

Level II CEET Robotics Lesson - Terms and Definitions

1. Some robots use _____ motors to control movement.
2. The junctions between the links of a robot are called _____.
3. The EOAT of a robot is the _____ connected to the face of the robot.
4. The first 3 Axis of a robot make up the _____ axis.
5. Joints 4, 5 and 6 make up the _____ axis.
6. The area in which the tooling works is called the _____ Frame.
7. When the robot is in _____ each axis moves individually.
8. The _____ Frame allows the complete robot to move as 1 unit.
9. The end effector is also known as the _____.
10. The gripper on the end of the 200lc robot is a type of _____.
11. The 200lc uses _____ to actuate the grippers of the robot.
12. List three other types of attachments a robot could use as its EOAT besides grippers:
a. _____ b. _____ c. _____
13. A manufacturing cell must have a _____ around it for protection.
14. The _____ is used to program the robot.
15. _____ are programmed into the robot to move from place to place.
16. A robot with _____ has the capabilities of determining what a part looks like and can make decisions based on size shape and color.
17. A robot is capable of communicating with a PLC though the _____ of the robot.
18. Axis 6 is like the _____ of a human.

WORD BANK:	Vision	Servo	Wrist	Fence	Axis	Curtain
Magnetic	Joint	Points	Air	Water	Oil	Drilling
Suction	Gripper	Tooling	EOAT	Major	Tool	Pendant
I / O	DO	DI	Minor	Hand	Output	