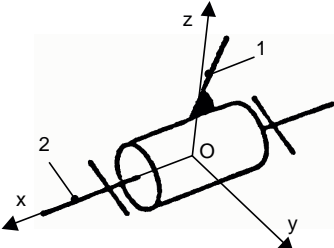
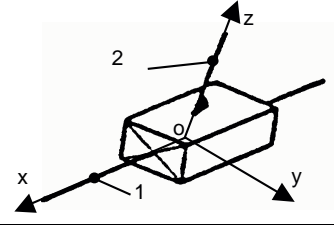
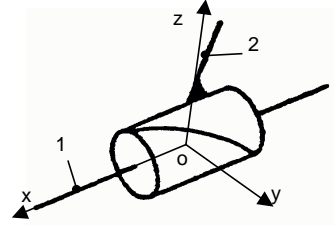
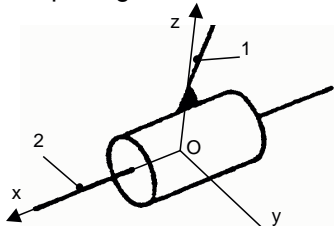
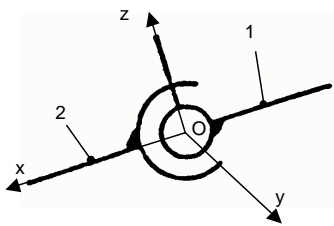
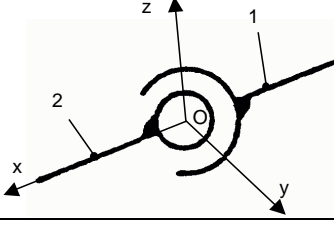
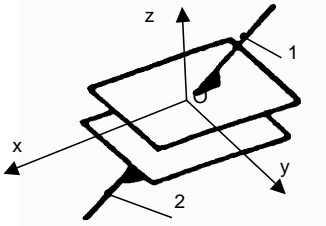
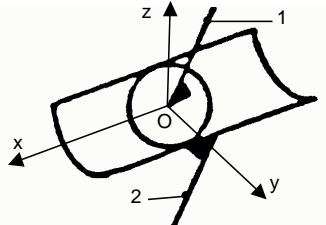
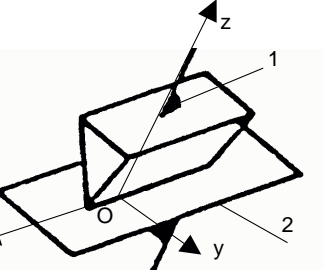
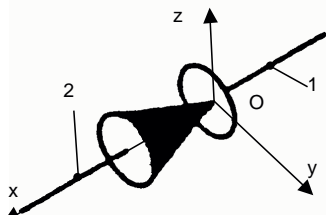


Annexe 1 : Torseurs d'action mécanique transmissible par les liaisons normalisées sans frottement.

Nom de la liaison	Torseur cinématique	Torseur d'action mécanique transmissible
Liaison pivot 	$\left\{ V_{2/1} \right\}_O = \begin{Bmatrix} \Omega_x & 0 \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}_R$	$\left\{ F_{1 \rightarrow 2} \right\}_O = \begin{Bmatrix} X_{1 \rightarrow 2} & 0 \\ Y_{1 \rightarrow 2} & M_{1 \rightarrow 2} \\ Z_{1 \rightarrow 2} & N_{1 \rightarrow 2} \end{Bmatrix}_R$
Liaison glissière 	$\left\{ V_{2/1} \right\}_O = \begin{Bmatrix} 0 & V_x \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}_R$	$\left\{ F_{1 \rightarrow 2} \right\}_O = \begin{Bmatrix} 0 & L_{1 \rightarrow 2} \\ Y_{1 \rightarrow 2} & M_{1 \rightarrow 2} \\ Z_{1 \rightarrow 2} & N_{1 \rightarrow 2} \end{Bmatrix}_R$
Liaison hélicoïdale 	$\left\{ V_{2/1} \right\}_O = \begin{Bmatrix} \Omega_x & V_x \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}_R$ avec $\Omega_x = \frac{2\pi}{p} \cdot V_x$	$\left\{ F_{1 \rightarrow 2} \right\}_O = \begin{Bmatrix} X_{1 \rightarrow 2} & L_{1 \rightarrow 2} \\ Y_{1 \rightarrow 2} & M_{1 \rightarrow 2} \\ Z_{1 \rightarrow 2} & N_{1 \rightarrow 2} \end{Bmatrix}_R$ avec $X_{1 \rightarrow 2} = -\frac{2\pi}{p} \cdot L_{1 \rightarrow 2}$
Liaison pivot glissant 	$\left\{ V_{2/1} \right\}_O = \begin{Bmatrix} \Omega_x & V_x \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}_R$	$\left\{ F_{1 \rightarrow 2} \right\}_O = \begin{Bmatrix} 0 & 0 \\ Y_{1 \rightarrow 2} & M_{1 \rightarrow 2} \\ Z_{1 \rightarrow 2} & N_{1 \rightarrow 2} \end{Bmatrix}_R$
Liaison sphérique à doigts 	$\left\{ V_{2/1} \right\}_O = \begin{Bmatrix} 0 & 0 \\ \Omega_y & 0 \\ \Omega_z & 0 \end{Bmatrix}_R$	$\left\{ F_{1 \rightarrow 2} \right\}_O = \begin{Bmatrix} X_{1 \rightarrow 2} & L_{1 \rightarrow 2} \\ Y_{1 \rightarrow 2} & 0 \\ Z_{1 \rightarrow 2} & 0 \end{Bmatrix}_R$
Liaison rotule 	$\left\{ V_{2/1} \right\}_O = \begin{Bmatrix} \Omega_x & 0 \\ \Omega_y & 0 \\ \Omega_z & 0 \end{Bmatrix}_R$	$\left\{ F_{1 \rightarrow 2} \right\}_O = \begin{Bmatrix} X_{1 \rightarrow 2} & 0 \\ Y_{1 \rightarrow 2} & 0 \\ Z_{1 \rightarrow 2} & 0 \end{Bmatrix}_R$

<p>Liaison appui plan</p> 	$\{V_{2/1}\} = \begin{Bmatrix} 0 & V_x \\ 0 & V_y \\ \Omega_z & 0 \end{Bmatrix}_R$	$\{F_{1 \rightarrow 2}\} = \begin{Bmatrix} 0 & L_{1 \rightarrow 2} \\ 0 & M_{1 \rightarrow 2} \\ Z_{1 \rightarrow 2} & 0 \end{Bmatrix}_R$
<p>Liaison linéaire annulaire</p> 	$\{V_{2/1}\} = \begin{Bmatrix} \Omega_x & V_x \\ \Omega_y & 0 \\ \Omega_z & 0 \end{Bmatrix}_R$	$\{F_{1 \rightarrow 2}\} = \begin{Bmatrix} 0 & 0 \\ Y_{1 \rightarrow 2} & 0 \\ Z_{1 \rightarrow 2} & 0 \end{Bmatrix}_R$
<p>Liaison linéaire rectiligne</p> 	$\{V_{2/1}\} = \begin{Bmatrix} \Omega_x & V_x \\ 0 & V_y \\ \Omega_z & 0 \end{Bmatrix}_R$	$\{F_{1 \rightarrow 2}\} = \begin{Bmatrix} 0 & 0 \\ 0 & M_{1 \rightarrow 2} \\ Z_{1 \rightarrow 2} & 0 \end{Bmatrix}_R$
<p>Liaison ponctuelle</p> 	$\{V_{2/1}\} = \begin{Bmatrix} \Omega_x & 0 \\ \Omega_y & V_y \\ \Omega_z & V_z \end{Bmatrix}_R$	$\{F_{1 \rightarrow 2}\} = \begin{Bmatrix} X_{1 \rightarrow 2} & 0 \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}_R$