							
	Engineering Data, Architectural Modeling,							
T 4								
Text	oooks:							
1.	itive Manufacturing Technologies, Gibson, Ian, David W. Rosen, Brent Stucker, and							
	Mahyar Khorasani, Springer, 2021							
2.	Rapid prototyping: Principles and applications, second edition, Chua C.K., Leong K.F., and Lim							
D C	C.S., World Scientific Publishers, 2003.							
	rence Books:							
1.	Rapid prototyping, Andreas Gebhardt, Hanser Gardener Publications, 2003.							
2.	Rapid Prototyping and Engineering applications: A tool box for prototype development, LiouW.Liou, Frank W.Liou, CRC Press, 2007.							
3.	Rapid Prototyping: Theory and practice, Ali K. Kamrani, Emad Abouel Nasr, Springer, 2006.							
4.	Paul F.Jacobs – "Stereo lithography and other RP & M Technologies", SME, NY 2011							
5	Additive Manufacturing Technologies: 3D Printing, Rapid Prototyping, and Direct Digital							
5.	Manufacturing, Ian Gibson, David W Rosen, Brent Stucker, Springer, 2015, 2nd Edition.							
6	Rapid Tooling: Technologies and Industrial Applications, Peter D.Hilton, Hilton/Jacobs, Paul							
6.	F.Jacobs, CRC press, 2000.							
	ources:							
1.	https://courses.gen3d.com/courses/enrolled/988400							
2.	https://all3dp.com/1/design-for-additive-manufacturing-dfam-simply-explained/#where-to-learn- dfam							
3	https://markforged.com/resources/blog/design-for-additive-manufacturing-dfam							
5	https://manuforged.com/resources/orog/design for additive manufacturing dram							

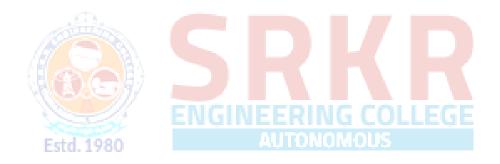
Cour	rse Cod	e Category	L	Т	Р	С	I.M	E.M	Exam		
B20 N	ME411	l PE	3			3	30	70	3 Hrs.		
	POWER PLANT ENGINEERING (Professional Elective- V)										
Com				(]	For ME)						
Cours	v	e Objectives: The course is aimed at providing knowledge of power generation through different prime									
1.		novers viz steam, ICGT, Hydro, nuclear and hybrid systems.									
2.		oart knowledge of	-		-	-		nsideration	s.		
Cours	se Outo	omes: At the end	d of the cou	irse, stud	lents will	be able to)				
S.No				Outco	me				Knowledge Level		
1.	and as	ate the layouts as h handling system	ms	-	-	-		handling	К3		
2.		ss the working of							K3		
3.		ine various hydro	-	-	-				K3		
4.		ibe various type viron <mark>me</mark> nt.	es of nucle	ear pow	er plants	, reactors	s and the	ir impact	K2		
5.		late load factor ated by power pla		and ut	ilization	factor a	nd cost	of power	К3		
			E	VGIN	JEER	ING	COLL	EGE			
		Estd, 1980			LLABU		US				
				•		e			el and handling		
UNI (10 H	Hrs)		erfeed and	underfe	ed fuel b	eds, trav	eling grat	e stokers,	andling systems. spreader stokers,		
		Internal Combu	stion and	Gas Tur	bine Pov	ver Plant	s:				
UNI' (08 F	I -II Hrs)	 Diesel Power Plant: Plant layout with auxiliaries – fuel supply system, air starting equipment, super charging. Gas Turbine Plant: Introduction – classification - construction – layout with auxiliaries, Combined cycle power plants and comparison. 									
	UNIT-III (08 Hrs)Hydro Electric Power Plant: Waterpower – hydrological cycle / flow measurement -hydrographs – storage and pondage –classification of dams and spill ways. Classification of hydroelectric power plants.										
UNIT (08 H	Nuclear Power Station: Nuclear fuel – breeding and fertile materials – nuclear										

		reactor, gas cooled reactor, radiation hazards and shielding – radioactive waste disposal.						
UNI' (08 F		Power Plant Economics and Environmental Considerations: Capital cost, investment of fixed charges, operating costs, general arrangement of power distribution, load curves, load duration curve, definitions of connected load, maximum demand, demand factor, average load, load factor, diversity factor. Effluents from power plants and Impact on environment.						
Textb	ooks:							
1.	A co	ourse in Power Plant Engineering /Arora and Domkundwar/Dhanpatrai& Co.						
2.	Pow	er Plant Engineering /P.C.Sharma / S.K.Kataria Pub						
Refer	ence l	Books:						
1.	Pow	er Plant Engineering: P.K.Nag/ II Edition /TMH.						
2.	Pow	er station Engineering – ElWakil / McGrawHill.						
e-Res	ource	s:						
1.	https	://archive.nptel.ac.in/courses/112/107/112107291/						
2.	https	://www.coursera.org/lecture/electricity/power-plants-gAZ4H						



Course Code	Category	L	Т	Р	С	I.M	E.M	C.M Exam					
B20ME4112	PE				3	30	70	3 Hrs.					
MOOCs-V													
(For ME)													
MOOCs-V course should belong to the B.Tech. Programme and that course should not be studied earlier.													
Students should select a course from SWAYAM/ NPTEL with minimum 12 weeks of duration.													

The percentage obtained for the candidate in MOOCs will be mapped to the grade table given in the Academic Regulations.



Cours	e Code	Category	L	T	Р	С	I.M	E.M	Exam	
B20M	E4113	SOC	1		2	2		50	3 Hrs.	
		11				1			I	
					MATLA	B				
				(Skill (Oriented	Course)				
					(For ME)				
Course	e Objecti									
1	This course helps the students to get a basic understanding of MATLAB and Simulink									
2		-	learn a	oplication	ns of vari	ous doma	ins of med	chanical engi	ineering using	
-	MATL	AB.								
Course	e Outcon	nes: At the e	nd of the	e course t	he studen	ts will be	able to		Γ	
S.No				Οι	itcome				Knowledge	
1									Level	
1	11.0	the basic pro	0	U 1					K3	
2		MATLAB p	-					angla ang ang	K3	
3	Apply various features and functions of MATLAB for solving problems of engineering									
4		p <mark>Simulink</mark> 1	nodels	f physics	1 systems	and perfe	rm simula	tion	K3	
+	Develo			i pirysica	1 systems			uon	KJ	
	- 6		87	S	YLLAB	IIS				
1	Write a	MATLAB	script for				tion of a n	article		
2	-	and the second se					the second second second	ient of a bear	n	
3		MATLAB	_							
4		MATLAB	-	0			1			
5		MATLAB						n		
6		MATLAB								
7		p a simulink	-							
8	-	p a Simulink								
		onitude for a	a system with							
9	Write a MATLAB script for the non-dimensional response magnitude for a system with harmonically moving base and the response phase angle for system with harmonically									
-	moving		8			I	0)	j	
10	_		script for	obtainin	g the dyn	amic equa	ations of a	2-DOF robot		
	I		-							
Refere	nce Boo	ks:								
1	MATL	AB: An Intro	oduction	with Ap	plications	by Rao V	⁷ Dukkipat	i		



SAGI RAMA KRISHNAM RAJU ENGINEERING COLLEGE (AUTONOMOUS)

(Affiliated to JNTUK, Kakinada), (Recognized by AICTE, New Delhi) UG Programmes CE, CSE, ECE, EEE, IT & ME are Accredited by NBA, Accredited by NAAC with A⁺ CHINNA AMIRAM (P.O):: BHIMAVARAM :: W.G.Dt., A.P., INDIA :: PIN: 534 204

Estd:1980

Regula	ation: R20	IV / IV - B.Tech. II - Semester										
MECHANICAL ENGINEERING												
SCHEME OF INSTRUCTION & EXAMINATION (With effect from 2020-21 admitted Batch onwards)												
Course Code	Course Name	Category	Cr	L	Т	Р	Int. Marks	Ext. Marks	Total Marks			
B20ME4201	OME4201 Project Work (Project work, seminar and internship in industry)			0	0	16	60	140	200			
		TOTAL	8	0	0	16	60	140	200			
	EN				CO	LLE	EGE					

Cour	se Code	Category	L	Т	Р	С	I.M	E.M	Exam		
B20	ME4201	PR			16	8	60	140	3 Hrs.		
					1						
				PROJ	ECT WC	ORK					
				(]	For ME)						
Cours	se Objecti	ves:									
1 '	To provide an opportunity to work in group on a topic / problem / experimentation										
2	To encoura	age creative the	inking pro	cess							
3 '	To provide	e an opportunit	y to analy	ze and di	iscuss the	results to	draw con	clusions			
4	To acquire	e and apply fu	Indamenta	l princip	les of pla	anning ar	nd carrying	g out the wo	ork plan of the		
-	project thre	ough observati	ons, discu	ssions ar	nd decisio	n-making	g process.				
Cours	se Outcom	nes: At the end	l of the cou	irse the s	students w	ill be abl	e to		-		
S.No.		Outcome							Knowledge Level		
	, 										
1		a current prob		0					K3		
2	Identify	the objectives	s and meth	odology	for solvir	ng the pro	blem		K3		
3	Design	and Develop to	echno <mark>log</mark> y.	/process	for solvir	ng <mark>the</mark> pro	blem		K4		
4 Evaluate the technology/process K5								K5			
	Y.										
*The	object of I	Project Work i	s to enable	e the stu	dent to ta	ke up inv	vestigative	study in the	broad field of		
	-	L3UU. 1700	•				U		l and practical		
work	to be assig	ned by the De	partment of	on an ind	lividual b	asis or a	group of s	tudents, unde	er the guidance		

of a Supervisor. This is expected to provide a good initiation for the student(s) in R&D work.

The assignment to normally include:

- a) Survey and study of published literature on the assigned topic.
- b) Working out a preliminary approach to the problem relating to the assigned topic.

c) Conducting preliminary Analysis/Modeling/Simulation/Experiment/Design/ Feasibility.

d) Preparing a written report on the study conducted for presentation to the department.

e) Final Seminar, as oral Presentation before a departmental committee.