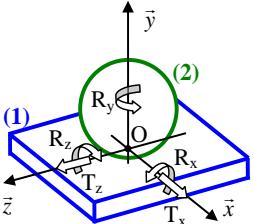
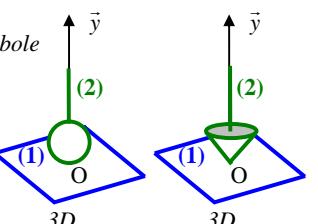
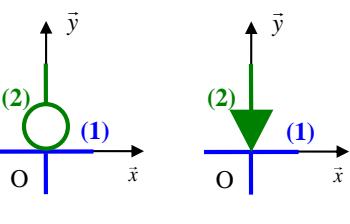
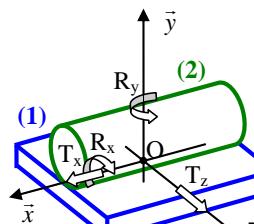
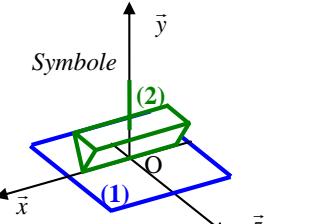
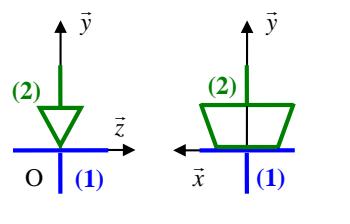
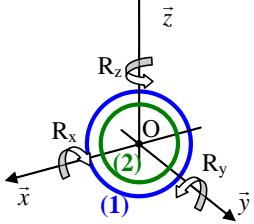
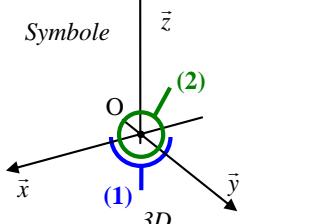
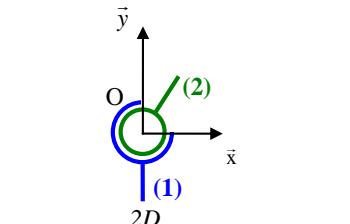
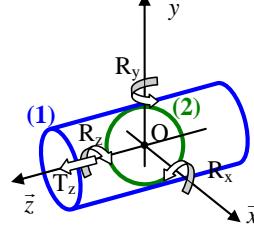
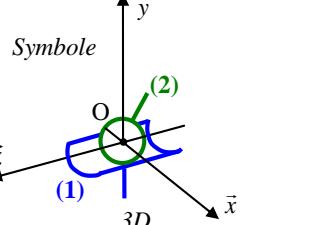
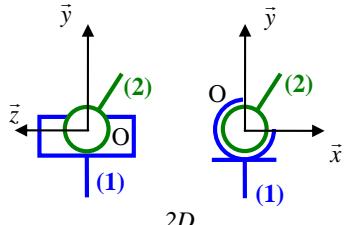
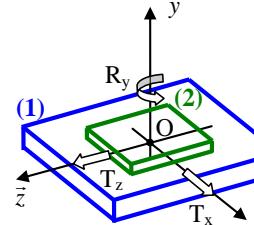
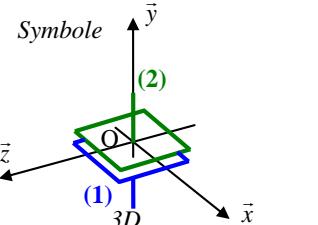
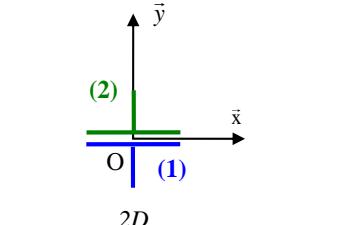
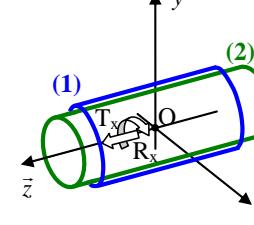
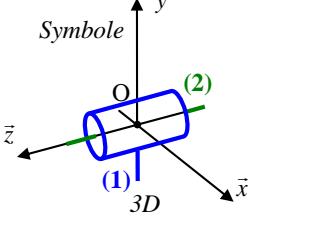
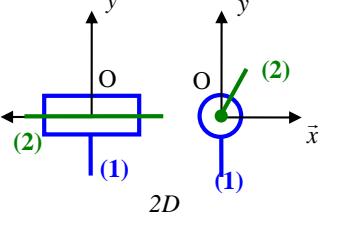


# Synthèse – Représentation des liaisons

Représentation 3D	Représentation 2D	Degrés de liberté	Actions transmises.
 <p>Symbol : </p>		$R_x \quad T_x$ $R_y \quad 0$ $R_z \quad T_z$	$\begin{Bmatrix} 0 & 0 \\ Y & 0 \\ 0 & 0 \end{Bmatrix}_o$
 <p>Symbol : </p>		$R_x \quad T_x$ $R_y \quad 0$ $0 \quad T_z$	$\begin{Bmatrix} 0 & 0 \\ Y & 0 \\ 0 & N \end{Bmatrix}_o$
 <p>Symbol : </p>		$R_x \quad 0$ $R_y \quad 0$ $R_z \quad 0$	$\begin{Bmatrix} X & 0 \\ Y & 0 \\ Z & 0 \end{Bmatrix}_o$
 <p>Symbol : </p>		$R_x \quad 0$ $R_y \quad 0$ $R_z \quad T_z$	$\begin{Bmatrix} X & 0 \\ Y & 0 \\ 0 & 0 \end{Bmatrix}_o$
 <p>Symbol : </p>		$0 \quad T_x$ $R_y \quad 0$ $0 \quad T_z$	$\begin{Bmatrix} 0 & L \\ Y & 0 \\ 0 & N \end{Bmatrix}_o$
 <p>Symbol : </p>		$0 \quad 0$ $0 \quad 0$ $R_z \quad T_z$	$\begin{Bmatrix} X & L \\ Y & M \\ 0 & 0 \end{Bmatrix}_o$

<p>Symbolic representation:</p> <p><i>3D</i></p>	<p>Symbolic representation:</p> <p><i>2D</i></p>	$\begin{pmatrix} X & L \\ Y & M \\ Z & 0 \end{pmatrix}_O$	
<p>Symbolic representation:</p> <p><i>3D</i></p>	<p>Symbolic representation:</p> <p><i>2D</i></p>	$\begin{pmatrix} X & L \\ Y & M \\ Z & 0 \end{pmatrix}_O$	