

# 100-2 Preliminary Syllabus, Da-Yeh Univ

Information			
Title	高等機器人學	Serial No. / ID	2109 / ADR5053
Dept.	機械與自動化工程學系博士班	School System / Class	研究所博士班1年1班
Lecturer	鄭鴻儀	Full or Part-time	專任
Required / Credit	Optinal / 3	Graduate Class	No
Time / Place	(二)2 / (四)34 /	Language	English

Introduction	
Omitted.	

Outline	
<ol style="list-style-type: none"><li>1. Introduction</li><li>2. Spatial Descriptions and Transformations</li><li>3. Manipulator Kinematics</li><li>4. Inverse Manipulator Kinematics</li><li>5. Jacobians: Velocities and Static Forces</li><li>6. Manipulator Dynamics</li><li>7. Trajectory Generation</li><li>8. Manipulator-Mechanism Design</li><li>9. Linear Control of Manipulators</li><li>10. Nonlinear Control of Manipulators</li><li>11. Force Control of Manipulators</li></ol>	

Prerequisite	
Omitted.	