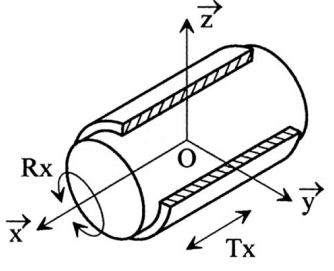
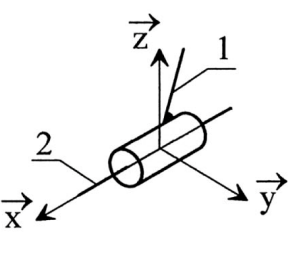
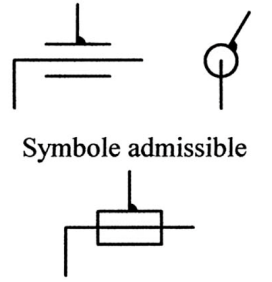
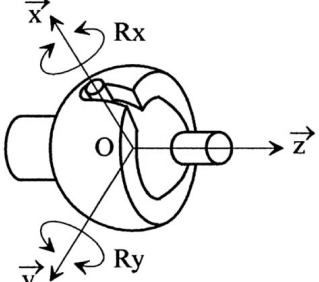
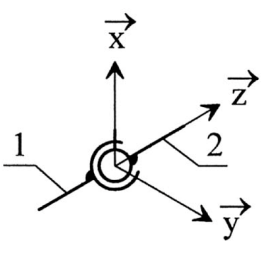

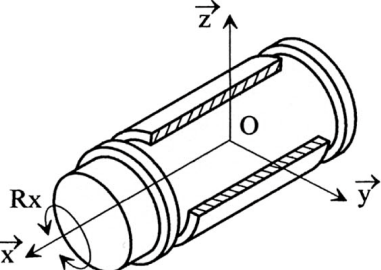
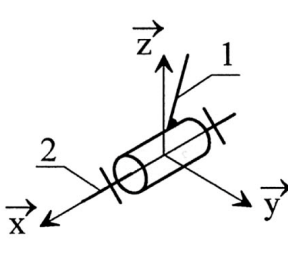
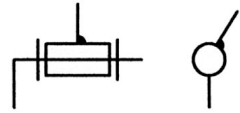
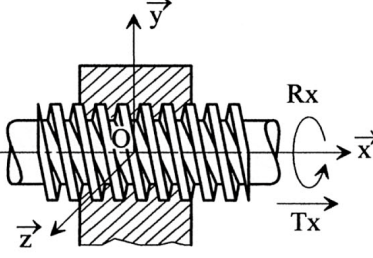
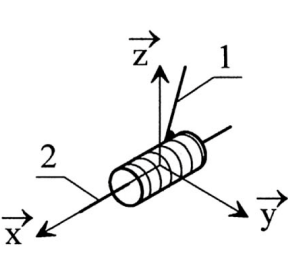
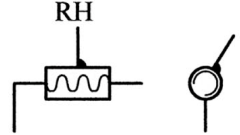
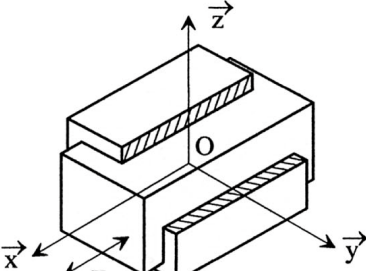
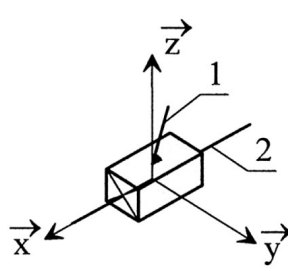
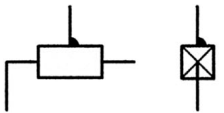


# MODELISATION CINEMATIQUE ET GEOMETRIQUE DES LIAISONS

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

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