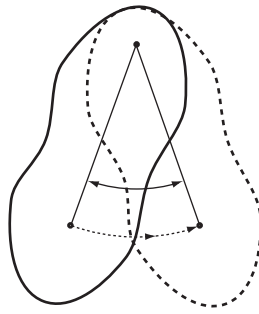


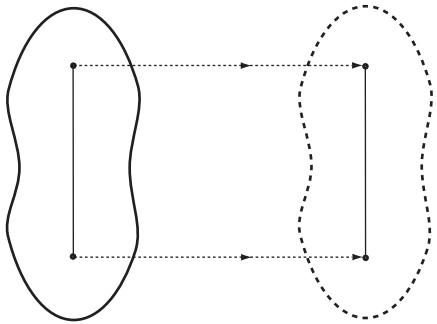
Figure 1.1

rotation

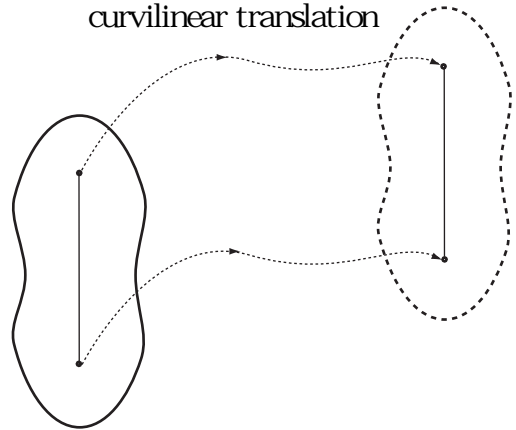


(a)

rectilinear translation

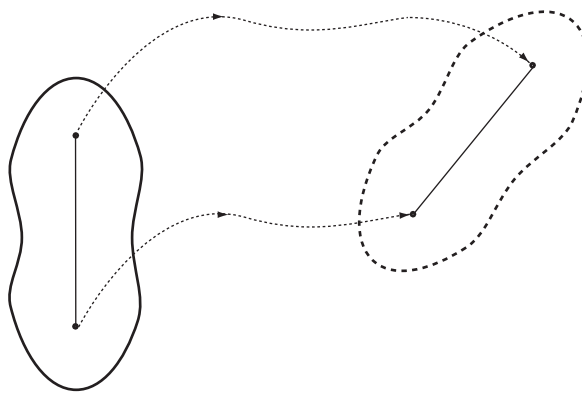


curvilinear translation



(b)

general plane motion

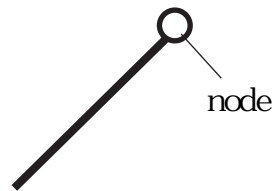
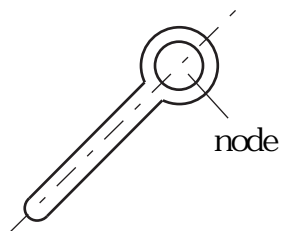


(c)

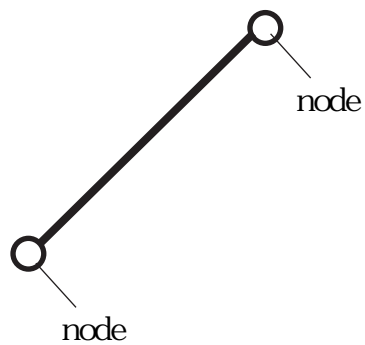
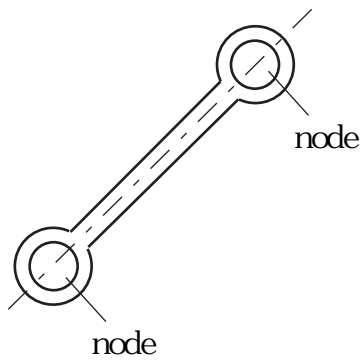
Figure 1.2

Link

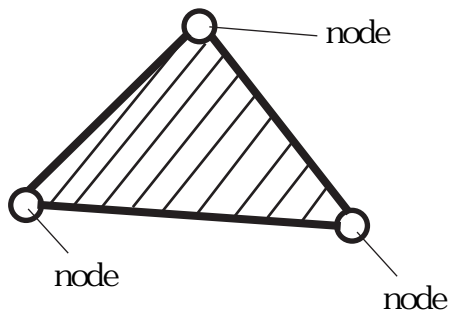
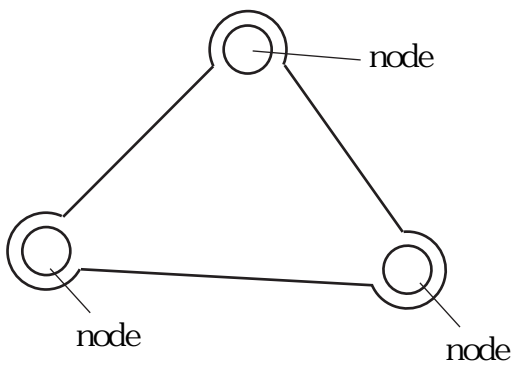
Schematic representation



(a)



(b)

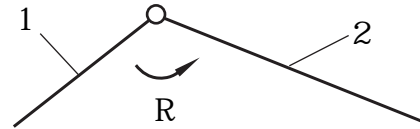
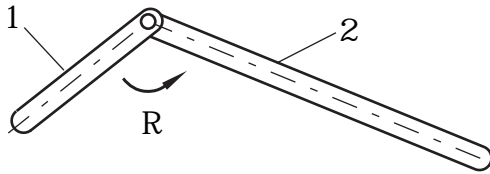
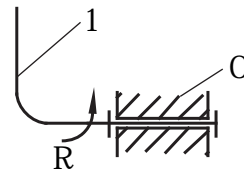
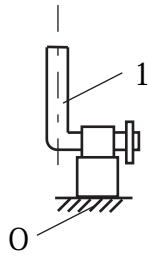
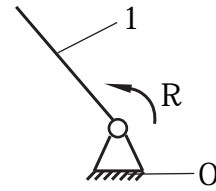
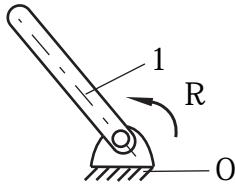


(c)

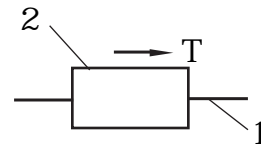
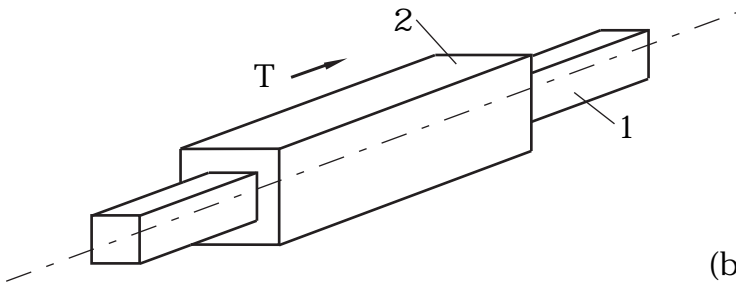
Figure 1.3

Type of full joint

Schematic representation



(a)

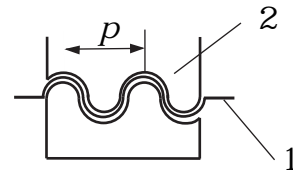
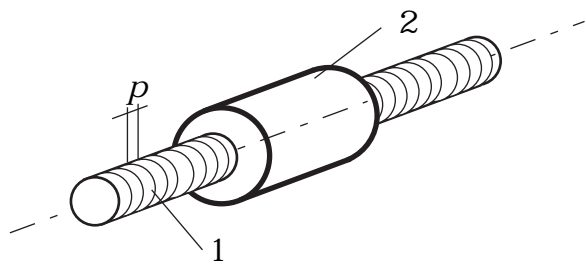


(b)

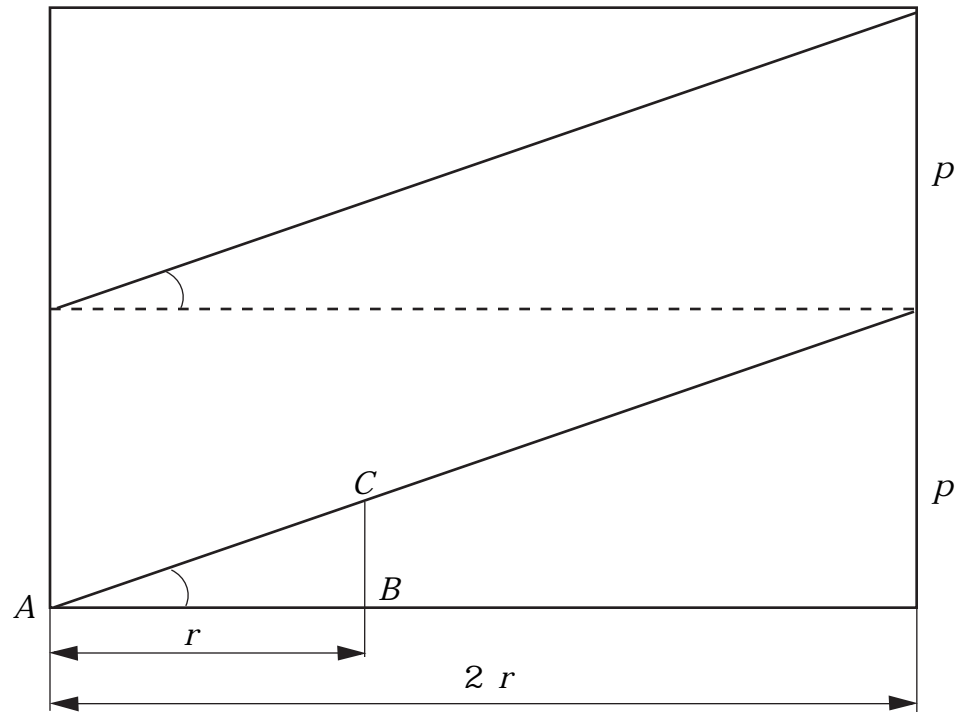
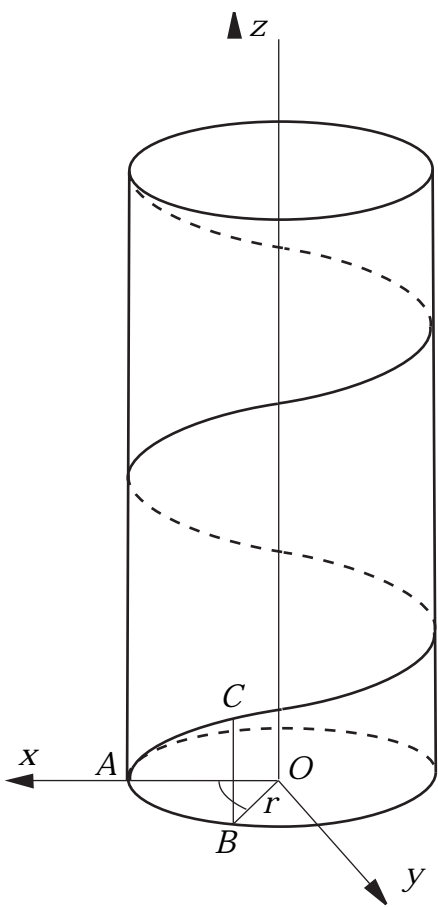
Figure 1.4

Type of full joint

Schematic representation



(a)



= helix angle
 p = pitch

(b)

Figure 1.5

