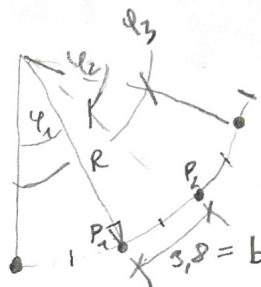
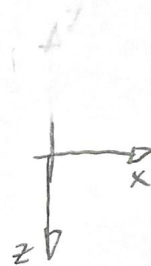
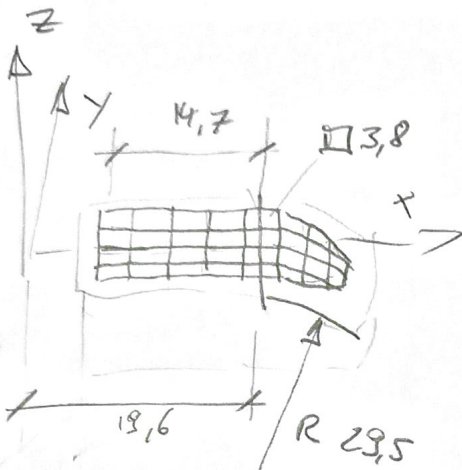


LOCAL CF



INSTITUTO DE SISTEMAS
E ROBÓTICA PÓLO DO IST

$$r \cdot \varphi = b$$



$$\varphi_1 = \frac{b}{R}, \quad \varphi_2 = \frac{2b}{R}, \quad l = 19.6$$

$$\varphi_3 = \frac{3b}{R}$$

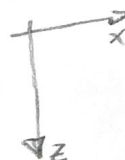
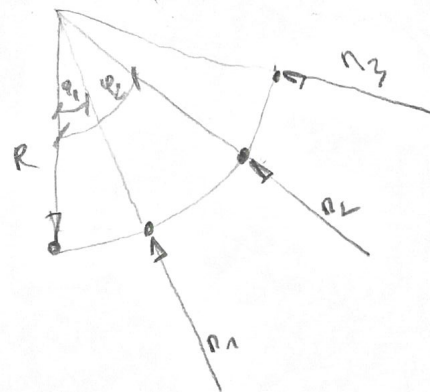
$$P_{1x} = l + R \cdot \sin(\varphi_1), \quad P_{2x} = R \sin(\varphi_2) + l$$

$$P_{3x} = R \sin(\varphi_3) + l$$

$$P_{1z} = -R + R \cos \varphi_1 = -R(1 - \cos \varphi_1)$$

$$P_{2z} = -R(1 - \cos \varphi_2)$$

$$P_{3z} = -R(1 - \cos \varphi_3)$$



$$n_{1x} = -\sin \varphi_1, \quad n_{1z} = -\cos \varphi_1$$

$$n_{2x} = -\sin \varphi_2, \quad n_{2z} = \cos \varphi_2$$

$$n_{3x} = \sin \varphi_3, \quad n_{3z} = \cos \varphi_3$$

1	2	3	4
5	6	7	8
9	10	11	12
13	14	15	16
17	18	19	20
21	22	23	24
25	26	27	28
29	30	31	32