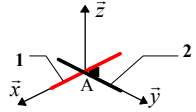
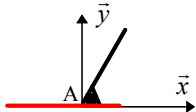
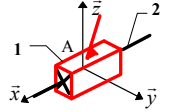
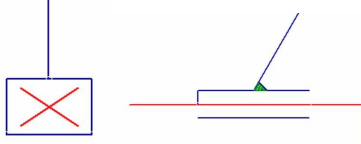
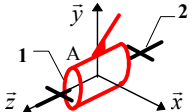
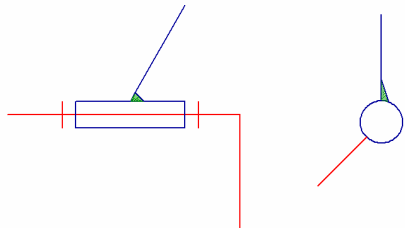
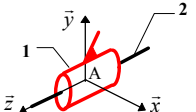
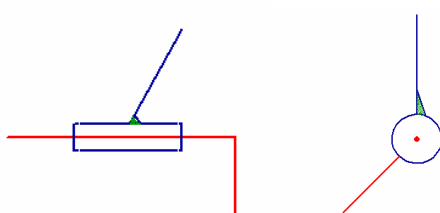
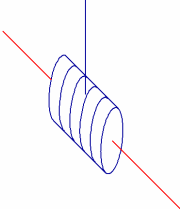
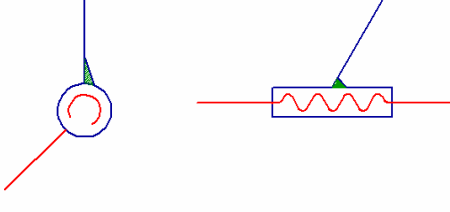
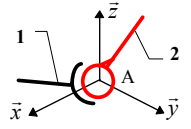
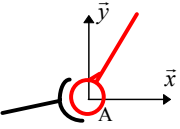
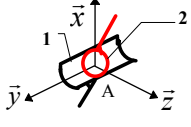
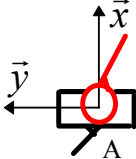
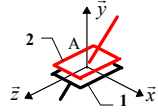
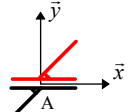
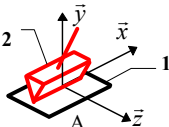
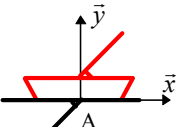
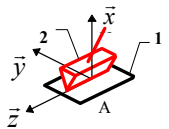
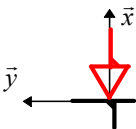
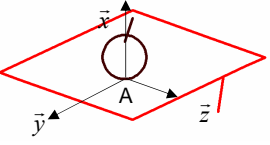
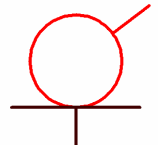


Nature de la liaison et position par rapport à son repère associé : R	Schématisation spatiale	Schématisation plane	Mouvements possibles	Torseur transmissible $\{\tau_{1/2}\}$ au point A
Encastrement R quelconque			$\begin{Bmatrix} 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}$	$A \begin{Bmatrix} X & L \\ Y & M \\ Z & N \end{Bmatrix}$
Glissière d'axe (A, \bar{x})			$\begin{Bmatrix} T_x & 0 \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}$	$A \begin{Bmatrix} 0 & L \\ Y & M \\ Z & N \end{Bmatrix}$
Pivot d'axe (A, \bar{z})			$\begin{Bmatrix} 0 & 0 \\ 0 & 0 \\ 0 & R_z \end{Bmatrix}$	$A \begin{Bmatrix} X & L \\ Y & M \\ Z & 0 \end{Bmatrix}$
Pivot glissant d'axe (A, \bar{z})			$\begin{Bmatrix} 0 & 0 \\ 0 & 0 \\ T_z & R_z \end{Bmatrix}$	$A \begin{Bmatrix} X & L \\ Y & M \\ 0 & 0 \end{Bmatrix}$
Hélicoïdale d'axe (A, \bar{x})			$\begin{Bmatrix} T_x & R_x \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}$ avec $T_x = \rho/2\pi R_x$	$A \begin{Bmatrix} X & L \\ Y & M \\ Z & N \end{Bmatrix}$ avec $L = \rho/2\pi \cdot X$

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<p>Rotule de centre A</p>			$\begin{Bmatrix} 0 & R_x \\ 0 & R_y \\ 0 & R_z \end{Bmatrix}$	$\begin{Bmatrix} X & 0 \\ Y & 0 \\ A & Z & 0 \end{Bmatrix}$
<p>Linéaire annulaire de centre A et d'axe (A, \vec{y}) (ou Sphère cylindre)</p>			$\begin{Bmatrix} 0 & R_x \\ T_y & R_y \\ 0 & R_z \end{Bmatrix}$	$\begin{Bmatrix} X & 0 \\ 0 & 0 \\ A & Z & 0 \end{Bmatrix}$
<p>Appui plan de normale (A, \vec{y})</p>			$\begin{Bmatrix} T_x & 0 \\ 0 & R_y \\ T_z & 0 \end{Bmatrix}$	$\begin{Bmatrix} 0 & L \\ Y & 0 \\ A & 0 & N \end{Bmatrix}$
<p>Linéaire rectiligne de normale (A, \vec{y}) et de droite de contact (A, \vec{x})</p>			$\begin{Bmatrix} T_x & R_x \\ 0 & R_y \\ T_z & 0 \end{Bmatrix}$	$\begin{Bmatrix} 0 & 0 \\ Y & 0 \\ A & 0 & N \end{Bmatrix}$
<p>Linéaire rectiligne de normale (A, \vec{x}) et de droite de contact (A, \vec{z})</p>			$\begin{Bmatrix} 0 & R_x \\ T_y & 0 \\ T_z & R_z \end{Bmatrix}$	$\begin{Bmatrix} X & 0 \\ 0 & M \\ A & 0 & 0 \end{Bmatrix}$
<p>Ponctuelle de normale (A, \vec{x}) (ou Sphère plan)</p>			$\begin{Bmatrix} 0 & R_x \\ T_y & R_y \\ T_z & R_z \end{Bmatrix}$	$\begin{Bmatrix} X & 0 \\ 0 & 0 \\ A & 0 & 0 \end{Bmatrix}$