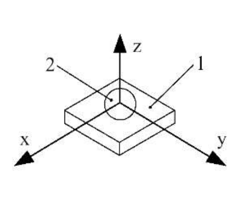
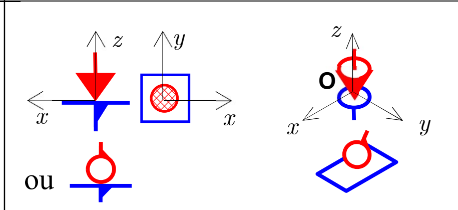
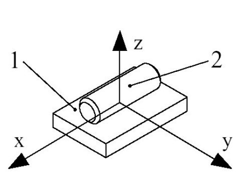
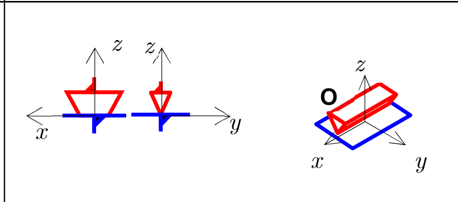
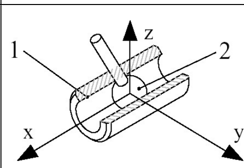
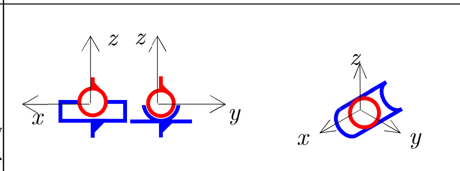
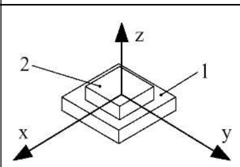
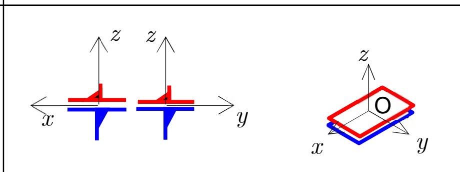
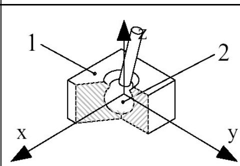
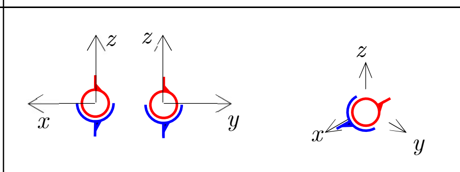
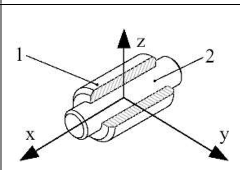
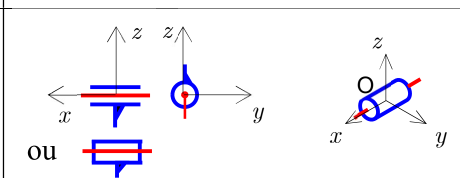
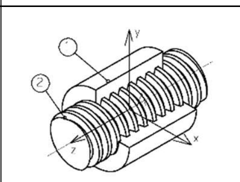
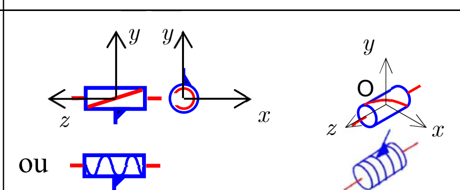
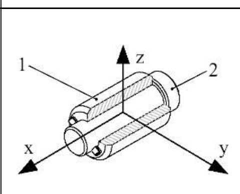
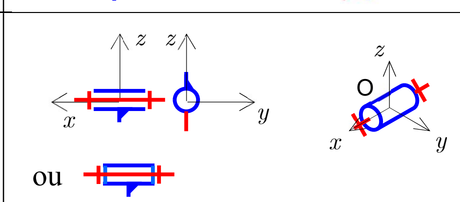
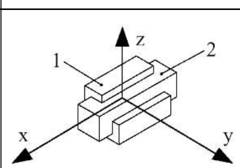
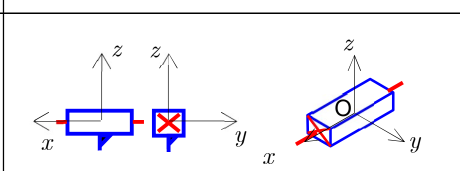
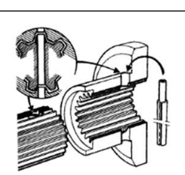
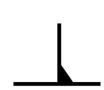
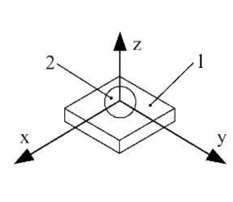
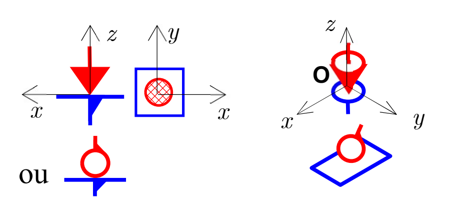
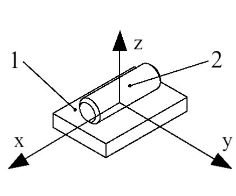
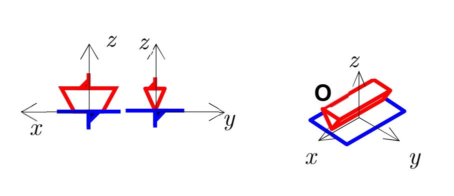
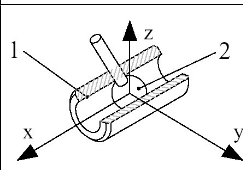
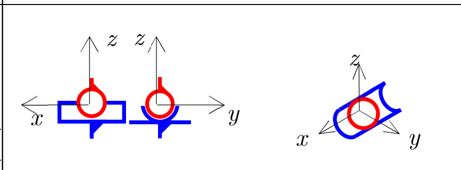
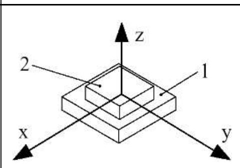
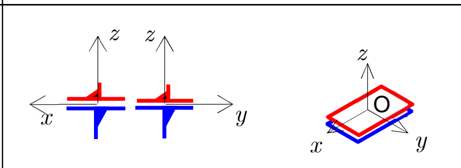
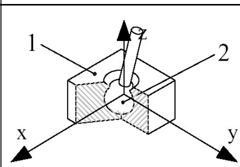
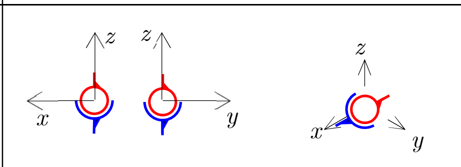
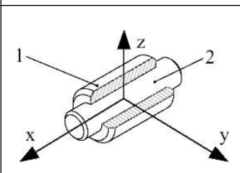
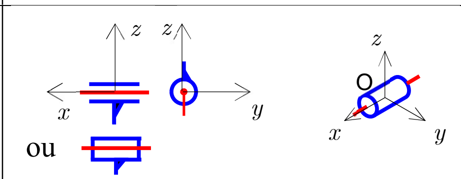
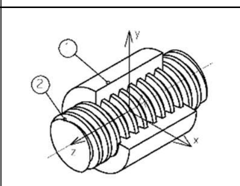
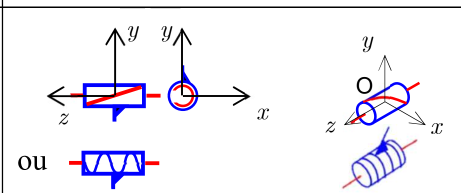
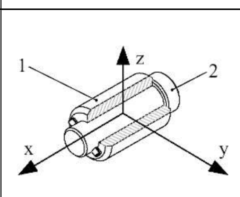
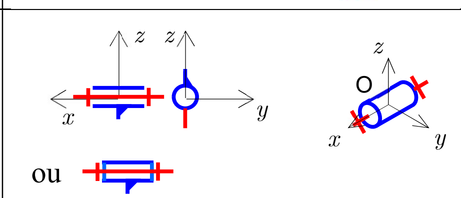
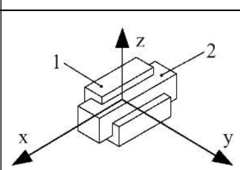
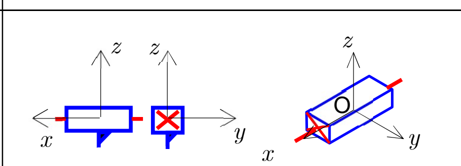
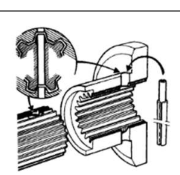
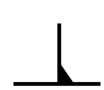
Nom de la liaison	Exemple	Schématisation normalisée	Torseur cinématique	Torseur des A.M transmissibles.
Ponctuelle de normale $(O,\vec{z})$			$\{\vartheta_{2\to1}\} = \begin{Bmatrix} \omega_x\vec{x} + \omega_y\vec{y} + \omega_z\vec{z} \\ V_x\vec{x} + V_y\vec{y} \end{Bmatrix}_O$	$\{\Im_{2\to1}\} = \begin{Bmatrix} Z\vec{z} \\ \vec{0} \end{Bmatrix}_O$
Linéaire rectiligne de normale $(O,\vec{z})$ **et d'axe** $(O,\vec{x})$			$\{\vartheta_{2\to1}\} = \begin{Bmatrix} \omega_x\vec{x} + \omega_z\vec{z} \\ V_x\vec{x} + V_y\vec{y} \end{Bmatrix}_O$	$\{\Im_{2\to1}\} = \begin{Bmatrix} Z\vec{z} \\ M\vec{y} \end{Bmatrix}_O$
Linéaire annulaire d'axe $(O,\vec{x})$			$\{\vartheta_{2\to1}\} = \begin{Bmatrix} \omega_x\vec{x} + \omega_y\vec{y} + \omega_z\vec{z} \\ V_x\vec{x} \end{Bmatrix}_O$	$\{\Im_{2\to1}\} = \begin{Bmatrix} Y\vec{y} + Z\vec{z} \\ \vec{0} \end{Bmatrix}_O$
Appui plan de normale $(O,\vec{z})$			$\{\vartheta_{2\to1}\} = \begin{Bmatrix} \omega_z\vec{z} \\ V_x\vec{x} + V_y\vec{y} \end{Bmatrix}_O$	$\{\Im_{2\to1}\} = \begin{Bmatrix} Z\vec{z} \\ L\vec{x} + M\vec{y} \end{Bmatrix}_O$
Rotule de centre O			$\{\vartheta_{2\to1}\} = \begin{Bmatrix} \omega_x\vec{x} + \omega_y\vec{y} + \omega_z\vec{z} \\ \vec{0} \end{Bmatrix}_O$	$\{\Im_{2\to1}\} = \begin{Bmatrix} X\vec{x} + Y\vec{y} + Z\vec{z} \\ \vec{0} \end{Bmatrix}_O$
Pivot glissant d'axe $(O,\vec{x})$			$\{\vartheta_{2\to1}\} = \begin{Bmatrix} \omega_x\vec{x} \\ V_x\vec{x} \end{Bmatrix}_O$	$\{\Im_{2\to1}\} = \begin{Bmatrix} Y\vec{y} + Z\vec{z} \\ M\vec{y} + N\vec{z} \end{Bmatrix}_O$
Hélicoïdale d'axe $(O,\vec{z})$			$\{\vartheta_{2\to1}\} = \begin{Bmatrix} \omega_z\vec{z} \\ V_z\vec{z} \end{Bmatrix}_O$ Avec $V_z = \frac{p}{2\pi}\omega_z$	$\{\Im_{2\to1}\} = \begin{Bmatrix} X\vec{x} + Y\vec{y} + Z\vec{z} \\ L\vec{x} + M\vec{y} + N\vec{z} \end{Bmatrix}_O$ Avec $N = \frac{p}{2\pi}Z$ (liaison parfaite)
Pivot d'axe $(O,\vec{x})$			$\{\vartheta_{2\to1}\} = \begin{Bmatrix} \omega_x\vec{x} \\ \vec{0} \end{Bmatrix}_O$	$\{\Im_{2\to1}\} = \begin{Bmatrix} X\vec{x} + Y\vec{y} + Z\vec{z} \\ M\vec{y} + N\vec{z} \end{Bmatrix}_O$
Glissière d'axe $(O,\vec{x})$			$\{\vartheta_{2\to1}\} = \begin{Bmatrix} \vec{0} \\ V_x\vec{x} \end{Bmatrix}_{\forall P}$	$\{\Im_{2\to1}\} = \begin{Bmatrix} Y\vec{y} + Z\vec{z} \\ L\vec{x} + M\vec{y} + N\vec{z} \end{Bmatrix}_O$
Encastrement			$\{\vartheta_{2\to1}\} = \begin{Bmatrix} \vec{0} \\ \vec{0} \end{Bmatrix}_{\forall P}$	$\{\Im_{2\to1}\} = \begin{Bmatrix} X\vec{x} + Y\vec{y} + Z\vec{z} \\ L\vec{x} + M\vec{y} + N\vec{z} \end{Bmatrix}_O$

Nom de la liaison	Exemple	Schématisation normalisée	Degrés de liberté	Torseur des A.M transmissibles.
Ponctuelle de normale $(O,\vec z)$			Tx Rx Ty Ry 0 Rz	$\left\{\mathfrak{F}_{2\to 1}\right\}=\left\{\begin{matrix} Z\vec z \\ \vec 0\end{matrix}\right\}_O$
Linéaire rectiligne de normale $(O,\vec z)$ **et d'axe** $(O,\vec x)$			Tx Rx Ty 0 0 Rz	$\left\{\mathfrak{F}_{2\to 1}\right\}=\left\{\begin{matrix} Z\vec z \\ M\vec y\end{matrix}\right\}_O$
Linéaire annulaire d'axe $(O,\vec x)$			Tx Rx 0 Ry 0 Rz	$\left\{\mathfrak{F}_{2\to 1}\right\}=\left\{\begin{matrix} Y\vec y + Z\vec z \\ \vec 0\end{matrix}\right\}_O$
Appui plan de normale $(O,\vec z)$			Tx 0 Ty 0 0 Rz	$\left\{\mathfrak{F}_{2\to 1}\right\}=\left\{\begin{matrix} Z\vec z \\ L\vec x + M\vec y\end{matrix}\right\}_O$
Rotule de centre O			0 Rx 0 Ry 0 Rz	$\left\{\mathfrak{F}_{2\to 1}\right\}=\left\{\begin{matrix} X\vec x + Y\vec y + Z\vec z \\ \vec 0\end{matrix}\right\}_O$
Pivot glissant d'axe $(O,\vec x)$			Tx Rx 0 0 0 0	$\left\{\mathfrak{F}_{2\to 1}\right\}=\left\{\begin{matrix} Y\vec y + Z\vec z \\ M\vec y + N\vec z\end{matrix}\right\}_O$
Hélicoïdale d'axe $(O,\vec z)$			0 0 0 0 Tz← →Rz	$\left\{\mathfrak{F}_{2\to 1}\right\}=\left\{\begin{matrix} X\vec x + Y\vec y + Z\vec z \\ L\vec x + M\vec y + N\vec z\end{matrix}\right\}_O$ Avec $N=\frac{p}{2\pi}Z$ (liaison parfaite)
Pivot d'axe $(O,\vec x)$			0 Rx 0 0 0 0	$\left\{\mathfrak{F}_{2\to 1}\right\}=\left\{\begin{matrix} X\vec x + Y\vec y + Z\vec z \\ M\vec y + N\vec z\end{matrix}\right\}_O$
Glissière d'axe $(O,\vec x)$			Tx 0 0 0 0 0	$\left\{\mathfrak{F}_{2\to 1}\right\}=\left\{\begin{matrix} Y\vec y + Z\vec z \\ L\vec x + M\vec y + N\vec z\end{matrix}\right\}_O$
Encastrement			0 0 0 0 0 0	$\left\{\mathfrak{F}_{2\to 1}\right\}=\left\{\begin{matrix} X\vec x + Y\vec y + Z\vec z \\ L\vec x + M\vec y + N\vec z\end{matrix}\right\}_O$