Politechnika Poznańska, Wydział Automatyki, Robotyki i Elektrotechniki

Lista zagadnień na egzamin dyplomowy

Kierunek studiów: Automatyka i Robotyka Stopień studiów: pierwszy
Specjalność: Automatyka

Ways to pass arguments to functions in C++. [Information engineering]	Nr	Zagadnienie
The role of the IP address in network communication. [Information engineering] 3 Basic laws of electrical engineering. [Electrical engineering] 4 Conservation laws in physics. [Physics] 5 Basics of wave optics (Interference, diffraction, polarization). [Physics] 6 Parameters of random signals. [Signals and dynamic systems] 7 Fourier transformation - its physical meaning and properties. [Signals and dynamic systems] 8 Controllers and control performance in a closed-loop system. [Automatic control] 9 Stability of linear continuous-time systems. [Automatic control] 10 Modelling of dynamical systems in discrete-time. [Automatic control] 11 Sampling versus control performance and properties of a model. [Automatic control] 12 Effects of presence of nonlinearities in control systems. [Automatic control] 13 Programming model for real-time systems. [Real-time systems] 14 Programming model for real-time systems. [Real-time systems] 15 Measurement uncertainty. [Metrology] 16 Sensors and transducers of non-electrical quantities. [Metrology] 17 Software and hardware implementation of combinational circuits. Minimization of logical expressions. [Microprocessor systems] 18 Software and hardware implementation, incl. multiplexers, demultiplexers, flip-flops and memory; software and hardware implementation of sequential circuits. [Microprocessor systems] 19 Peripheral systems (GPIO, TIM, ADC, DAC) of the microcontroller, their operation and hardware interfaces. [Microprocessor systems] 19 Pripheral systems (GPIO, TIM, ADC, DAC) of the microcontroller, their operation and hardware interfaces. [Microprocessor systems] 20 Classification of methods for solving inverse kinematics of robot manipulators. [Robotics] 21 Classification of methods for solving inverse kinematics of robot manipulators. [Robotics] 22 Classification of methods for solving inverse kinematics of robot manipulators. [Popidal controllers and PLC] 23 Robot control methods. [Robotics] 24 Design and manufacturing process of the Printed Circuit		
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40	Petri nets. [Flexible manufacturing systems]