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Nota di contenuto	Contents -- Foreword -- Introduction -- An enumerative theory of equilibrium rotations for planar kinematic chains -- Stability and stiffening of driven and free planar rotating beams -- Characterization of Hamiltonian input-output systems -- Robustness of distributed parameter systems -- On the relationship between discrete-time optimal control and recursive dynamics for elastic multibody chains -- Some solvable stochastic control problems in compact symmetric spaces of rank one -- Slew-induced deformation shaping on slow integral manifolds -- Feedback equivalence and symmetries of Brunowski normal forms -- The application of total energy as a Lyapunov function for mechanical control systems -- Classical adiabatic angles for slowly moving mechanical systems -- Eulerian many-body problems -- Morse theory for a model space structure -- A unified approach for the control of multifingered robot hands -- Tethered satellite system stability -- Quantum control theory I --

Cartan-Hannay-Berry phases and symmetry -- Block diagonalization and the energy-momentum method -- The dynamics of two coupled rigid bodies in three space -- Nonsmooth optimization algorithms for the design of controlled flexible structures -- Stability analysis of a rigid body with attached geometrically nonlinear rod by the energy-momentum method -- Controllability of Poisson control systems with symmetries -- Chaos in a rapidly forced pendulum equation -- Accurate time critical control of many body systems -- Hamiltonian control systems: decomposition and clamped dynamics -- Graph-theoretical methods in multibody dynamics.