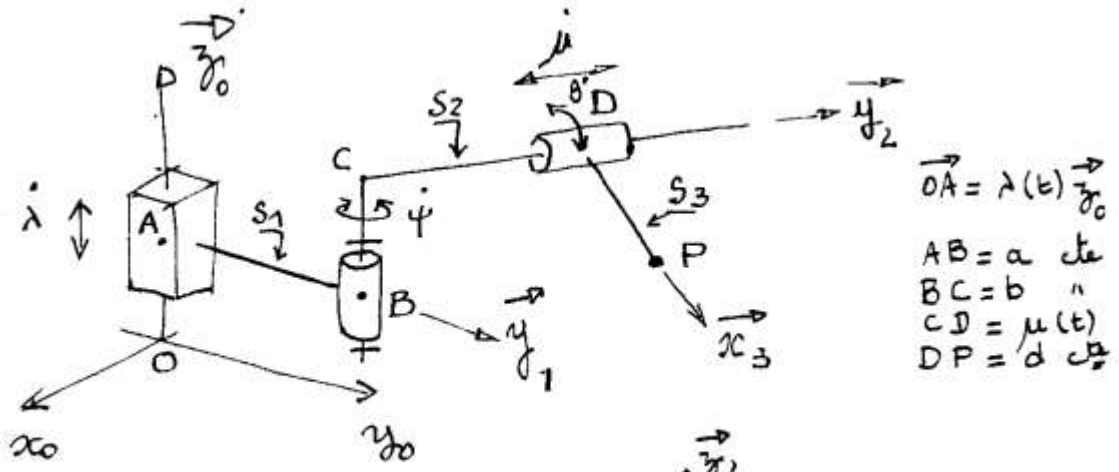



1)


$\vec{\Omega}_{1/0}$ = $\vec{\Omega}_{2/1}$ = $\vec{\Omega}_{/}$ =

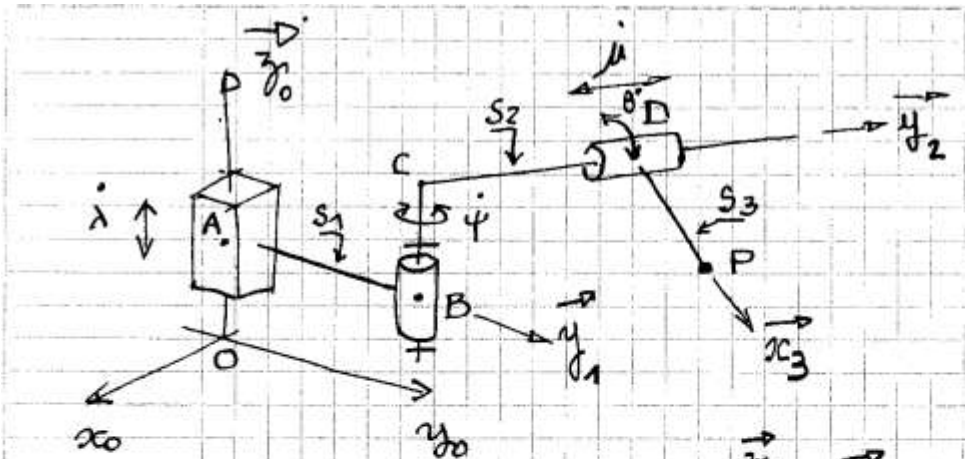
2) Vecteurs position /Ro de A, D, P

3) Vecteur vitesse $\vec{V}_{D/Ro}$ , $\vec{V}_{P/Ro}$

4) Vecteur accélération $\vec{\Gamma}_{D/Ro}$.

$\vec{V}_{D/Ro} = \dot{\lambda}\vec{z}_0 + \dot{\mu}\vec{y}_2 - \mu\dot{\psi}\vec{x}_2$ $\quad \vec{V}_{P/Ro} = \dot{\lambda}\vec{z}_0 + \dot{\mu}\vec{y}_2 - \mu\dot{\psi}\vec{x}_2 + d\dot{\psi}\cos\theta\,\vec{y}_2 - d\dot{\theta}\vec{z}_3$

$\vec{\Gamma}_{D/Ro} = \ddot{\lambda}\vec{z}_0 - 2\dot{\mu}\dot{\psi}\vec{x}_2 - \mu\ddot{\psi}\vec{x}_2 + \ddot{\mu}\vec{y}_2 - \mu\dot{\psi}^2\vec{y}_2$




1) $\vec{\Omega}_{1/0} = \vec{0}$ $\quad \vec{\Omega}_{2/1} = \dot{\psi}\,\vec{z}_1$ $\quad \vec{\Omega}_{3/2} = \dot{\theta}\,\vec{y}_2$

2) Vecteurs position /Ro de A, D, P $\quad \vec{OA} = \lambda\,\vec{z}_0$

$$\vec{AP} = \vec{AD} + d\,\vec{x}_3 \qquad \vec{AD} = \lambda\,\vec{z}_0 + a\,\vec{y}_1 + b\,\vec{z}_0 + \mu\,\vec{y}_2$$

3) Vecteur vitesse $\vec{V}_{D/R_0}$, $\vec{V}_{P/R_0}$

4) Vecteur accélération $\vec{\Gamma}_{D/R_0}$.

$$\vec{V}_{D/R_0} = \dot{\lambda}\,\vec{z}_0 + a(\vec{0} \wedge \vec{y}_1) + \vec{0} + \dot{\mu}\,\vec{y}_2 + \mu(\dot{\psi}\,\vec{z}_1 \wedge \vec{y}_2)$$

$$\vec{V}_{D/R_0} = \dot{\lambda}\,\vec{z}_0 + \dot{\mu}\,\vec{y}_2 - \mu\dot{\psi}\,\vec{x}_2$$

$$\vec{V}_{P/R_0} = \dot{\lambda}\,\vec{z}_0 + \dot{\mu}\,\vec{y}_2 - \mu\dot{\psi}\,\vec{x}_2 + d(\dot{\psi}\,\vec{z}_1 + \dot{\theta}\,\vec{y}_2) \wedge \vec{x}_3$$

$$\vec{V}_{P/R_0} = \dot{\lambda}\,\vec{z}_0 + \dot{\mu}\,\vec{y}_2 - \mu\dot{\psi}\,\vec{x}_2 + d\dot{\psi}\cos\theta\,\vec{y}_2 - d\dot{\theta}\,\vec{z}_3$$

$$\vec{\Gamma}_{D/R_0} = \ddot{\lambda}\,\vec{z}_0 + \ddot{\mu}\,\vec{y}_2 - \dot{\mu}\dot{\psi}\,\vec{x}_2 - \dot{\mu}\dot{\psi}\,x_2 - \mu\ddot{\psi}\,\vec{x}_2 - \mu\dot{\psi}^2\,\vec{y}_2$$