

IEEE vTOOLS Event Reporting

IEEE RAS Malaysia Chapter



Title of Event:	"Project for Robotics (MCTE 4352/MCT 4215)"				
Event	<input type="checkbox"/> Physical / <input checked="" type="checkbox"/> Virtual				
Description:	We arranged a project competitions among the students who took the course Robotics. We provided certificates of appreciation for the top performers. The detail of the event description is attached herewith.				
Keywords:	Robotics, Project				
Category:	<input type="checkbox"/> Professional	<input checked="" type="checkbox"/> Technical	<input type="checkbox"/> Non-Technical	<input type="checkbox"/> Administrative	
Sub-category:	Professional:	<input type="checkbox"/> Continuing Education	<input type="checkbox"/> Professional Development	<input type="checkbox"/> Industry Relations	<input type="checkbox"/> Professional (Other)
	Nontechnical:	<input type="checkbox"/> Social	<input type="checkbox"/> Awards Dinner	<input type="checkbox"/> Pre-Univ. activities	<input type="checkbox"/> Nontechnical (Other)
	Administrative:	<input type="checkbox"/> Vice chair		<input type="checkbox"/> Officer training	
Date and Time:	3/06/22-21/06/22		Start Time:	End Time: 11:59 PM	
Event Location:	International Islamic University Malaysia				
Organizational Unit:	Department of Mechatronics Engineering and Autonomous Systems and Robotics Research Unit				
Attendance:	No. of IEEE attended:	0	No. of Guests/students attended:	>10	
Registration:	<input type="checkbox"/> No registration required				
	<input type="checkbox"/> Registration required				
Registration Fees:	-				
Corresponding Name:	Dr. Tanveer Saleh				
Corresponding Email:	tanveers@iium.edu.my				

Photo/ Image

Project for Robotics (MCTE 4352/MCT 4215)

Dr. Tanveer Saleh



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INTERNATIONAL ISLAMIC UNIVERSITY MALAYSIA
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Project/Assignment

- You need to design robot program using as shown in the figure on the right.
- The robot is required only for point to point motion path planning is not required.
- $L1$ = last two digits of your matric number,
- $L2 = 0.1L1, L3 = 1.15L1, L4 = L2, L5 = 0.75L1$
- Develop forward kinematic solution using DH method.
- Simulate the work envelope of the robot using the FK solution.
- Develop the IK solution.



