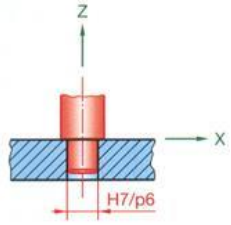
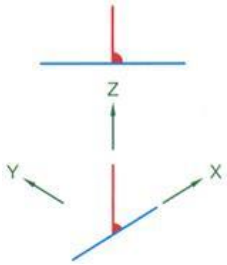
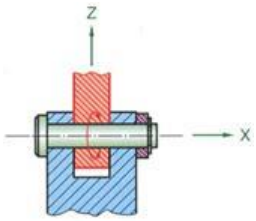
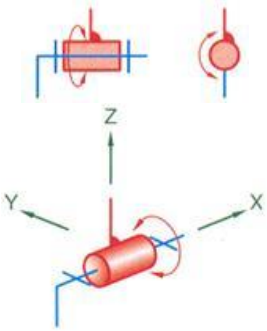
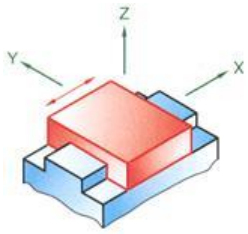
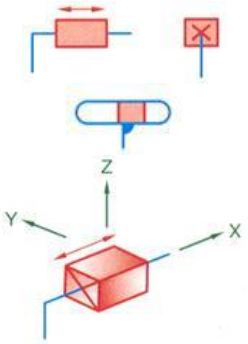
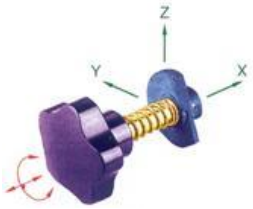
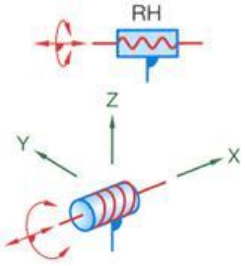
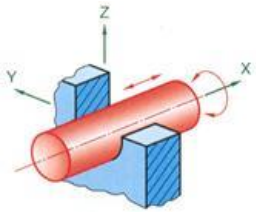
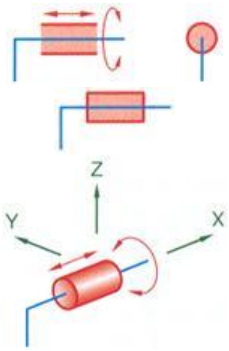
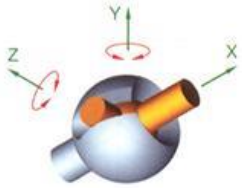
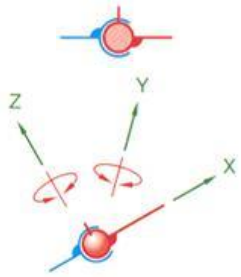
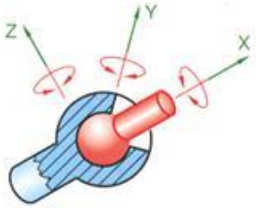
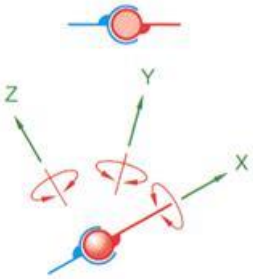
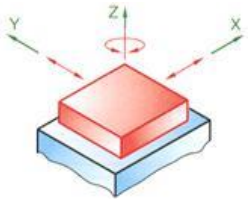
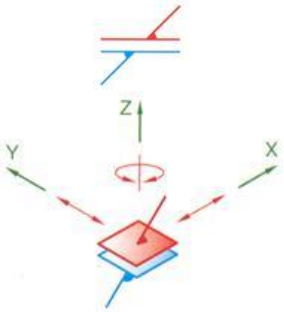
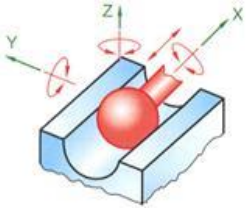
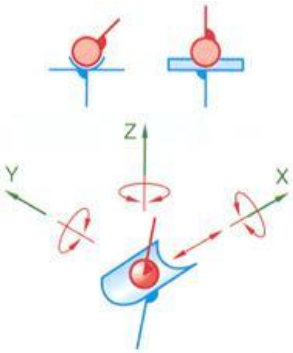
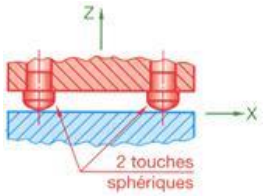
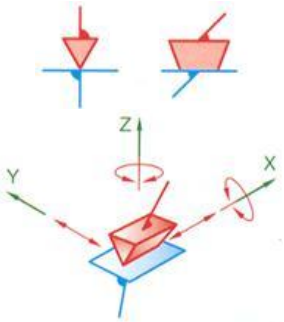
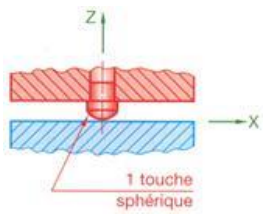
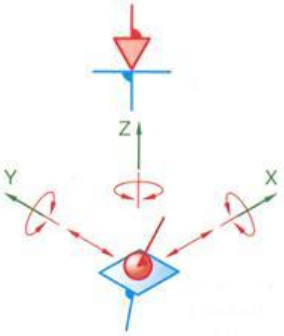
Degré de liberté	**Désignation** **Exemple de réalisation** ou **de géométrie de contact**	**Schématisation** Projection orthogonale (2 normes parfois) Perspective	**Caractéristiques géométriques**	**Forme du Torseur cinématique** exprimé en P dans R $(O;\vec{x},\vec{y},\vec{z})$	**Forme du Torseur d'actions mécaniques** exprimé en P dans R $(O;\vec{x},\vec{y},\vec{z})$	**Formes valables**
0	Encastrement ou Fixe 		aucune	$\begin{Bmatrix} 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}$	$\begin{Bmatrix} X & L \\ Y & M \\ Z & N \end{Bmatrix}$	$\forall P$
1	Pivot 		Axe $(O,\vec{x})$	$\begin{Bmatrix} \omega_x & 0 \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}$	$\begin{Bmatrix} X & 0 \\ Y & M \\ Z & N \end{Bmatrix}$	$\forall P \in (O,\vec{x})$
1	Glissière 		Direction $\vec{x}$	$\begin{Bmatrix} 0 & V_x \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}$	$\begin{Bmatrix} 0 & L \\ Y & M \\ Z & N \end{Bmatrix}$	$\forall P$
1	Hélicoïdale 		Axe $(O,\vec{x})$	$\begin{Bmatrix} \omega_x & V_x \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}$ Avec : $V_x = \frac{p}{2\pi}\omega_x$ *p : pas en mm/tr*	$\begin{Bmatrix} X & L \\ Y & M \\ Z & N \end{Bmatrix}$ Avec : $L = -\frac{p}{2\pi}X$ *p : pas en mm/tr*	$\forall P \in (O,\vec{x})$
2	Pivot glissant 		Axe $(O,\vec{x})$	$\begin{Bmatrix} \omega_x & V_x \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}$	$\begin{Bmatrix} 0 & 0 \\ Y & M \\ Z & N \end{Bmatrix}$	$\forall P \in (O,\vec{x})$

2	Sphérique à doigt 		Centre O Plan de la rainure	$\begin{Bmatrix} 0 & 0 \\ \omega_y & 0 \\ \omega_z & 0 \end{Bmatrix}$	$\begin{Bmatrix} X & L \\ Y & 0 \\ Z & 0 \end{Bmatrix}$	en O
3	Rotule ou Sphérique 		Centre O	$\begin{Bmatrix} \omega_x & 0 \\ \omega_y & 0 \\ \omega_z & 0 \end{Bmatrix}$	$\begin{Bmatrix} X & 0 \\ Y & 0 \\ Z & 0 \end{Bmatrix}$	en O
3	Appui plan 		Normale $\vec{z}$	$\begin{Bmatrix} 0 & V_x \\ 0 & V_y \\ \omega_z & 0 \end{Bmatrix}$	$\begin{Bmatrix} 0 & L \\ 0 & M \\ Z & 0 \end{Bmatrix}$	$\forall P$
4	Sphère-cylindre ou Linéaire annulaire 		Axe $\left(O,\vec{x}\right)$	$\begin{Bmatrix} \omega_x & V_x \\ \omega_y & 0 \\ \omega_z & 0 \end{Bmatrix}$	$\begin{Bmatrix} 0 & 0 \\ Y & 0 \\ Z & 0 \end{Bmatrix}$	en O
4	Cylindre-plan ou Linéaire rectiligne 		Droite $\left(O,\vec{x}\right)$ Normale $\vec{z}$	$\begin{Bmatrix} \omega_x & V_x \\ 0 & V_y \\ \omega_z & 0 \end{Bmatrix}$	$\begin{Bmatrix} 0 & 0 \\ 0 & M \\ Z & 0 \end{Bmatrix}$	$\forall P \in \left(O,\vec{x},\vec{z}\right)$
5	Sphère-plan ou Ponctuelle 		Point O Normale $\vec{z}$	$\begin{Bmatrix} \omega_x & V_x \\ \omega_y & V_y \\ \omega_z & 0 \end{Bmatrix}$	$\begin{Bmatrix} 0 & 0 \\ 0 & 0 \\ Z & 0 \end{Bmatrix}$	$\forall P \in \left(O,\vec{z}\right)$