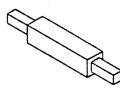
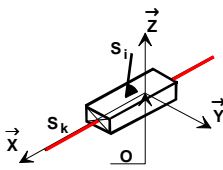
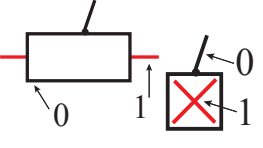
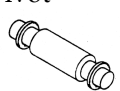
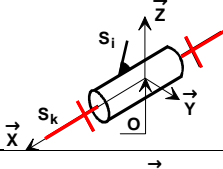
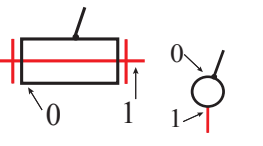
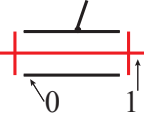
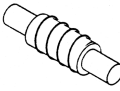
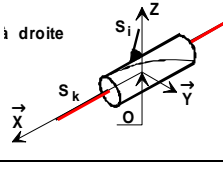
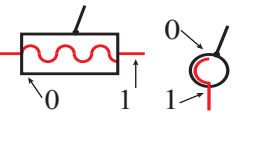
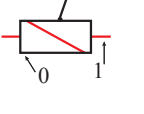
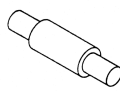
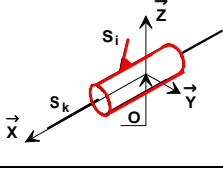
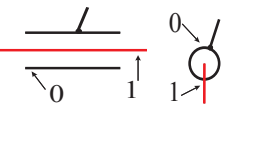
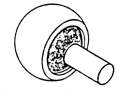
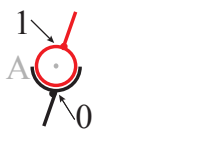
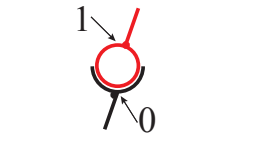
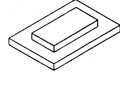
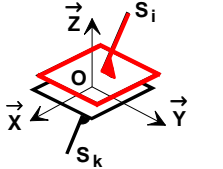
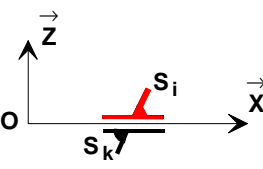
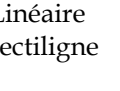
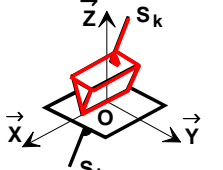
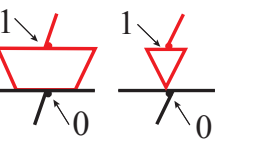
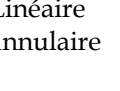
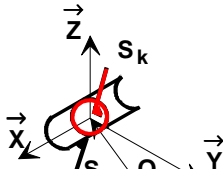
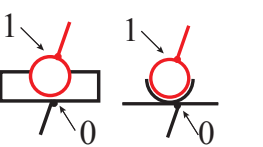
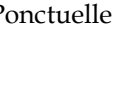
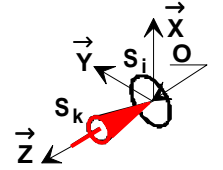
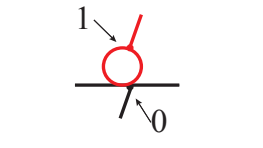
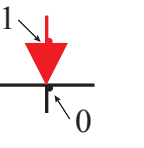
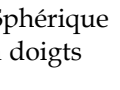
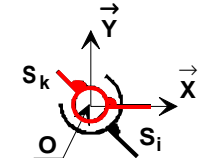


Tableau des liaisons normalisées

Nom de la liaison croquis	Degrés de liberté	Schéma spatial	Schémas plans	Autres symboles	Carac. Géom.	torseur cinématique $\left\{ \mathcal{V}_{(S_k/S_i)} \right\}$
 Glissière	1 translation				Direction	$\begin{Bmatrix} \vec{0} \\ V_x \vec{x} \end{Bmatrix}_o$
 Pivot	1 Rotation				Axe des cylindres	$\begin{Bmatrix} \omega_x \vec{x} \\ \vec{0} \end{Bmatrix}_o$
 Hélicoïdale	1 rotation 1 translation conjuguées	<i>à droite</i> 			Axes des hélices	$\begin{Bmatrix} \omega_x \vec{x} \\ V_x \vec{x} \end{Bmatrix}_o$
 Pivot glissant	1 rotation 1 translation				Axe des cylindres	$\begin{Bmatrix} \omega_x \vec{x} \\ V_x \vec{x} \end{Bmatrix}_o$
 Rotule	3 rotations				Centre de la sphère	$\begin{Bmatrix} \omega_x \vec{x} + \omega_y \vec{y} + \omega_z \vec{z} \\ \vec{0} \end{Bmatrix}_o$
 Appui plan	1 rotation 2 translations				Normale au contact	$\begin{Bmatrix} \omega_z \vec{z} \\ V_x \vec{x} + V_y \vec{y} \end{Bmatrix}_o$
 Linéaire rectiligne	2 rotations 2 translations				Ligne de contact Normale au contact	$\begin{Bmatrix} \omega_x \vec{x} + \omega_z \vec{z} \\ V_x \vec{x} + V_y \vec{y} \end{Bmatrix}_o$
 Linéaire annulaire	3 rotations 1 translation				Centre de la sphère Direction du cylindre	$\begin{Bmatrix} \omega_x \vec{x} + \omega_y \vec{y} + \omega_z \vec{z} \\ V_x \vec{x} \end{Bmatrix}_o$
 Ponctuelle	3 rotations 2 translations				Point de contact Normale au contact	$\begin{Bmatrix} \omega_x \vec{x} + \omega_y \vec{y} + \omega_z \vec{z} \\ V_x \vec{x} + V_y \vec{y} \end{Bmatrix}_o$
 Sphérique à doigts	2 rotations				Centre de la sphère Direction du doigt	$\begin{Bmatrix} \omega_x \vec{x} + \omega_z \vec{z} \\ \vec{0} \end{Bmatrix}_o$