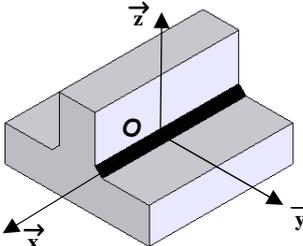
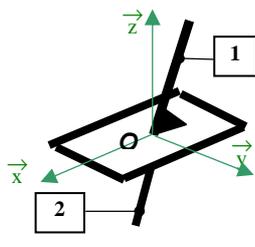
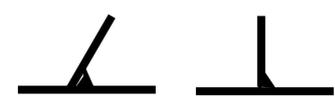
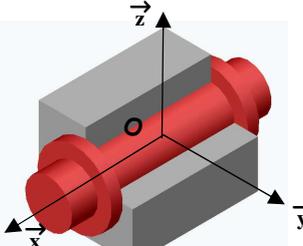
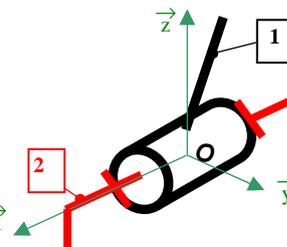
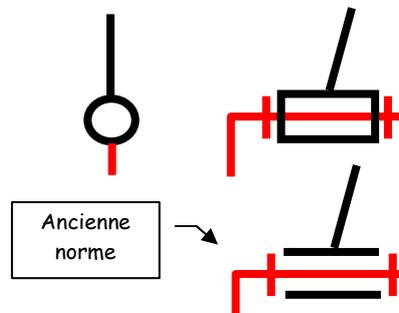
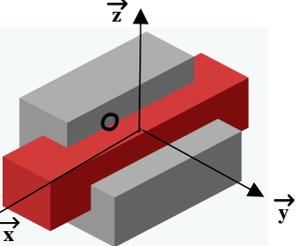
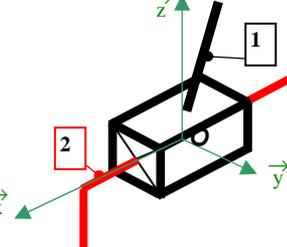
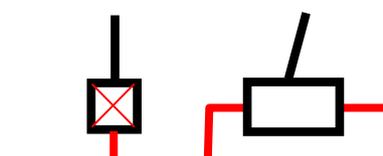
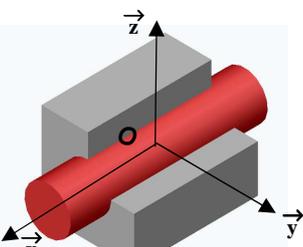
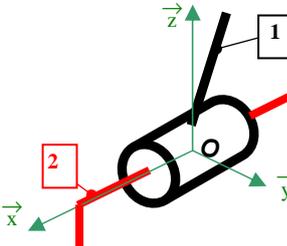
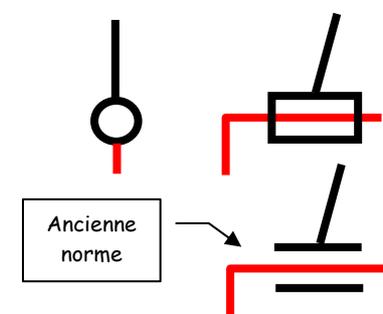
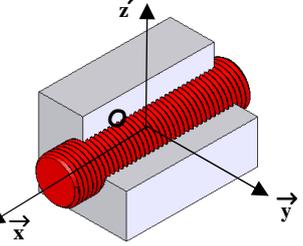
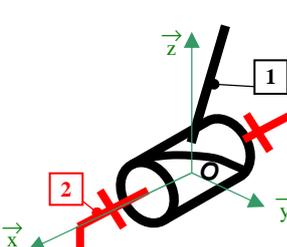
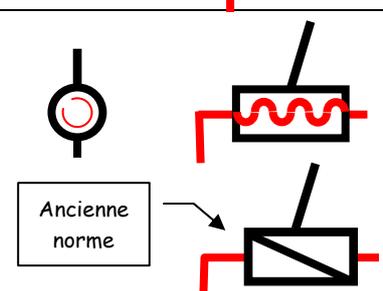
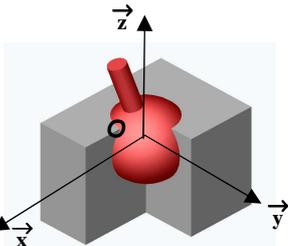
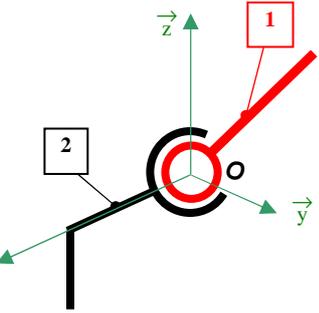
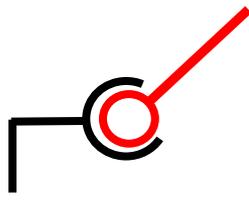
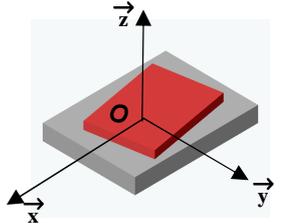
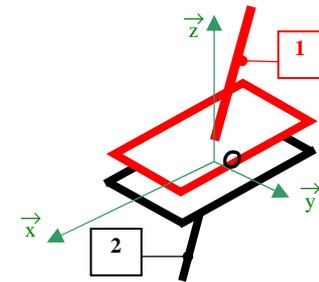
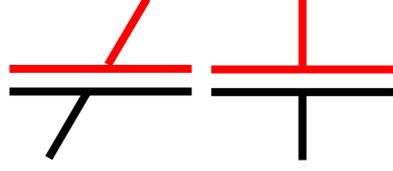
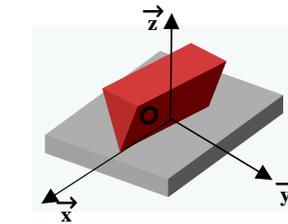
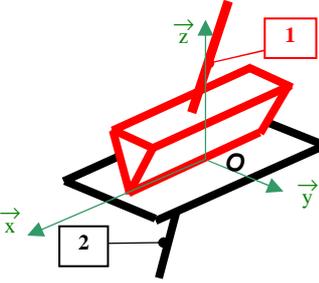
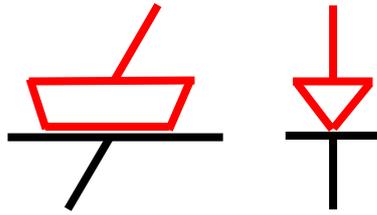
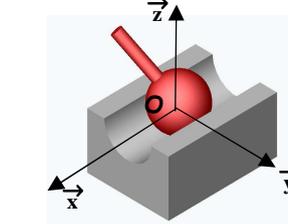
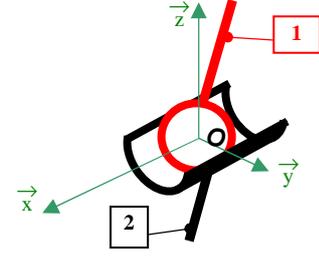
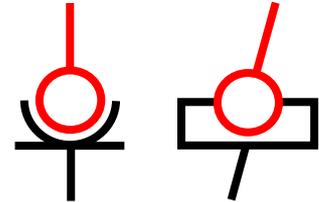
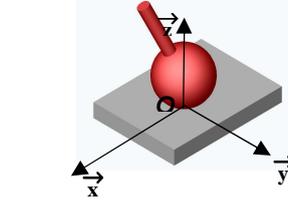
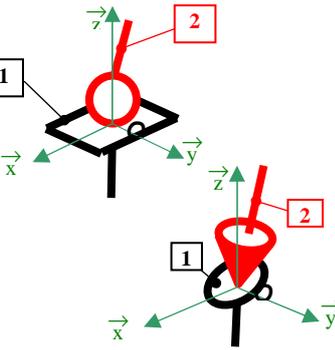
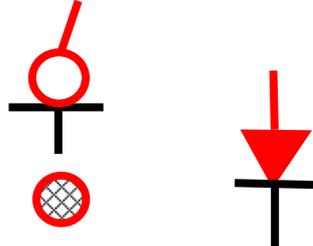


Un schéma cinématique un schéma qui permet de représenter un mécanisme de façon simple et rapide dans le but

- De comprendre ou expliquer son fonctionnement
- Avoir un modèle pour faire des calculs de mécanique : mouvement vitesse, forces
- De rentrer le mécanisme dans un simulateur mécanique de type « Motion Works » , « Cosmos motion »

1. Un schéma cinématique est construit à partir de liaisons normalisées (voir liste ci-dessous)

Nom et modèle 3D	Degrés de liberté	Schéma 3D	Schéma 2D								
<p>Encastrement</p> 	<table border="1"> <tr><td>Tr</td><td>Rot</td></tr> <tr><td>0</td><td>0</td></tr> <tr><td>0</td><td>0</td></tr> <tr><td>0</td><td>0</td></tr> </table> <p>Bilan degrés de lib <u>0 T, 0 R</u></p>	Tr	Rot	0	0	0	0	0	0		
Tr	Rot										
0	0										
0	0										
0	0										
<p>Pivot</p> 	<table border="1"> <tr><td>Tr</td><td>Rot</td></tr> <tr><td>0</td><td>Rx</td></tr> <tr><td>0</td><td>0</td></tr> <tr><td>0</td><td>0</td></tr> </table> <p>Bilan degrés de lib <u>0 T, 1 R</u></p>	Tr	Rot	0	Rx	0	0	0	0		
Tr	Rot										
0	Rx										
0	0										
0	0										
<p>Glissière</p> 	<table border="1"> <tr><td>Tr</td><td>Rot</td></tr> <tr><td>Tx</td><td>0</td></tr> <tr><td>0</td><td>0</td></tr> <tr><td>0</td><td>0</td></tr> </table> <p>Bilan degrés de lib <u>1 T, 0 R</u></p>	Tr	Rot	Tx	0	0	0	0	0		
Tr	Rot										
Tx	0										
0	0										
0	0										
<p>Pivot glissant</p> 	<table border="1"> <tr><td>Tr</td><td>Rot</td></tr> <tr><td>Tx</td><td>Rx</td></tr> <tr><td>0</td><td>0</td></tr> <tr><td>0</td><td>0</td></tr> </table> <p>Bilan degrés de lib <u>1 T, 1 R</u></p>	Tr	Rot	Tx	Rx	0	0	0	0		
Tr	Rot										
Tx	Rx										
0	0										
0	0										
<p>Hélicoïdale</p> 	<table border="1"> <tr><td>Tr</td><td>Rot</td></tr> <tr><td>Tx</td><td>Rx</td></tr> <tr><td>0</td><td>0</td></tr> <tr><td>0</td><td>0</td></tr> </table> <p>Bilan degrés de lib <u>1 T + R conjugués</u></p>	Tr	Rot	Tx	Rx	0	0	0	0		
Tr	Rot										
Tx	Rx										
0	0										
0	0										

Nom et modèle 3D	Degrés de liberté	Schéma 3D	Schéma 2D								
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Tr	Rot										
0	Rx										
0	Ry										
0	Rz										
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Tr	Rot										
Tx	0										
Ty	0										
0	Rz										
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Tr	Rot										
Tx	Rx										
Ty	0										
0	Rz										
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Tr	Rot										
Tx	Rx										
0	Ry										
0	Rz										
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Tr	Rot										
Tx	Rx										
Ty	Ry										
0	Rz										