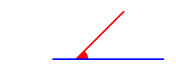
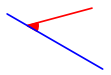
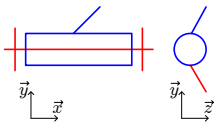
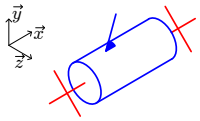
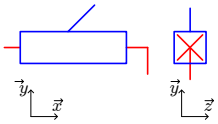
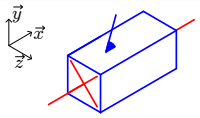
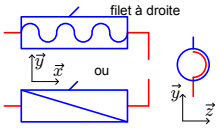
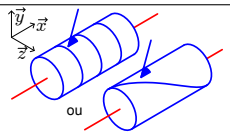
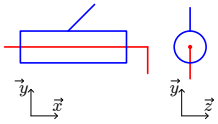
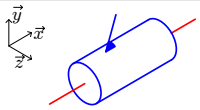
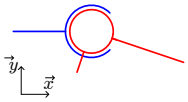
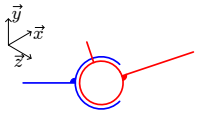
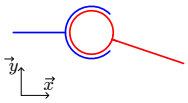
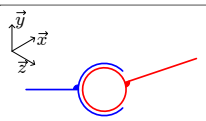
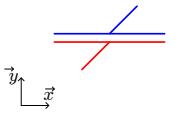
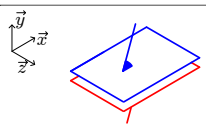
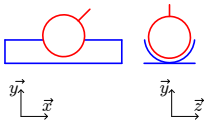
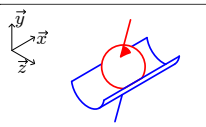
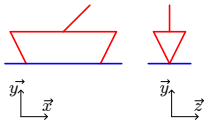
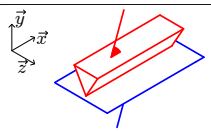
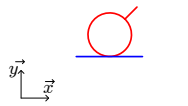
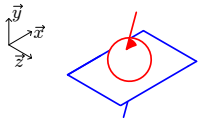
Nom	point d'application	ddl	Représentation plane	Représentation 3D	Torseur cinématique	Torseur des AM
Encastrement	tout point de l'espace	0			${}_A\begin{Bmatrix} 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} F_x & M_x \\ F_y & M_y \\ F_z & M_z \end{Bmatrix}_{\mathcal{R}}$
Pivot d'axe $(A, \overrightarrow{x})$	tout point de l'axe	1			${}_A\begin{Bmatrix} \omega_x & 0 \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} F_x & 0 \\ F_y & M_y \\ F_z & M_z \end{Bmatrix}_{\mathcal{R}}$
Glissière de direction $\overrightarrow{x}$	tout point de l'espace	1			${}_A\begin{Bmatrix} 0 & V_x \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} 0 & M_x \\ F_y & M_y \\ F_z & M_z \end{Bmatrix}_{\mathcal{R}}$
Hélicoïdale d'axe $(A, \overrightarrow{x})$	tout point de l'axe	1			${}_A\begin{Bmatrix} \omega_x & p.\omega_x \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} F_x & p.F_x \\ F_y & M_y \\ F_z & M_z \end{Bmatrix}_{\mathcal{R}}$
Pivot glissant d'axe $(A, \overrightarrow{x})$	tout point de l'axe	2			${}_A\begin{Bmatrix} \omega_x & V_x \\ 0 & 0 \\ 0 & 0 \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} 0 & 0 \\ F_y & M_y \\ F_z & M_z \end{Bmatrix}_{\mathcal{R}}$
Rotule à doigt de centre A bloquée en $\overrightarrow{x}$	centre de la liaison	2			${}_A\begin{Bmatrix} 0 & 0 \\ \omega_y & 0 \\ \omega_z & 0 \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} F_x & M_x \\ F_y & 0 \\ F_z & 0 \end{Bmatrix}_{\mathcal{R}}$
Rotule de centre A	centre de la liaison	3			${}_A\begin{Bmatrix} \omega_x & 0 \\ \omega_y & 0 \\ \omega_z & 0 \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} F_x & 0 \\ F_y & 0 \\ F_z & 0 \end{Bmatrix}_{\mathcal{R}}$
Appui plan de normale $\overrightarrow{y}$	tout point de l'espace	3			${}_A\begin{Bmatrix} 0 & V_x \\ \omega_y & 0 \\ 0 & V_z \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} 0 & M_x \\ F_y & 0 \\ 0 & M_z \end{Bmatrix}_{\mathcal{R}}$
Linéaire Annulaire d'axe $(A, \overrightarrow{x})$	au centre de la liaison	4			${}_A\begin{Bmatrix} \omega_x & V_x \\ \omega_y & 0 \\ \omega_z & 0 \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} 0 & 0 \\ F_y & 0 \\ F_z & 0 \end{Bmatrix}_{\mathcal{R}}$
Linéaire Rectiligne d'axe$(A, \overrightarrow{x})$ et de normale $\overrightarrow{y}$	tout point du plan $(A, \overrightarrow{x}, \overrightarrow{y})$	4			${}_A\begin{Bmatrix} \omega_x & V_x \\ \omega_y & 0 \\ 0 & V_z \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} 0 & 0 \\ F_y & 0 \\ 0 & M_z \end{Bmatrix}_{\mathcal{R}}$
Ponctuelle en A de normale $\overrightarrow{y}$	tout point de la normale au contact	5			${}_A\begin{Bmatrix} \omega_x & V_x \\ \omega_y & 0 \\ \omega_z & V_z \end{Bmatrix}_{\mathcal{R}}$	${}_A\begin{Bmatrix} 0 & 0 \\ F_y & 0 \\ 0 & 0 \end{Bmatrix}_{\mathcal{R}}$

Etapes pour dessiner le schéma cinématique (2D ou 3D) :

1. dessiner le repère absolu
2. placer les points et les axes des liaisons
3. dessiner les liaisons
4. relier les liaisons en respectant les axes du repère