Triedro de Frenet.

**AVISO 1:Para hacer correctamente la implementación de matlab debereís copiar  
y pegar en la ventana de Command Window todas las partes de este programa  
las cuales estan separadas por avisos como este. (No copiar todo a la vez)**

**AVISO 2:La función implicitplot3d no está definida en Matlab, por lo que antes de empezar a copiar el programa debemos introducir dicha función (la cual os facilito al final de esta página).**

**AVISO 3:Esto es solo un ejemplo cualquiera, si queremos introducir otra función deberemos definirla en el primero de los apartados que hay a continuación.**

**Vectores que debemos definir.**

syms t  
modulo = @(v) simplify ( sqrt ( v \* transpose(v) ) )  
unitario = @(v) v / modulo (v)  
dibuja\_vector = @(v,r,color) plot3 ( [r(1), r(1)+v(1)], [r(2), r(2)+v(2)], [r(3), r(3)+v(3)], color)  
xt = 2 \* cos (t), yt = sin (t), zt = 0, tmin = 0, tmax = 2\*pi, tp = ( tmin + tmax ) / 4  
r = [ xt, yt, zt]  
pretty(r)  
rp = subs(r , {t}, {tp} ), xp = rp(1), yp = rp(2), zp =rp(3)

**Vectores velocidad y aceleración.**

ezplot3( xt, yt, zt, [tmin, tmax] ), hold on, scatter3( xp, yp, zp, 'filled' ), hold off  
axis equal, title( 'CURVA TRABAJO')

v = simplify( diff (r) ), pretty(v), modv = simplify( modulo (v) ), pretty(modv) %velocidad  
a = simplify( diff (v) ), pretty(a), moda = simplify( modulo (a) ), pretty(moda) %aceleración  
vp = subs(v , {t}, {tp} ), ap = subs(a , {t}, {tp} ) %velocidad y aceleración en el punto

ezplot3( xt, yt, zt, [tmin, tmax]), hold on,  
scatter3( xp, yp, zp, 'filled' ),  
dibuja\_vector( vp, rp, 'red')  
dibuja\_vector( ap, rp, 'black')  
hold off  
axis equal, title( 'VELOCIDAD Y ACELERACIÓN')

subplot(2,1,1), ezplot( modv, [tmin, tmax] ), xlabel ( ' Parámetro t '), ylabel( 'Velocidad' ), title('Módulo de la Velocidad')  
subplot(2,1,2), ezplot( moda, [tmin, tmax] ), xlabel( ' Parámetro t '), ylabel( 'Aceleración' ), title('Módulo de la Aceleración')

**Longitud del arco de curva.**

L\_t = simplify( int ( modv, t ) )  
L = simplify( int (modv, t, tmin, tmax) )  
double(L)

**Triedro de Frénet.**

T = simplify( unitario(v) ) %Vector Tangente.  
pretty (T)  
N = simplify( unitario( diff (T) ) ) %Vector Normal Principal.  
pretty(N)  
B = simplify( cross(T,N) ) %Vector Binormal.  
pretty(B)

**Triedro de Frénet en el punto.**

Tp = subs(T , {t}, {tp} ), Np = subs(N , {t}, {tp} ), Bp = subs(B , {t}, {tp} )

**Dibujo del Triedro de Frénet en el punto.**

ezplot3( xt, yt, zt, [tmin, tmax]), hold on,  
scatter3( xp, yp, zp, 'filled' ),  
dibuja\_vector( Tp, rp, 'red')  
dibuja\_vector( Np, rp, 'black')  
dibuja\_vector( Bp, rp, 'magenta')  
hold off  
axis equal, title( 'Triedro de Frénet')

**Planos del Triedro de Frénet.**

syms x y z  
X = [ x, y, z]

**Plano Normal.**

Plano\_N = simplify( (X - r) \* transpose(T) )  
pretty(Plano\_N)

**Plano Normal en el punto.**

Plano\_N\_p = vpa(subs(Plano\_N , {t}, {tp} ), 3 )

**Dibujo del Plano Normal.**

ezplot3( xt, yt, zt, [tmin, tmax]), hold on  
scatter3( xp, yp, zp, 'filled' )  
dibuja\_vector( Tp, rp, 'red')  
hold off  
implicitplot3d( Plano\_N\_p, 0, xp-1, xp+1, yp-1, yp+1, zp-1, zp+1, 40,'blue')  
axis equal, title( 'Plano Normal y Tangente')

**Plano Rectificante.**

Plano\_R = simplify( (X - r) \* transpose(N) )  
pretty(Plano\_R)

**Plano Rectificante en el punto.**

Plano\_R\_p = vpa(subs(Plano\_R , {t}, {tp} ), 3 )

**Dibujo del Plano Rectificante.**

ezplot3( xt, yt, zt, [tmin, tmax]), hold on  
scatter3( xp, yp, zp, 'filled' )  
dibuja\_vector( Np, rp, 'red')  
hold off  
implicitplot3d( Plano\_R\_p, 0, xp-1, xp+1, yp-1, yp+1, zp-1, zp+1, 40,'blue')  
axis equal, title( 'Plano Rectificante y Normal Principal')

**Plano Osculador.**

Plano\_O = simplify( (X - r) \* transpose(B) )  
pretty(Plano\_O)

**Plano Osculador en el punto.**

Plano\_O\_p = vpa(subs(Plano\_O , {t}, {tp} ), 3 )

**Dibujo del Plano Osculador.**

ezplot3( xt, yt, zt, [tmin, tmax]), hold on  
scatter3( xp, yp, zp, 'filled' )  
dibuja\_vector( Bp, rp, 'red')  
hold off  
implicitplot3d( Plano\_O\_p, 0, xp-1, xp+1, yp-1, yp+1, zp-1, zp+1, 40,'blue')  
axis equal, title( 'Plano Osculador y Binormal')

**Curvatura.**

kappa = simplify( modulo( diff (T) ) / modv )  
pretty(kappa)

**Torsión.**

tau = simplify( - diff (B) \* transpose(N) / modv )  
pretty(tau)

**Dibujo de ambas.**

subplot(2,1,1), ezplot( kappa, [tmin, tmax] ), xlabel( ' Parámetro t '), ylabel( 'Curvatura' ), title('CURVATURA')  
subplot(2,1,2), ezplot( tau, [tmin, tmax] ), xlabel( ' Parámetro t '), ylabel( 'Torsión' ), title('TORSIÓN')

**Aceleración Tangencial.**

aT = simplify( diff (modv) ), pretty(aT)

**Aceleración Normal.**

aN = simplify( kappa \* modv^2), pretty(aN)

**Dibujo de ambas y su módulo.**

subplot(3,1,1), ezplot( aT, [tmin, tmax] ), xlabel ( ' Parámetro t '), ylabel ( 'Tangencial' ), title ('ACELERACIONES')  
subplot(3,1,2), ezplot( aN, [tmin, tmax] ), xlabel ( ' Parámetro t '), ylabel ( 'Normal' ), title (' ')  
subplot(3,1,3), ezplot( moda, [tmin, tmax] ), xlabel ( ' Parámetro t '), ylabel ( 'Módulo' ), title (' ')

Función implicitplot3d.

*Esta implementación de matlab se usa para dibujar los planos normal,  
rectificante y osculador.*

function out=implicitplot3d(varargin)  
%IMPLICITPLOT3D 3-D implicit plot  
% IMPLICITPLOT3D(eq, val, xvar, yvar, zvar, xmin, xmax,  
% ymin, ymax, zmin, zmax) plots an implicit equation  
% eq=val, where eq is either symbolic expression of (symbolic)  
% variables xvar, yvar, and zvar in the indicated ranges, or  
% a string representing such an expression, and val is a number.  
% If xvar, yvar, and zvar are not specified, it is assumed they are  
% x, y, z in the symbolic case, or 'x', 'y',and 'z' in the  
% string form of the command, respectively.  
% The optional parameter plotpoints (added at the end)  
% gives the number of steps in each direction between plotting points.  
%  
% Example: implicitplot3d('x^2+y^2+z^2', 5, -3, 3, -3, 3, -3, 3)  
% plots the sphere 'x^2+y^2+z^2=5' with 'x', 'y', and 'z'  
% going from -3 to 3.  
% implicitplot3d('x^2+y^2+z^2', 5, -3, 3, -3, 3, -3, 3, 30)  
% does the same with higher accuracy.  
% implicitplot3d('x^2+y^2+z^2', 5, -3, 3, -3, 3, -3, 3, 30, 'color')  
% does the same with a given color.  
% written by Jonathan Rosenberg, 7/30/99  
% rewritten for MATLAB 7, 8/22/05  
% modified by Santiago de Vicente, 3/20/12

if nargin<8  
error('not enough input arguments — need at least expression string, value, xmin, xmax, ymin, ymax, zmin, zmax');  
end

if nargin==11, error('impossible number of input arguments'); end

if nargin>13, error('too many input arguments'); end

% Default value of plotpoints is 10.  
plotpoints=10; color='black';

eq=varargin{1}; val=varargin{2};  
stringflag=ischar(eq); % This is 'true' in the string case,  
% 'false' in the symbolic case.

% Next, handle subcase where variable names are missing.  
if nargin<11  
if stringflag % First we deal with the string case.  
xvar='x'; yvar='y'; zvar='z';  
else % Now deal with the case where eq is symbolic.  
syms x y z; xvar=x; yvar=y; zvar=z;  
end  
xmin=varargin{3}; xmax=varargin{4};  
ymin=varargin{5}; ymax=varargin{6};  
zmin=varargin{7}; zmax=varargin{8};  
if nargin==9, plotpoints=varargin{9}; end  
if nargin==10, plotpoints=varargin{9}; color=char(varargin(10)); end  
end  
% Next, handle subcase where variable names are included.  
if nargin>11  
xvar=varargin{3}; yvar=varargin{4}; zvar=varargin{5};  
xmin=varargin{6}; xmax=varargin{7};  
ymin=varargin{8}; ymax=varargin{9};  
zmin=varargin{10}; zmax=varargin{11};  
if nargin==12, plotpoints=varargin{12}; end  
if nargin==13, plotpoints=varargin{12}; color=char(varargin(10)); end  
end

if stringflag  
F = vectorize(inline(eq,xvar,yvar,zvar));  
else  
F = inline(vectorize(eq),char(xvar),char(yvar),char(zvar));  
end  
[X Y]= meshgrid(xmin:(xmax-xmin)/plotpoints:xmax, ymin:(ymax-ymin)/plotpoints:ymax);

% Go through zvalues one at a time. For each one, plot corresponding  
% contourplot in x and y, with that z-value. We could use "contour"  
% except that it makes a "shadow", so we copy some of  
% the code of "contour".

for z=zmin:(zmax-zmin)/plotpoints:zmax  
lims = [min(X(:)),max(X(:)), min(Y(:)),max(Y(:))];  
c = contours(X,Y,F(X,Y,z), [val val]);  
limit = size(c,2);  
i = 1;  
h = [];  
while(i < limit)  
npoints = c(2,i);  
nexti = i+npoints+1;  
xdata = c(1,i+1:i+npoints);  
ydata = c(2,i+1:i+npoints);  
zdata = z + 0\*xdata; % Make zdata the same size as xdata  
line('XData',xdata,'YData',ydata,'ZData',zdata,'Color',color); hold on;  
i = nexti;  
end  
end  
view(3)  
xlabel(char(xvar))  
ylabel(char(yvar))  
zlabel(char(zvar))  
title([char(eq),' = ',num2str(val)], 'Interpreter','none')  
hold off  
end

<http://matcalculus.wikidot.com/implementacion>