LES LIAISONS USUELLES : BILAN

ddl	Nom de la liaison	Schématisation normalisée		Tableau des mobilités													
		Dans le plan	Dans l'espace														
0	Liaison encastrement ou liaison complète				<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>0</td> <td>0</td> </tr> <tr> <th>y</th> <td>0</td> <td>0</td> </tr> <tr> <th>z</th> <td>0</td> <td>0</td> </tr> </tbody> </table>		T	R	x	0	0	y	0	0	z	0	0
	T	R															
x	0	0															
y	0	0															
z	0	0															
1	Pivot d'axe ($A, \vec{x}$)				<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>0</td> <td>1</td> </tr> <tr> <th>y</th> <td>0</td> <td>0</td> </tr> <tr> <th>z</th> <td>0</td> <td>0</td> </tr> </tbody> </table>		T	R	x	0	1	y	0	0	z	0	0
	T	R															
x	0	1															
y	0	0															
z	0	0															
1	Glissière d'axe ($A, \vec{x}$)				<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>1</td> <td>0</td> </tr> <tr> <th>y</th> <td>0</td> <td>0</td> </tr> <tr> <th>z</th> <td>0</td> <td>0</td> </tr> </tbody> </table>		T	R	x	1	0	y	0	0	z	0	0
	T	R															
x	1	0															
y	0	0															
z	0	0															
1	Hélicoïdale d'axe ($A, \vec{x}$) <i>Rq : la translation et la rotation sont conjuguées</i>				<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>1</td> <td>1</td> </tr> <tr> <th>y</th> <td>0</td> <td>0</td> </tr> <tr> <th>z</th> <td>0</td> <td>0</td> </tr> </tbody> </table>		T	R	x	1	1	y	0	0	z	0	0
	T	R															
x	1	1															
y	0	0															
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2	Pivot glissant d'axe ($A, \vec{x}$)				<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>1</td> <td>1</td> </tr> <tr> <th>y</th> <td>0</td> <td>0</td> </tr> <tr> <th>z</th> <td>0</td> <td>0</td> </tr> </tbody> </table>		T	R	x	1	1	y	0	0	z	0	0
	T	R															
x	1	1															
y	0	0															
z	0	0															
2	Sphérique à doigt				<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>0</td> <td>0</td> </tr> <tr> <th>y</th> <td>0</td> <td>1</td> </tr> <tr> <th>z</th> <td>0</td> <td>1</td> </tr> </tbody> </table>		T	R	x	0	0	y	0	1	z	0	1
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ddl	Nom de la liaison	Schématisation normalisée		Tableau des mobilités												
		Dans le plan	Dans l'espace													
3	Rotule ou sphérique de centre A			<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>0</td> <td>1</td> </tr> <tr> <th>y</th> <td>0</td> <td>1</td> </tr> <tr> <th>z</th> <td>0</td> <td>1</td> </tr> </tbody> </table>		T	R	x	0	1	y	0	1	z	0	1
	T	R														
x	0	1														
y	0	1														
z	0	1														
3	Appui plan de normale $\vec{(A, x)}$			<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>0</td> <td>1</td> </tr> <tr> <th>y</th> <td>1</td> <td>0</td> </tr> <tr> <th>z</th> <td>1</td> <td>0</td> </tr> </tbody> </table>		T	R	x	0	1	y	1	0	z	1	0
	T	R														
x	0	1														
y	1	0														
z	1	0														
4	Linéaire rectiligne de normale $\vec{(A, x)}$ et de direction $\vec{y}$			<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>0</td> <td>1</td> </tr> <tr> <th>y</th> <td>1</td> <td>1</td> </tr> <tr> <th>z</th> <td>1</td> <td>0</td> </tr> </tbody> </table>		T	R	x	0	1	y	1	1	z	1	0
	T	R														
x	0	1														
y	1	1														
z	1	0														
4	Linéaire annulaire d'axe $\vec{(A, x)}$			<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>1</td> <td>1</td> </tr> <tr> <th>y</th> <td>0</td> <td>1</td> </tr> <tr> <th>z</th> <td>0</td> <td>1</td> </tr> </tbody> </table>		T	R	x	1	1	y	0	1	z	0	1
	T	R														
x	1	1														
y	0	1														
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5	Ponctuelle de normale $\vec{(A, x)}$			<table border="1"> <thead> <tr> <th></th> <th>T</th> <th>R</th> </tr> </thead> <tbody> <tr> <th>x</th> <td>0</td> <td>1</td> </tr> <tr> <th>y</th> <td>1</td> <td>1</td> </tr> <tr> <th>z</th> <td>1</td> <td>1</td> </tr> </tbody> </table>		T	R	x	0	1	y	1	1	z	1	1
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