REPORT

PRAGATI ENGINEERING COLLEGE

(ApprovedbyAICTE,PermanentlyAffiliatedtoJNTUK,KAKINADA&AccreditedbyNBA)

1-378,A.D.B.Road,Surampalem,NearPeddapuram-533437

“Robotic Arms”

Date: 6-3-2025 To 8-3-2025.

Day: Thursday To Saturday

Turing Club organised by the Dept. of CSE – AI&ML of Pragati Engineering College in association with Career Guidance Cell is organizing a seminar on ***"Robotic Arms"*** as part of Industry 4.0.

REGISTRATION MADE BY STUDENTS :

Sl.No	Roll.No	Student Name
1	23A31A4201	BALUSU NAGA JAHNAVI
2	23A31A4202	CHADALAWADA LAKSHMI SUBRAHMANYA MOUNIKA
3	23A31A4203	DARSI SAHITHYA
4	23A31A4204	DEVARAPALLI HEMA SURYA SAHITYA
5	23A31A4205	GUTTULA AMRUTHA NOOKAMBIKA
6	23A31A4206	ILLA LAKSHMI SIRI SIVA SAI CHANDANA
7	23A31A4207	KAMIDI LALITHA KUMARI
8	23A31A4208	KEDASI ROSHINI
9	23A31A4209	KOLA SRI VANAJA GEETHA
10	23A31A4210	KOPPANA MONIKA SREE BALA
11	23A31A4211	KOPPISETTI SRIJA
12	23A31A4212	KORIBILLI BHAVYA SRI
13	23A31A4213	KOTHAPALLI SAI ROHINI
14	23A31A4214	KOTTAPALLI PUJA
15	23A31A4215	MADDUKURI SRILAYA
16	23A31A4216	MANDAPATI HARSHITHA
17	23A31A4217	MUMMIDI LAKSHMI SAI PAVANA ABHILASYA
18	23A31A4218	PAPPU CHANDRA SRAVANTHI
19	23A31A4219	PARAMSETTI TEJASRI
20	23A31A4220	PEDIREDLA PURUHOOTHIKA SRI LAKSHMI
21	23A31A4221	PENUGONDA MADHURI TEJA
22	23A31A4222	PERUMALLA JYOSHNA RANI
23	23A31A4223	PINJALA TEJA SRI
24	23A31A4224	TEEDA DIVYA CHANDANA
25	23A31A4225	TEKI PRASANNA KUMARI
26	23A31A4226	VADDI SAHITYA
27	23A31A4227	VANAPARTHI NAVYA SRI V VB KEERTHI VARDHINI
28	23A31A4228	VANUM POOJA SRI
29	23A31A4229	VEDULLA DIVYA
30	23A31A4230	VUNDI KAVYA
31	23A31A4231	YELIDINDI RAMA TULASI
32	23A31A4232	AGUTUMUDI HEMANTH
33	23A31A4233	BARRE NAGENDRA BABU
34	23A31A4234	BOMMANA MOHANA SURYA AJAY
35	23A31A4235	BUDIDHA SATHWIK ABHIRAM
36	23A31A4236	CHINNI BALAJI
37	23A31A4237	DASAM NEHRU
38	23A31A4238	DASARI GOUTAM
39	23A31A4239	DASARI JONATHAN
40	23A31A4240	DODDI VENKATA VIJAYA PRADEEP RAJ
41	23A31A4241	ETHAKOTA PHANI VEERA VENKATA ADITHYA
42	23A31A4242	JAGGUMAHANTHI NITHIN SAI
43	23A31A4243	KANCHUPATLA KARTHIKEYA

44	23A31A4244	KANDAPU CHARAN TEJA
45	23A31A4245	KATHA SAI VENU AKSHAY
46	23A31A4246	MADDALA NIKHIL
47	23A31A4247	MADHAVARAPU SAI SUPRATHEEK
48	23A31A4248	MALIPEDDI TARUN
49	23A31A4249	MARNI SHYAM SUNDAR
50	23A31A4250	MENDI SADU
51	23A31A4251	NAKKA AARON SUSHMITH
52	23A31A4252	NELLI VENKAT SAI PRAVEEN
53	23A31A4253	OLETI VAMSI
54	23A31A4254	PABBU SUDHEER
55	23A31A4255	PADMANADHUNI VEERA VENKATA SAI AKASH
56	23A31A4256	PANTHADI SWAROOP KUMAR
57	23A31A4257	PATTAPU PETER PAUL
58	23A31A4258	RAKETLA PREMASAI
59	23A31A4259	SALAGRAMA SURYA PAVAN
60	23A31A4260	SANNIGANTI AMIT PAUL
61	23A31A4261	SRIGHAKOLLAPU R N V H S SRI KRISHNA
62	23A31A4262	TATAPUDI NISHOK CHANDRA
63	23A31A4263	TURANGI GUNAVARDHAN DEVI PRASAD
64	23A31A4264	YARRA MANIKANTA
65	23A31A4265	ADDENKI SATYA SANTOSHI MAHALAKSHMI
66	23A31A4266	ALLAMPALLI SHARON ROSE
67	23A31A4267	AMJURI CHAITANYA SREYA
68	23A31A4268	B ANURITHIKA
69	23A31A4269	BELAGAM ANKITA PRIYADARSHINI
70	23A31A4270	CHAKKA VASAVI
71	23A31A4271	CHIKKALA KUSUMA CHANDU
72	23A31A4272	CHINTALA RAMANESWARI
73	23A31A4273	GANDHAM KAVYANJALI
74	23A31A4274	GEDDADA LAVANYA
75	23A31A4275	JAGADAM CHARISHMA
76	23A31A4276	KAKARLAPUDI ANIKSHA
77	23A31A4277	KALAGA CHANDINI NAGA LEELA
78	23A31A4278	KONA DEVI
79	23A31A4279	KOTHA SUGANYA
80	23A31A4280	KUDUPUDI MEGHANA
81	23A31A4281	MANDE JAYATHI SRI ANUSHKA
82	23A31A4282	MANEPALLI GAYATHRI BHAVANA DEVI
83	23A31A4283	MEENAVALLI LAKSHMI APOORVA
84	23A31A4284	MOHAMMED ASMA
85	23A31A4285	NUNNA NAGA SRILAKSHMI
86	23A31A4286	PADALA SIRI CHANDANA
87	23A31A4287	PAMPANA JYOTHIKA SRI RAMANI
88	23A31A4288	PATCHAMATLA VEERA VENKATA LAKSHMI N SUPRIYA

Attendance list :

PRAGATI ENGINEERING COLLEGE
(Autonomous)
B.Tech
Computer Science and Engineering
(Artificial Intelligence & Machine Learning)

EVENT NAME: Robotic Arms
DATE: 11-03-2025
SPEAKER NAMES: P.V. Deepthi, K. Deepika, K. V. Akhila
The list of students attended for this event.

S.No	Roll No.	Name of the Student	Year	Signature
1	23A31A42A5	G. Mukesh	II	G. Mukesh
2	23A31A42C2	O. Pradeep kumar	II	O. Pradeep
3	23A31A42A0	B. Rajesh	II	B. Rajesh
4	23A31A42B9	K. Harishankar	II	K. Harishankar
5	23A31A42B7	M. Bhanu Praveen	II	M. Bhanu Praveen
6	23A31A42D0	V. Siddartha	II	V. Siddartha
7	24A35A4209	B. Durgaprasad	II	B. Durgaprasad
8	23A31A4232	A. Hemanth	II	A. Hemanth
9	23A31A4243	K. Karthikeya	II	K. Karthikeya
10	23A31A4244	K. Charan teja	II	K. Charan Teja
11	23A31A4255	P. V. V. S. Akash	II	P. Akash
12	23A31A4263	T. Gunavardhan	II	T. Gunavardhan
13	23A31A4248	M. Tarun	II	M. Tarun
14	23A31A4254	P. Sudheer	IV	P. Sudheer

A. Eswari / G. Swarupa
Student coordinator

Faculty Coordinator

HoD-CSE(AI&ML)

PRAGATI ENGINEERING COLLEGE

(Autonomous)

B.Tech

Computer Science and Engineering
(Artificial Intelligence & Machine Learning)

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S.No	Roll No.	Name of the Student	Year	Signature
15	23A31A4235	B. Sathwik Abhi Ram	II	B. Abhi Ram
16	23A31A4245	K.S.V. AKSHAY	II	
17	24A35A4203	A. Thenus Chowdary	II	
18	23A31A4234	B. Mohana Sooraj Ajay	II	
19	23A31A42I3	N. Jaya Aashik	II	N. Ashik
20	23A31A42G4	B. chandrasekharswamy	II	B.C.S swamy.
21	23A31A42I2	N.V. Poorna chandra Varma	II	N. RAJU
22	23A31A42G9	G.D.E. Ashok	II	G.D.E. Ashok
23	24A35A4206	T. Sivaganga	II	T Siva
24.	22A31A4236	Ch. Balaji	II	Ch. Balaji
25.	23A31A4258	O. Vamsi	II	O. Vamsi
26.	22A31A42B3	K. Prudhvi	II	K.P.V.N. Krishna
27.	24A35A4211	K. Satyanarayana	II	K. Satyanarayana
28	23A31A4214	Kottapalli Priya.	II nd	Priya
29.	23A31A4222	P. Jyoshna Rani	II n	P. Jyoshna

G. Swaroopa / A. Eswari
Student coordinator

Faculty Coordinator

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S.No	Roll No.	Name of the Student	Year	Signature
1	23A31A4205	B.Mathru Sri	II	B.Mathru Sri
2	23A31A42D6	ch.Varsha	II	ch.Varsha
3	23A31A42D1	A. Sowmya	II	A. Sowmya
4	23A31A4212	K.Bhavya Sri	II	K.Bhavya Sri
5	23A31A4208	K.Roshini	II	K.Roshini
6	23A31A42J7	K.Kusuma Sri	II	K.Kusuma Sri
7	23A31A4213	K.Sai Rohini	II	K.Sai Rohini
8	23A31A42J6	S.Swaroopa Rani	II	S.Swaroopa Rani
9	23A31A4202	Ch.L.S.Mounika	II	Ch.L.S.Mounika
10	23A31A4220	P.Puruhoothika	II	P.Puruhoothika
11	23A31A42E2	K.Anjani Surya prabha	II	K.A.S. prabha
12	23A31A42D7	Ch.y.Ramya Sri	II	Ch.y.Ramya Sri
13	23A31A42D8	B.Lakshmi Sravani	II	B.L.Sravani
14	23A31A42F6	T. Renuka Lakshmi	II	T. Renuka

A.Eswari / G.Swarupa
Student coordinator

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S.No	Roll No.	Name of the Student	Year	Signature
1	24A35A4204	K. Goutham Karthik	II	GK
2	24A35A4205	P. Jagadeesh	II	P. Jag
3	23A31A42H7	K. Rajesh	II	K. Rajesh
4	23A31A42H2	G. Durga Malleswari	II	G. Malli
5	23A31A42J3	V. Satish preetham	II	V. S. preetham
6	23A31A42H5	K. Mohan Sai	II	K. Mohansai
7	23A31A42I4	P. Sriram	II	P. Sriram
8	23A31A42B5	K. Satya Sai	II	K. Satya Sai
9	23A31A42A1	Ch. V. Sairam	II	Chvsa
10	24A35A4210	K. Manikanta sai Ram	II	K. M. sai Ram
11	23A31A42G3	A. V. Tarun	II	A. V. Tarun
12	23A31A42J5	Y. Lalith Aditya	II	Y. Lal
13	23A31A42G5	Ch. Pranay Reddy	II	Ch. P. Reddy
14	23A31A42G8	D. Aditya	II	D

AEswari/G.Swarupa
Student coordinator

Faculty Coordinator

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S.No	Roll No.	Name of the Student	Year	Signature
15	23A31A4236	Ch.Balaji	II	Ch.Balaji
16	23A31A4253	O.Vamsi	II	O.Vamsi
17	23A31A42B3	K.Prudhvi	II	K.P.V.N.krishna
18	24A35A4211	K.Satyanarayana	II	K.Satyanarayana

G.Swarupa/A.Eswari
Student coordinator

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S.No	Roll No.	Name of the Student	Year	Signature
1	23A31A4268	B. Amurithika	II	B Amurithika
2	23A31A4272	ch. Ramaneswari	II	ch. Ramaneswari
3	23A31A4269	B. Ankita Priyadarshini	II	B. Ankita
4	23A31A4270	Ch. Vasavi	II	Ch. Vasavi
5	23A31A4282	M. Bhavana	II	M. Bhavana.
6	23A31A4283	M.L. Apoorva	II	M.L. Apoorva
7	23A31A4284	MD Asma	II	Asma
8	23A31A4285	N.N. Sri Lakshmi	II	Sri Lakshmi
9	23A31A4281	M. J.S. Anushka	II	M. J.S.
10	23A31A4226	V. Sahitya	II	V. Sahitya
11	23A31A4221	P. Madhuleja	II	P. Madhuleja
12	23A31A4231	Y. Ramatulasi	II	Y. Ramatulasi
13	23A31A4201	B. Naga Jahnavi	II	B.N. Jahnavi.
14	23A31A4216	M. Harshitha	II	Harshitha

A. Eswari / G. Swapna
Student coordinator

Faculty Coordinator

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S.No	Roll No.	Name of the Student	Year	Signature
1	23A31A42D4	B. Hari Deepika	II	B. Hari Deepika
2.	23A31A42E3	K. NavyaJyothi	II	K. Navya
3.	23A31A4267	A. Chaitanyasriya	II	A. Chaitanyasriya
4.	23A31A4280	K. Meghana	II	K. Meghana
5.	23A31A42F8	K. Devi	II	K. Devi
6.	23A31A42F7	T. Chandrakranthi	II	T. Chandrakranthi
7	23A31A42F4	R. KUSUMA	II	R. KUSUMA
8.	23A31A42D9	D. Sriya	II	D. Sriya
9.	23A31A42F1	P. LiKhitha	II	P. Likhitha
10.	23A31A4265	A. Santoshi	II	A. Santoshi
11.	24A35A4207	D. Srikanakadurga	II	D. Durga
12.	23A31A42F9	K. Suganya	II	K. Suganya
13	23A31A4277	K. Chandini	II	K. Chandini
14.	23A31A4214	Kottapalli pooja	II	Pooja
15.	23 A31A4222	P. Jyoshnarani	II	P. Jyoshnarani

G. Swaroopa / A. Eswari
Student coordinator

A. Sujana
Faculty Coordinator

HoD-CSE(AI&ML)

FEED BACK ANALYSIS

How satisfied were you with the session content:

Total number of Students **: 84**

TECHNICAL PRESENTATION OF THE SPEAKER (1(Lowest)-5(Highest)):

Number Of Students Rating **5 : 45**

Number Of Students Rating **4 : 28**

Number Of Students Rating **3 : 7**

Number Of Students Rating **2.5: 4**

CONTENT OF THE TOPIC COVERED (1(Lowest)-5(Highest)):

Number Of Students Rating **5 : 52**

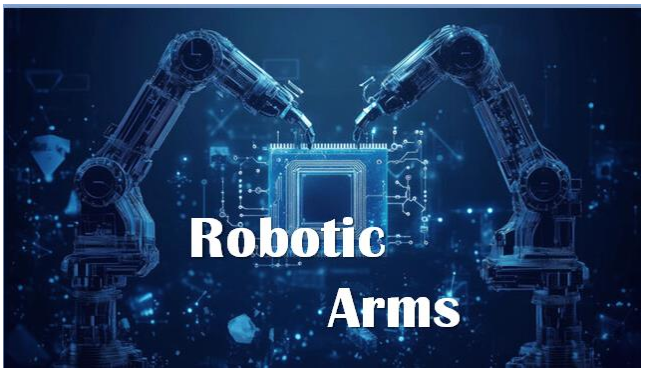
Number Of Students Rating **4 : 29**

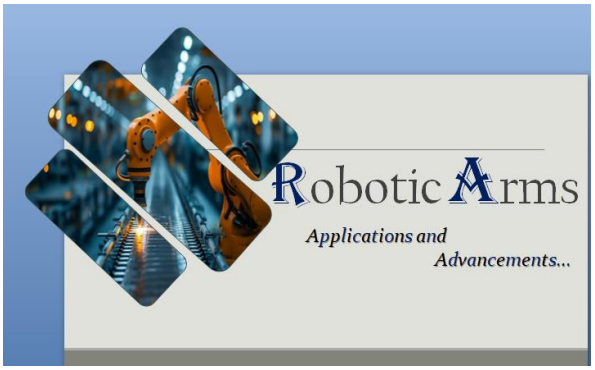
Number Of Students Rating **3 : 3**

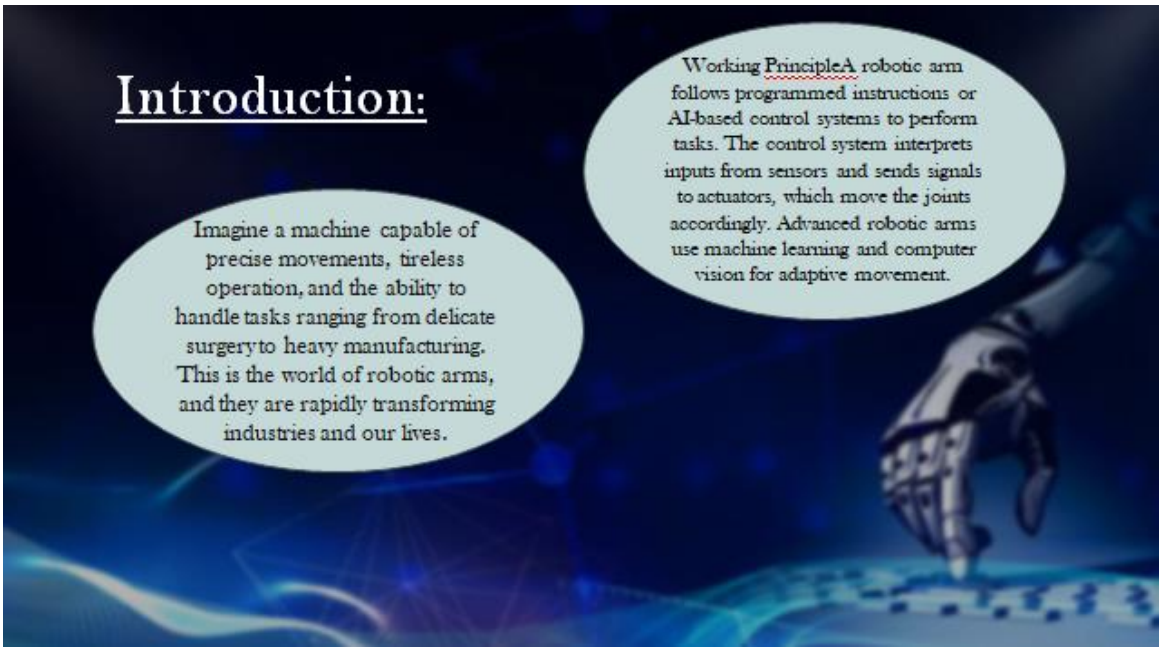
Overall rating: **Very Good**

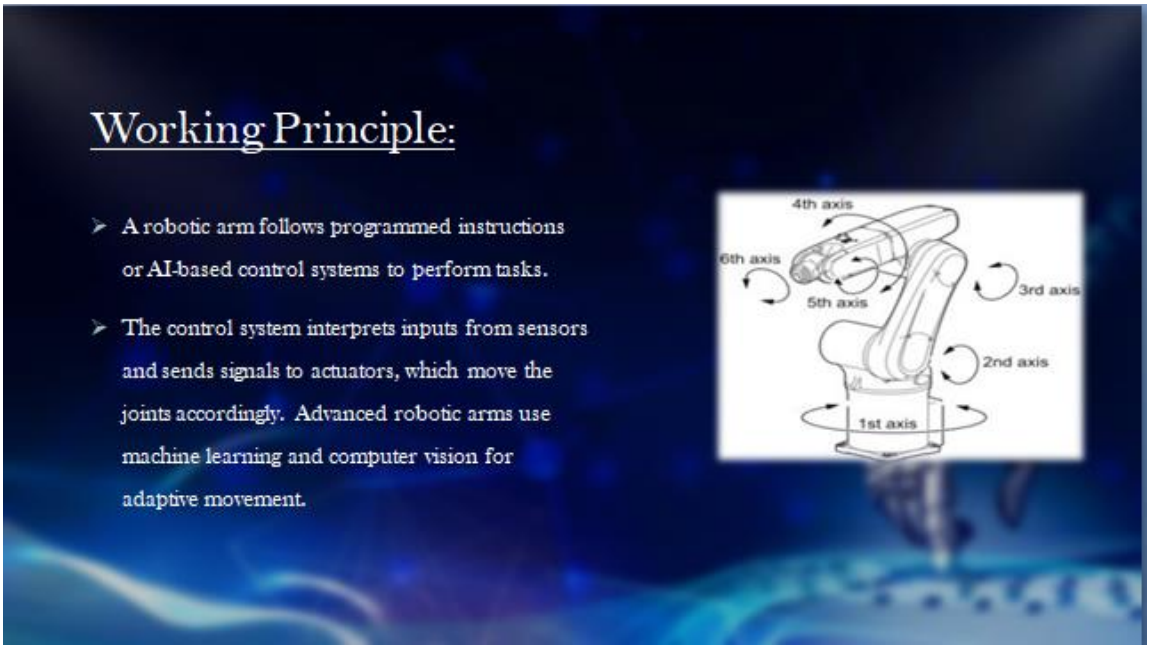
Overall Feedback :**GOOD**

Content Delivered in the Event:



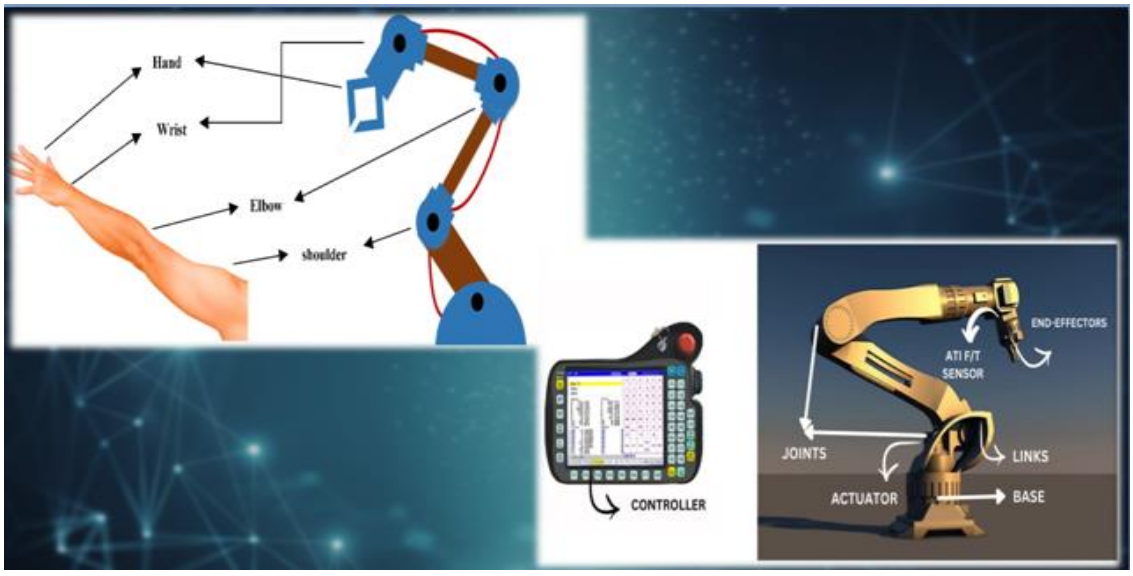


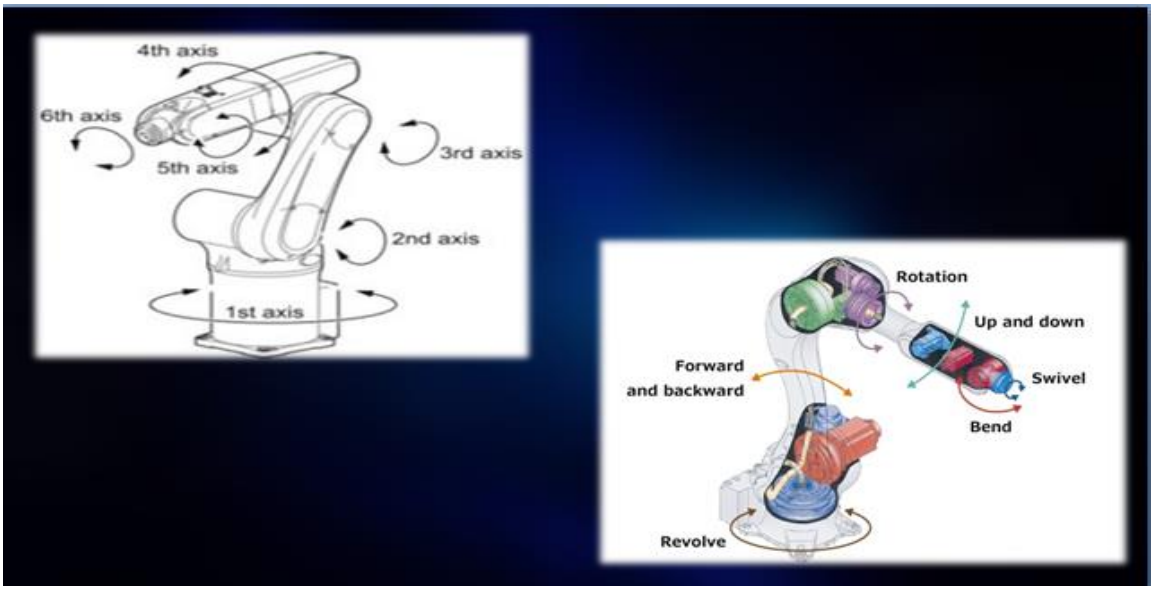




Components of Robotic Arm:

- Base:The foundation of the robotic arm, which holds it stable.Can be fixed or mobile (e.g., on a moving platform).
- Joints:Allow movement and flexibility.Types: Rotational, prismatic (linear movement), spherical.
- Links:The rigid segments that connect joints.
- Actuators:Motors that drive the arm's motion.Types: Electric (servo, stepper motors), Hydraulic, Pneumatic.
- End-Effector (Gripper/Tool):The "hand" of the robotic arm, which performs tasks.Can be a gripper, suction cup, welding torch, or robotic hand.
- Sensors:Provide feedback on position, force, and obstacles.Examples: Proximity sensors, force sensors, vision cameras.
- Controller & Software:The brain of the robotic arm, controlling movement.Uses programming languages like Python, C++, and ROS (Robot Operating System).





Key Characteristics:

- **Programmability:** Robotic arms are controlled by computer programs, allowing for automated and also repeatable tasks.
- **Degrees of Freedom:** The number of independent movements a robotic arm can make. More degrees of freedom generally mean greater flexibility.
- **Precision:** Robotic arms can perform tasks with a high degree of accuracy and repeatability.
- **Payload Capacity:** The amount of weight a robotic arm can lift or manipulate.
- **End Effector:** The tool attached to the end of the arm, customized for specific tasks (e.g., grippers, welders, spray guns).

Overview of Applications:

- From manufacturing and healthcare to exploration and research, robotic arms are finding applications in a vast range of fields.
- Robotic arms, with their versatile applications, are transforming industries by automating tasks like material handling, welding, assembly, and more, increasing efficiency and reducing human labor.
- Robotic arms are helping in warehouses to seamlessly load and unload heavy items from conveyor belts, transport fragile products without causing damage, and stack pallets with impeccable accuracy.

Examples of robotic arms assembling products:

Welding: Show robotic welding in automotive or other industries.

Painting: Show robotic arms painting cars or other objects.

Material Handling: Show robotic arms moving materials in a warehouse.

Packaging: Show robotic arms packaging products. Discuss the benefits of using robotic arms in manufacturing (e.g., increased efficiency, precision, safety).

Types of robotic arms:

Spherical robotic arm

SCARA robotic arm

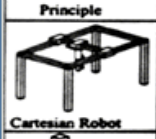
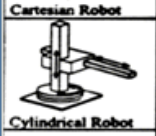
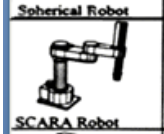
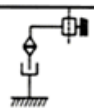
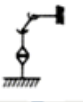
Articulated robotic arm

Cartesian robotic arm

Cylindrical robotic arm

Collaborative robotic arm

Parallel robotic arm

Principle	Kinematic Structure	Workspace	Function
 Cartesian Robot			Rectangular arms are sometimes called "**Cartesian**" because the arm´s axes can be described by using the X, Y, and Z coordinate system. It is claimed that the cartesian design will produce the most accurate movements.
 Cylindrical Robot			A **cylindrical** arm also has three degrees of freedom, but it moves linearly only along the Y and Z axes. Its third degree of freedom is the rotation at its base around the two axes. The work envelope is in the shape of a cylinder.
 Spherical Robot			The **spherical** arm, also known as polar coordinate robot arm, has one sliding motion and two rotational, around the vertical post and around a shoulder joint. The spherical arm's work envelope is a partial sphere which has various length radii.
 SCARA Robot			The **SCARA** (Selection Compliance Assembly Robot Arm) is also known as a horizontal articulated arm robot. Some SCARA robots rotate about all three axes, and some have sliding motion along one axis in combination with rotation about another.
 Articulated Robot			The last and most used design is the **jointed**-arm., also known as an articulated robot arm. All joints in the arm can rotate, creating six degrees of freedom The other three are pitch, yaw, and roll. Pitch is when you move your wrist up and down.

Spherical robot / Polar robot:

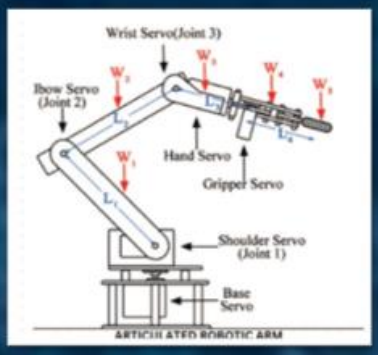
Used for handling machine tools, spot welding, die casting, fettling machines, gas welding and arc welding. It is a robot whose axes form a polar coordinate system.

SCARA Robot(Selective Compliance Assembly Robot Arm):

- SCARA robots have a distinctive design with two parallel arms connected by joints, allowing movement in a single plane (typically the horizontal plane).
- They also have a vertical axis for up-and-down motion.
- This configuration gives them "selective compliance" – they are compliant (flexible) in the X-Y plane but rigid in the Z-axis.

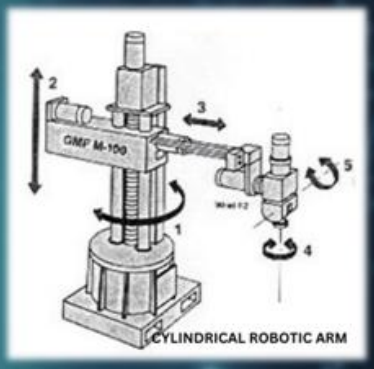
Articulated Robots:

- Description: The most common type, resembling a human arm with multiple joints (typically 4-6 degrees of freedom).
- Advantages: Highly flexible and versatile, capable of complex movements and reaching into tight spaces.
- Applications: Welding, painting, assembly, material handling.



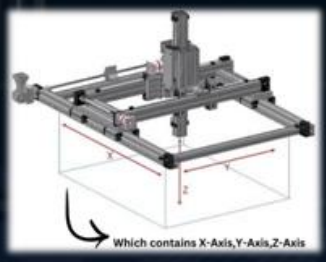
Cylindrical Robots:

- Description: Have one rotary axis and two linear axes, creating a cylindrical workspace.
- Advantages: Relatively simple design, suitable for specific tasks.
- Applications: Pick and place, material handling, welding.



Cartesian Robots (Gantry Robots):

- Description: Move along three linear axes (X, Y, Z). Often large and used for heavy lifting.
- Advantages: Simple to program, high accuracy, large workspace.
- Applications: Material handling, packaging, palletizing, CNC machining.

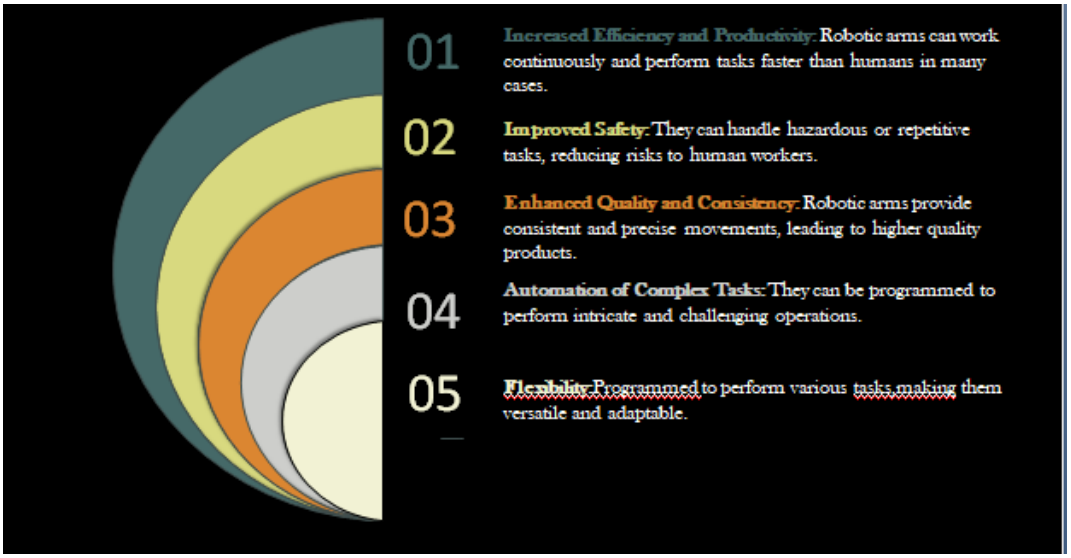


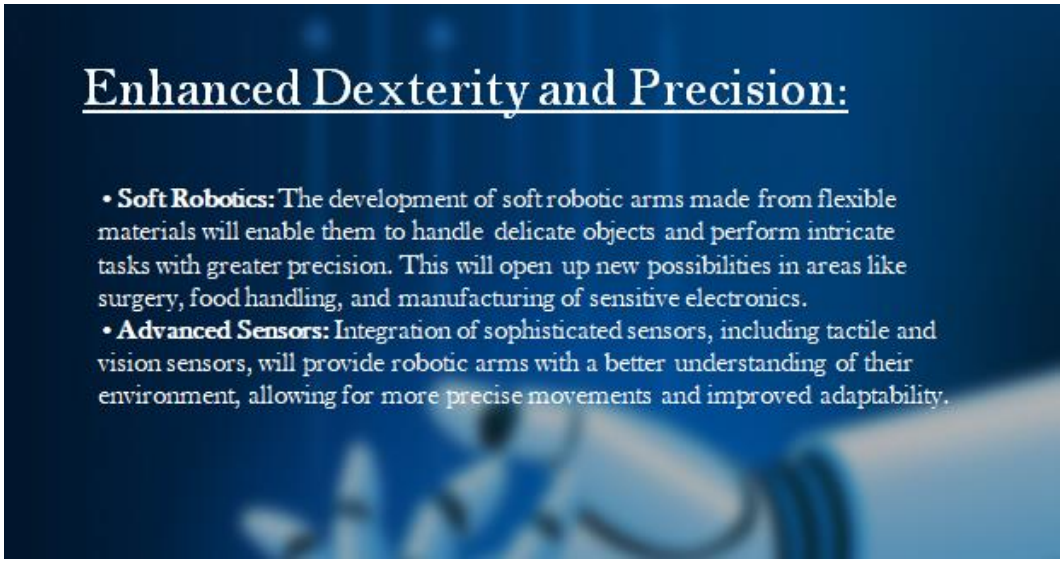
Collaborative Robots (Cobots):

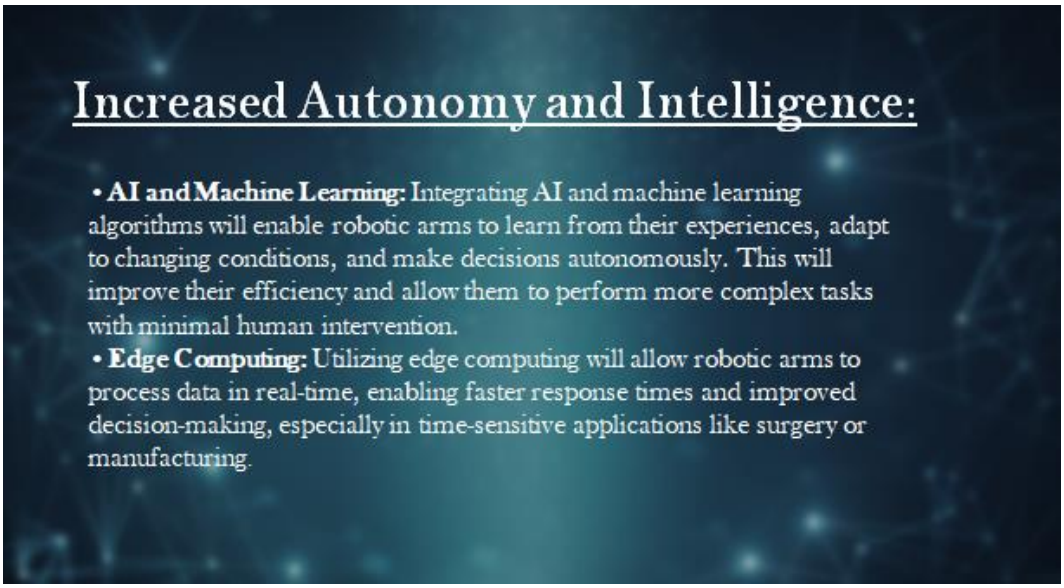
- Description: Designed to work collaboratively with humans in a shared workspace. Focus on safety and ease of use.
- Advantages: Safe for human interaction, easy to program, adaptable to various tasks.
- Applications: Assembly, material handling, inspection, research.

Parallel Robots (Delta Robots):

- Description: Use multiple linked parallel arms to support a single end effector.
- Advantages: High speed and acceleration, precise movements.
- Applications: High-speed pick and place, packaging, sorting.


01
Increased Efficiency and Productivity: Robotic arms can work continuously and perform tasks faster than humans in many cases.
02
Improved Safety: They can handle hazardous or repetitive tasks, reducing risks to human workers.
03
Enhanced Quality and Consistency: Robotic arms provide consistent and precise movements, leading to higher quality products.
04
Automation of Complex Tasks: They can be programmed to perform intricate and challenging operations.
05
Flexibility: Programmed to perform various tasks making them versatile and adaptable.


Enhanced Dexterity and Precision:
• Soft Robotics: The development of soft robotic arms made from flexible materials will enable them to handle delicate objects and perform intricate tasks with greater precision. This will open up new possibilities in areas like surgery, food handling, and manufacturing of sensitive electronics.
• Advanced Sensors: Integration of sophisticated sensors, including tactile and vision sensors, will provide robotic arms with a better understanding of their environment, allowing for more precise movements and improved adaptability.


Increased Autonomy and Intelligence:
• AI and Machine Learning: Integrating AI and machine learning algorithms will enable robotic arms to learn from their experiences, adapt to changing conditions, and make decisions autonomously. This will improve their efficiency and allow them to perform more complex tasks with minimal human intervention.
• Edge Computing: Utilizing edge computing will allow robotic arms to process data in real-time, enabling faster response times and improved decision-making, especially in time-sensitive applications like surgery or manufacturing.

Expanding Applications:

- **Service Robots:** Robotic arms will be increasingly integrated into service robots for tasks such as cleaning, cooking, elder care, and customer service. This will improve efficiency and quality of service in various industries.
- **Healthcare:** Robotic arms will play a greater role in surgery, rehabilitation, diagnostics, and drug dispensing, leading to improved patient outcomes and more efficient healthcare systems.
- **Space Exploration:** Robotic arms will be crucial in space exploration for tasks like assembling habitats, collecting samples, and performing repairs, enabling safer and more efficient space missions.
- **Construction:** Robotic arms will be used in construction for tasks such as bricklaying, welding, and material handling, improving safety and productivity on construction sites.

Human-Robot Collaboration:

- **Cobots:** Collaborative robots (cobots) designed to work alongside humans will become more prevalent in various industries. This will enable humans and robots to combine their strengths, leading to increased productivity and improved working conditions.
- **Intuitive Interfaces:** The development of intuitive interfaces, such as voice control or gesture recognition, will make it easier for humans to interact with and control robotic arms, fostering better collaboration.

Conclusion:

- In conclusion, robotic arms have emerged as a transformative technology with a profound impact across diverse sectors.
- From revolutionizing industrial manufacturing through automation and precision to enabling groundbreaking advancements in medical procedures and space exploration, their versatility and adaptability are undeniable.
- While challenges remain in areas like cost, complexity, and the need for sophisticated AI, the trajectory of robotic arm development points toward a future where they become even more integrated into our lives.
- Continued innovation in areas like soft robotics, enhanced sensing, and human-robot collaboration promises to unlock even greater potential, paving the way for more efficient, safer, and more productive workplaces, as well as opening up new possibilities in fields we can only begin to imagine.
- As robotic arms become more intelligent, dexterous, and accessible, they will undoubtedly play a crucial role in shaping the future of technology and human endeavor.

Learning is Supreme Diety

Pragati Engineering College

(AUTONOMOUS)

Department of

CSE(ARTIFICIAL INTELLIGENCE & MACHINE LEARNING)

organizes

ROBOTIC ARMS

- The Art of Automated Dexterity

Event Speakers:-

K.Veera Akhila
22A31A42D7

K.Deepika
22A31A42D9

P.Vidhya Deepthi
22A31A42E6

Date:- 11-03-2025
Venue:-Conference Hall
Time:-1:30PM - 3:30PM

Head of the Department

Dr. A.Radha Krishna

Student coordinators:

A.Eswari-22A31A42C7
G.Swarupa-22A31A42D3

Faculty coordinators

Mrs.L.Yamuna
Mrs.A.Srujana Jyothi

Event Photos:


GPS Map Camera
Kakinada,Andhra Pradesh,India
Peddapuram, Kakinada, Andhra Pradesh 533437, India
Lat 17.082954, Long 82.053939
03/11/2025 02:55 PM GMT+05:30
Note : Captured by GPS Map Camera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Kakinada,Andhra Pradesh,India
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Note : Captured by GPS Map Camera

PRAGATI ENGINEERING COLLEGE
(Autonomous)

DEPARTMENT OF CSE (Artificial Intelligence & Machine Learning)

PEC / Admin / Circular / 2025 / Turing CLUB

Date: 8-03-2025.

All the staff, Pragati Turing club coordinators, First year Students are informed that a seminar on **"Robotic Arms"** is being organized by Turing club & IAENG in association with career Guidance cell. The details are given below.

Date: 11- 3-2025
Time: 1:30 PM to 3:30 PM
Venue: Conference Hall
Faculty Co-ordinator: Mrs.L.Yamuna, Mrs. A Srujana Jyothi
Student Co-ordinator: A. Eswari (III -year CSE (AI&ML)-22A31A42C7)
G.Swarupa (III-year CSE (AI&ML)-22A31A42D3)
Speaker: K.Veera Akhila (III -year CSE (AI&ML)-22A31A42D7)
K.Deepika (III -year CSE (AI&ML)-22A31A42D9)
P.V.Deepthi (III -year CSE (AI&ML)-22A31A42E6)

Faculty coordinator **HoD-CSE(AI&ML)**

Copy to:

1) Chairman /All Directors / Vice President for kind information.
2) Vice Principal/Dean T&P for information.
3) All HoDs are requested to circulate among your staff members.
4) Convener-Career Guidance cell
5) Office File.