

Introduction

Rigid Motions and Homogeneous Transformations.

Forward Kinematics: The Denavit-Hartenberg Representation.

Inverse Kinematics.

Velocity Kinematics: The Manipulator Jacobian.

Dynamics.

Independent Joint Control.

Multivariable Control.

Force Control.

Feedback Linearization.

Variable Structure and Adaptive Control.

References.

Suggested Reading.

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