



## COURSE OUTLINE: RAA201 - ROBOTICS WITH VISION

Prepared: Donovan Kennedy

Approved: Corey Meunier, Chair, Technology and Skilled Trades

<b>Course Code: Title</b>	RAA201: APPLICATIONS OF ROBOTICS WITH VISION
<b>Program Number: Name</b>	4073: ROBOTICS & AUTOMATIO
<b>Department:</b>	ROBOTICS GRADUATE CERTIFICATE
<b>Academic Year:</b>	2022-2023
<b>Course Description:</b>	The objective of this course is to introduce students to machine vision technology and how it is used in conjunction with robotic applications. The student will explore vision components, mounting and lighting, learn different techniques for part identification and investigate frames of reference for cameras and robots using the ABB integrated vision package.
<b>Total Credits:</b>	5
<b>Hours/Week:</b>	5
<b>Total Hours:</b>	75
<b>Prerequisites:</b>	RAA106, RAA110, RAA111
<b>Corequisites:</b>	There are no co-requisites for this course.
<b>Vocational Learning Outcomes (VLO's) addressed in this course:</b>	<b>4073 - ROBOTICS &amp; AUTOMATIO</b>
<b>Please refer to program web page for a complete listing of program outcomes where applicable.</b>	VLO 1 Construct and evaluate robotic control programs for various scenarios against which to model the functionality and stability of automation systems.
	VLO 2 Plan and lead the installation of new industrial equipment and its physical and digital integration with existing systems.
	VLO 3 Collaborate with health and safety personnel to develop plans and specifications that incorporate, among other elements, safety controls and physical guarding to comply with all applicable regulatory safety designs and standards used in industrial robotic applications.
	VLO 5 Validate and optimize the functioning of motor, drive, control, and robotic systems.
	VLO 7 Formulate and use a variety of troubleshooting techniques on new and legacy electromechanical equipment, processes, systems and subsystems.
<b>Essential Employability Skills (EES) addressed in this course:</b>	EES 1 Communicate clearly, concisely and correctly in the written, spoken, and visual form that fulfills the purpose and meets the needs of the audience.
	EES 2 Respond to written, spoken, or visual messages in a manner that ensures effective communication.
	EES 3 Execute mathematical operations accurately.
	EES 4 Apply a systematic approach to solve problems.
	EES 5 Use a variety of thinking skills to anticipate and solve problems.
	EES 6 Locate, select, organize, and document information using appropriate technology and information systems.
	EES 7 Analyze, evaluate, and apply relevant information from a variety of sources.



	<p>EES 9 Interact with others in groups or teams that contribute to effective working relationships and the achievement of goals.</p> <p>EES 10 Manage the use of time and other resources to complete projects.</p> <p>EES 11 Take responsibility for ones own actions, decisions, and consequences.</p>										
<b>Course Evaluation:</b>	<p>Passing Grade: 50%, D</p> <p>A minimum program GPA of 2.0 or higher where program specific standards exist is required for graduation.</p>										
<b>Other Course Evaluation &amp; Assessment Requirements:</b>	<p>Grade Definition Grade Point Equivalent</p> <p>A+ 90 - 100% 4.00 A 80 - 89% 4.00 B 70 - 79% 3.00 C 60 - 69% 2.00 D 50 - 59% 1.00 F (Fail)49% and below 0.00 CR (Credit) Credit for diploma requirements has been awarded. S Satisfactory achievement in field /clinical placement or non-graded subject area. U Unsatisfactory achievement in field/clinical placement or non-graded subject area. X A temporary grade limited to situations with extenuating circumstances giving a student additional time to complete the requirements for a course. NR Grade not reported to Registrar`s office. W Student has withdrawn from the course without academic penalty.</p> <p>Students must pass both the theory portion and the lab portion of the course including the practical test to receive a passing grade in the course.</p> <p>Smart watches, smart phones and similar devices are not allowed during tests or quizzes and must be removed. Smart phones are not acceptable for use as a calculator during a test or quiz.</p>										
<b>Books and Required Resources:</b>	<p>Introduction to Robotics by Colin D. Simpson Publisher: Logic Design Publishing Edition: First ISBN: 978-0-9686860-3-4</p>										
<b>Course Outcomes and Learning Objectives:</b>	<table border="1"> <thead> <tr> <th><b>Course Outcome 1</b></th> <th><b>Learning Objectives for Course Outcome 1</b></th> </tr> </thead> <tbody> <tr> <td>1. Define the initial setup of a vision cell</td> <td>1.1 Define parts of cameras and peripheral equipment used in vision applications such as aperture, lens and lighting. 1.2 Connect a camera to a robot using Ethernet fieldbus 1.3 Demonstrate a typical camera setup in a robot cell</td> </tr> <tr> <th><b>Course Outcome 2</b></th> <th><b>Learning Objectives for Course Outcome 2</b></th> </tr> <tr> <td>2. Illustrate various applications of machine vision</td> <td>2.1 Identify applications of machine vision in robotic applications 2.2 Examine different parts of a typical vision application setup including calibration, lighting, lenses, and field of view. 2.3 Determine 2D offsets using a vision camera</td> </tr> <tr> <th><b>Course Outcome 3</b></th> <th><b>Learning Objectives for Course Outcome 3</b></th> </tr> </tbody> </table>	<b>Course Outcome 1</b>	<b>Learning Objectives for Course Outcome 1</b>	1. Define the initial setup of a vision cell	1.1 Define parts of cameras and peripheral equipment used in vision applications such as aperture, lens and lighting. 1.2 Connect a camera to a robot using Ethernet fieldbus 1.3 Demonstrate a typical camera setup in a robot cell	<b>Course Outcome 2</b>	<b>Learning Objectives for Course Outcome 2</b>	2. Illustrate various applications of machine vision	2.1 Identify applications of machine vision in robotic applications 2.2 Examine different parts of a typical vision application setup including calibration, lighting, lenses, and field of view. 2.3 Determine 2D offsets using a vision camera	<b>Course Outcome 3</b>	<b>Learning Objectives for Course Outcome 3</b>
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3. Demonstrate how machine vision cameras can be used in conjunction with robots for part identification and inspection

3.1 Differentiate between pixels and robot coordinates  
3.2 Apply vision offsets obtained to robot positions  
3.3 Vision applications to inspection and locate features  
3.4 Program a robot to move to part location using vision offsets

**Evaluation Process and Grading System:**

<b>Evaluation Type</b>	<b>Evaluation Weight</b>
Assignments	10%
Lab Practical Exam	20%
Labs	40%
Participation	10%
Written Exam 1	10%
Written Exam 2	10%

**Date:**

November 25, 2022

**Addendum:**

Please refer to the course outline addendum on the Learning Management System for further information.

