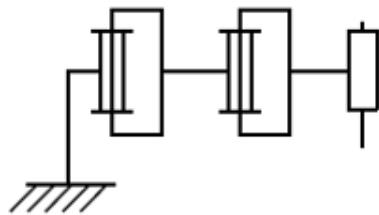


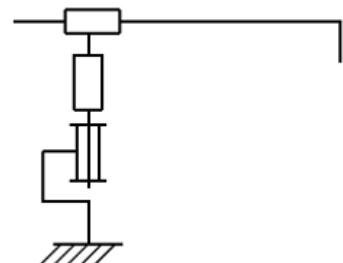
TD1 SMAR : Degrés de liberté (DDL)**Exercice 1 :**

Etant donnés les schémas cinématiques simplifiés des robots ci-après.

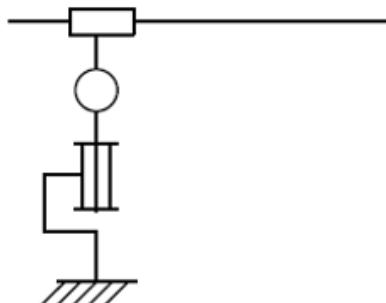
- 1- Donner la morphologie du robot manipulateur.
- 2- Nommer le type de robot.
- 3- Calculer le nombre de degrés de liberté (Nombre d'axes) du bras manipulateur en utilisant l'équation de Grübeler.



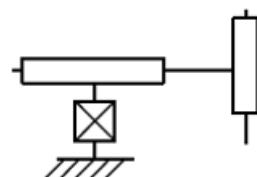
(a)



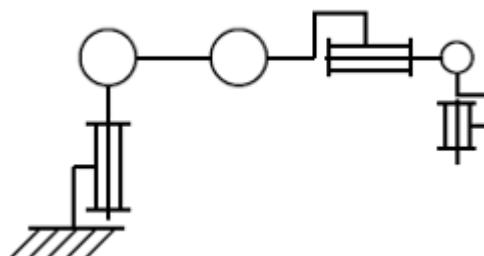
(b)



(c)



(d)



(e)