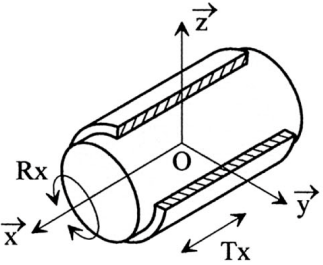
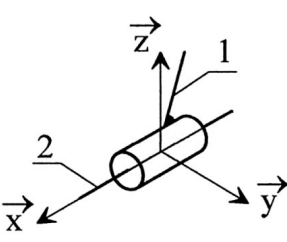
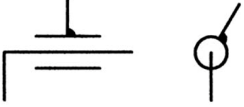
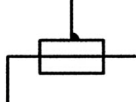
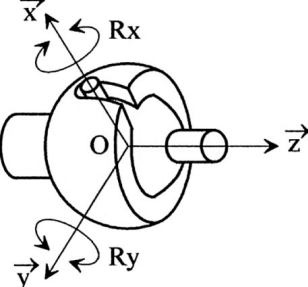
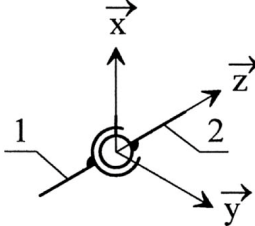

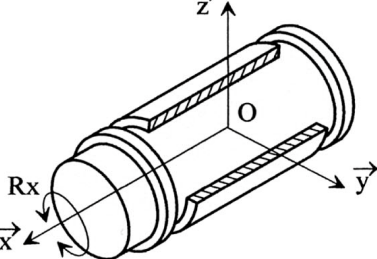
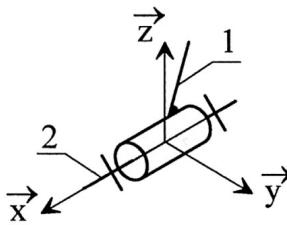
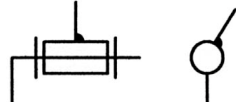
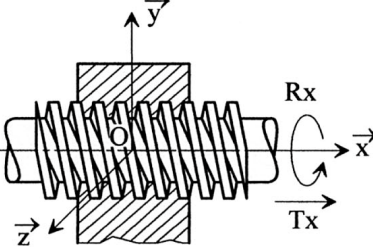
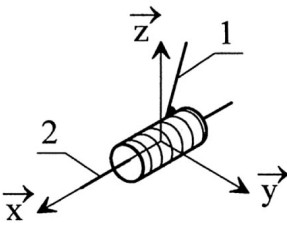
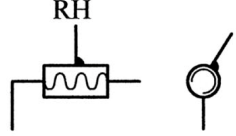
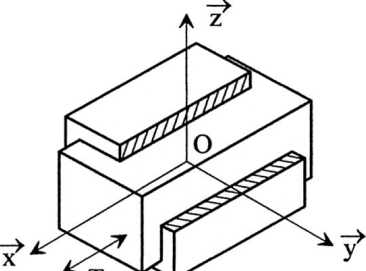
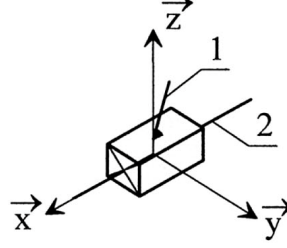
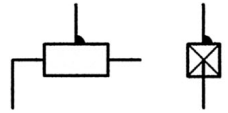


MODELISATION CINEMATIQUE ET GEOMETRIQUE DES LIAISONS

Désignation	Exemple	Représentation spatiale	Représentation plane
Liaison ponctuelle (sphère/plan) 5 degrés de liberté 2 translations T_x, T_y 3 rotations R_x, R_y, R_z			
Liaison linéaire-annulaire (sphère/cylindre) 4 degrés de liberté 1 translation T_x 3 rotations R_x, R_y, R_z			
Liaison rectiligne (cylindre/plan) 4 degrés de liberté 2 translations T_x, T_y 2 rotations R_x, R_z			
Liaison rotule ou sphérique (sphère/sphère) 3 degrés de liberté 0 translation 3 rotations R_x, R_y, R_z			
Liaison appui-plan (plan/plan) 3 degrés de liberté 2 translations T_x, T_y 1 rotation R_z			

<p>Liaison pivot-glissant (cylindre/cylindre)</p> <p>2 degrés de liberté 1 translation T_x 1 rotation R_x</p>			 <p>Symbole admissible</p> 
<p>Liaison sphérique à doigt</p> <p>2 degrés de liberté 0 translation 2 rotations R_x, R_y</p>			
<p>Liaison pivot</p> <p>1 degré de liberté 0 translation 1 rotation R_x</p>			
<p>Liaison hélicoïdale</p> <p>1 degré de liberté translation et rotation conjuguées $T_x = p/2\pi \cdot R_x$ p : pas de l'hélice</p>			 <p>RH : hélice à droite LH : hélice à gauche</p>
<p>Liaison glissière</p> <p>1 degré de liberté 1 translation T_x 0 rotation</p>			
<p>Liaison encastrement ou Liaison fixe</p> <p>0 degré de liberté 0 translation 0 rotation</p>	