

- Newton's laws, 208, 209
- Nonlinear algebraic equations, 66–72, 101
- Nonlinearity, order, 13
- Nonzero entry, 104
- Numerical:
 - differencing, 340–41, 345
 - integration formula, 307
 - methods (*see* Algorithms)
- O**
- Open-chain (*see also* Mechanism):
 - multibranch, 334
 - single-branch, 331, 333
- Optimal design, 2
- Optimization, 1, 6, 316, 343
- Ordinary differential equations, 244, 301, 313
 - closed-loop, 319
 - first-order, 301
 - open-loop, 319
 - second-order, 13, 302, 314, 319
 - stability, 319
- P**
- Particle dynamics, 208–11
- Passive point of view, 157
- Pendulum:
 - double, 37
 - single, 3, 322, 324
 - triple, 40
- Period of oscillation, 278
- Pivoting, 53, 61
 - column, 55
 - full (*or* complete), 54, 55, 61, 324, 327, 355
 - partial, 54, 61, 63, 324, 327, 355
 - row, 54, 55
- Planar:
 - dynamics, 227
 - kinematics, 77
- Platform, horizontal, 269
- Pointers, arrays:
 - DAP, 257
 - KAP, 121
- Points of interest, 127
- Polynomial approximation, 302, 307
- Position:

- Potential energy, 341
 - minimization, 342
- Predictor-corrector algorithms, 309, 323
- Products of inertia, 218, 225
- Program expansion, 140
- Pulling forces, 231, 234, 235
- Pushing forces, 231, 234, 235
- Q**
- QR decomposition, 327
- Quaternions, 153
- Quick-return mechanism, 80, 82, 99, 110
 - kinematic model, 112
 - simulation, 139
- R**
- Reaction force (*see* Constraint, force)
- Rigid body (*see also* Body), 35, 36
- Robot manipulator, 5, 245, 247
- Rotation:
 - angle, 39, 77, 158, 316
 - clockwise, 157
 - counterclockwise, 77, 157
 - formula, 159
- Rotational transformation matrix, 78, 157, 159, 348, 351
- Runge-Kutta, 260, 277, 315
 - algorithms, 303
 - fourth-order, 303
 - second-order, 303
 - subroutine, 260, 304
 - array pointers, 257
- S**
- Satellite antenna, 3–5
- Semirotating coordinate system, 176
- Single-step algorithm, 308, 310
- Singular-value decomposition, 327
- Slider-crank mechanism, 3, 7–9, 39, 40, 100, 105
 - Jacobian matrix, entries, 111
 - kinematic model, 108
 - simulation, 137
- Slip, roll with, 69
- Sparse matrix, 110, 144
- Spatial:

- Spline, cubic, 89
- Spring, 15, 222, 232, 236, 255, 271
 - angle, 236
 - characteristics, 232
 - compression, 232
 - potential (strain) energy, 342
 - stiffness, 233, 236
 - subroutine, 259, 264
 - tension, 232
- Stabilization terms, 320
- Static:
 - analysis, 255, 266
 - balance force, 245
 - equilibrium analysis, 339
 - force, 244
- Statics, 6
- Steering system, automobile, 3
- Step-size, 227, 302, 311
 - uniform, 302
 - variable, 311
- Stiff systems, 310, 327
- Structure, 244
- SUBROUTINE:
 - BODYF, 263
 - DIFEQN, 261
 - DRVVR, 133
 - DYNAM, 262
 - FORCE, 263
 - FUNCT, 131, 263
 - INBODY, 124, 258
 - INDRVVR, 127
 - INGRND, 125, 259
 - INPOIN, 127, 260
 - INRVLT, 124, 259
 - INSMPL, 126, 259
 - INSPRG, 259
 - INTRAN, 125, 259
 - JACTRN, 267
 - KINEM, 128
 - LU, 63, 263
 - LINEAR, 64, 263
 - MASS, 262
 - NEWTON, 71
 - FUNCT, 72
 - NUTON2, 129
 - REACT, 266
 - REPORT, 130, 265
 - REPORTS, 267
 - RFORCE, 266
- RUNGK4, 304
 - DIFEQN, 306, 307
 - INITL, 305, 306
- SMPL, 133, 263
- SOLVE, 65
- SPRNG, 264
 - STATIC, 267
 - TRAN, 132, 263
 - TRANSF, 129, 260
 - TRIG, 129, 262
- Subroutine, user-supplied, 70
- Superscript* prime, 79
- Suspension system, automobile, 3, 17
- Symbols, kinematic, 332
- Synthesis, 6
- T**
- Tangent, vector, 92
- Taylor series, 223
 - algorithms, 302
 - first-order, 303
 - second-order, 303
- Tilde operation, 25
- Time, initial, 40, 120
- Time, final, 40, 120
- Time increment (*or* step), 120, 280
- Time step selection, 277
- Topology, 333
- Torque, 212
- Transformation matrix (*see* Rotational transformation matrix)
- Truck, dump, 273
- V**
- Variable order/step algorithms, 311
- Vector:
 - algebraic representation, 19, 21
 - Cartesian components, 20
 - equal, 19
 - free, 214
 - geometric representation, 19
 - magnitude, 19
 - multiplication by a scalar, 19, 24
 - negative, 19
 - null, 19, 24
 - orthogonal, 20, 25, 29, 156
 - partial derivative, 29