Assignment 6

The due date for submitting this assignment has passed. Do not resubmit. Please answer the questions below and submit the assignment.

1. Which function of a robotic exoskeleton is:
   - Position
   - Velocity
   - Acceleration
   - None of the above

2. No, the answer is incorrect. Answer: Velocity

3. Choose True or False: The main function of a robotic exoskeleton is to:
   - Assist
   - Integrate
   - Protect
   - None of the above

4. No, the answer is incorrect. Answer: Assist

5. Choose True or False: The center of mass of a robotic exoskeleton is:
   - True
   - False

6. No, the answer is incorrect. Answer: False

7. Choose True or False: The calculation of a robotic exoskeleton is based on which body part is actuated:
   - True
   - False

8. No, the answer is incorrect. Answer: True

9. Select the incorrect multiple choice Options:
   - True
   - False
   - None of the above

10. No, the answer is incorrect. Answer: None of the above

11. Choose True or False: One of the common generalizations of robotic exoskeletons is “basically some actuated:
   - True
   - False

12. No, the answer is incorrect. Answer: True

13. Select the incorrect multiple choice Options:
   - True
   - False
   - None of the above

14. No, the answer is incorrect. Answer: None of the above

15. Choose True or False: The center of mass is:
   - True
   - False

16. No, the answer is incorrect. Answer: False

17. Choose True or False: A 4-bar mechanism-based exoskeleton is preferable to a serial link-based exoskeleton because:
   - True
   - False

18. No, the answer is incorrect. Answer: True

19. Select the incorrect multiple choice Options:
   - True
   - False
   - None of the above

20. No, the answer is incorrect. Answer: None of the above

21. Choose True or False: In the force control experiment set-up of the exoskeleton, where is the sensor placed?
   - True
   - False

22. No, the answer is incorrect. Answer: True

23. Select the incorrect multiple choice Options:
   - True
   - False
   - None of the above

24. No, the answer is incorrect. Answer: None of the above

25. Choose True or False: Why unconventional learning modes are preferred over the supervised learning mode for robotic inverse kinematics control of a redundant manipulator:
   - True
   - False

26. No, the answer is incorrect. Answer: True

27. Select the incorrect multiple choice Options:
   - True
   - False
   - None of the above

28. No, the answer is incorrect. Answer: None of the above

29. Choose True or False: What are the features used for the bio-signal based control of the exoskeleton?
   - True
   - False

30. No, the answer is incorrect. Answer: True

31. Select the incorrect multiple choice Options:
   - True
   - False
   - None of the above

32. No, the answer is incorrect. Answer: None of the above

33. Choose True or False: What are the bio-signals used in our study for the control of robotic exoskeleton?
   - True
   - False

34. No, the answer is incorrect. Answer: True

35. Select the incorrect multiple choice Options:
   - True
   - False
   - None of the above

36. No, the answer is incorrect. Answer: None of the above

37. Choose True or False: The expression for the relationship between the joint torque and end-effector force is given by:
   - True
   - False

38. No, the answer is incorrect. Answer: True

39. Select the incorrect multiple choice Options:
   - True
   - False
   - None of the above

40. No, the answer is incorrect. Answer: None of the above

Due on 2020-03-11, 23:59 IST.