

Name: _____

Date: _____

Robotics

H A V N O I T A R U G I F N O C A U E O F O C S
H C T I W S N A M D A E D W W G T G U X A O A E
L T R E D O C N E Z S Z P N T Z A Z Y C N K C P
P E S A B G O N V A M M B E Y N C Y C T A B T Y
Q O C E B C M E S N O S S W T C L U I H U Z I T
I C K E F E P M B X O A X R A I R N Y M O X V N
C Y P B M X U K N P W Q Y R Y A U F Q O D K E O
Y C R A J H T L D K L I O Z C O Q L C C A C C I
U T R R N J E T F O H U N Y U C A U J J T Y O T
U F W S O F R T V R S H S S K Z N B P W Z C M O
A F W O I O A J W E O Q C J R Z I A R N A L P M
R Z I K W G I K L Y T I L I B I X E L F G E L R
T B H P V L D M H T I R O G L A V Z T L F L I A
I H X O W H E J W S N M R F M A C I L T U T A L
C T G K T H D C H U J D T T O T M V O N Y E N U
U L D A Z L D A T K K F N U D Y S B M J G A T C
L G P Q G E E P X H M M O Z E C K R C T C N R R
A Y N X W R S D E I B C C T S Q N G X X U O O I
T G P I B A I L P F S A K H U A B R V P R H B C
I H D F P W G Z V C L O S E D L O O P R A C O N
O D M B G M N V I A E C P U N F H G E A C U T P
N S K B M J A E V V N W H B E V R B H I X V Q X
N Q Q R M M V L A Z F I I Q Y Y U N H D L I A T
N Y U T E S A A C T U A T O R E N L A R M Y K A

Active Compliant Robot

Computer Aided Design

Circular Motion Type

Dead Man Switch

Configuration

Articulation

Flexibility

Closed Loop

Continuous

Algorithm

Clamping

Carousel

Actuator

Accuracy

Encoder

Control

Gantry

Frame

Error

Cycle

Mode

Path

Base

Axis

Arm