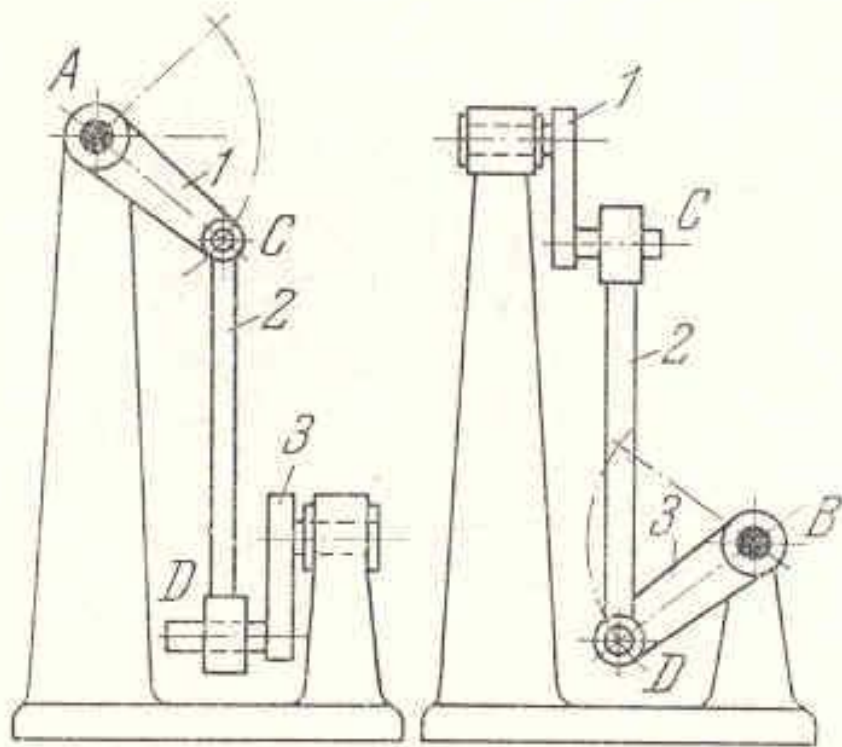
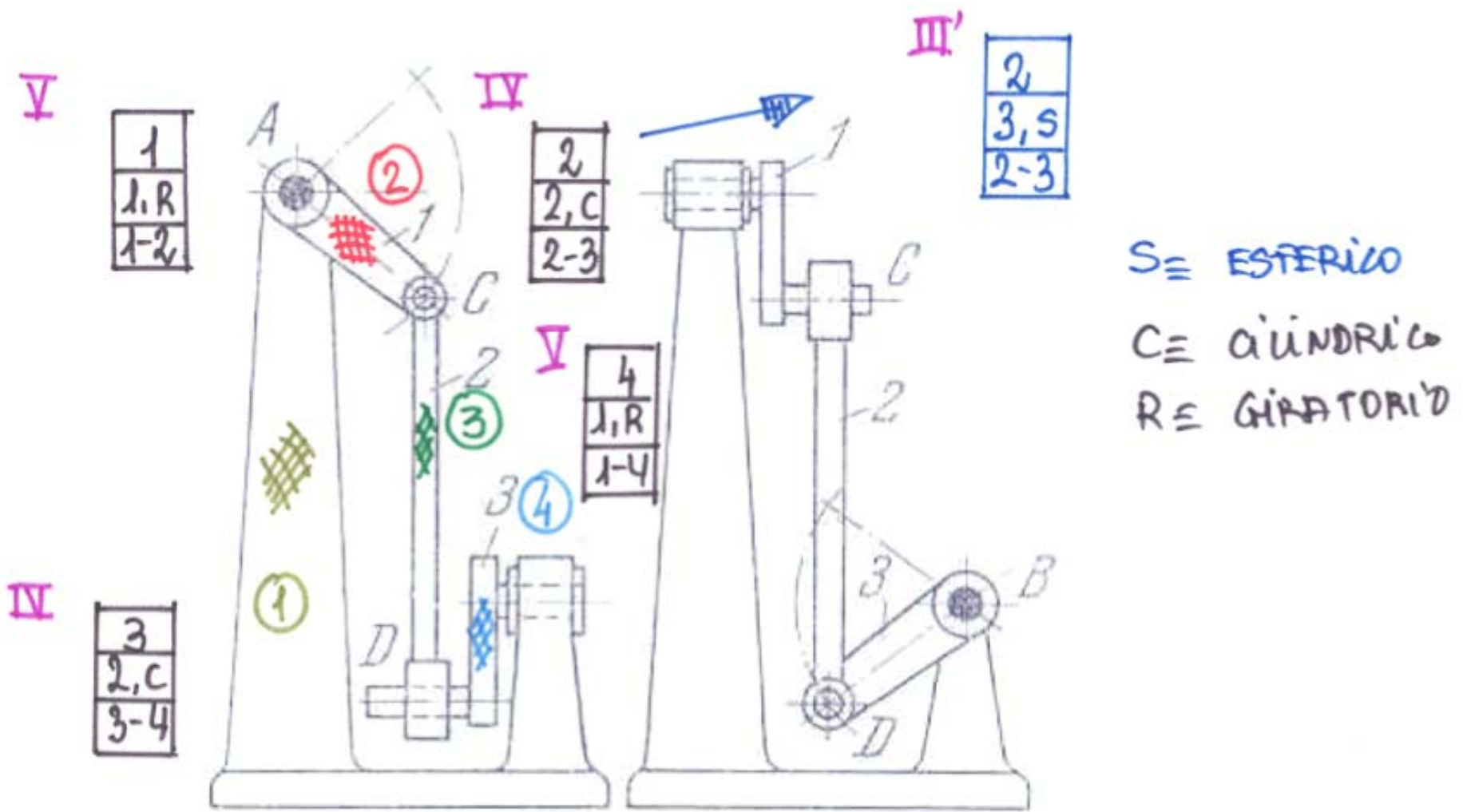


7. EJEMPLOS de Aplicación del Criterio de Movilidad.

560	MECANISMO ESPACIAL DE CUATRO ELEMENTOS ARTICULADOS	PA
		Cu



El movimiento basculante del elemento 1 alrededor del eje fijo A se transforma por la biela 2 en movimiento basculante del elemento 3 alrededor del eje fijo B. Los pares C y D son pares cilindricos que permiten la rotación y el deslizamiento. Los pares A y B son de rotación. Los ejes A y C son respectivamente perpendiculares a los ejes B y D.

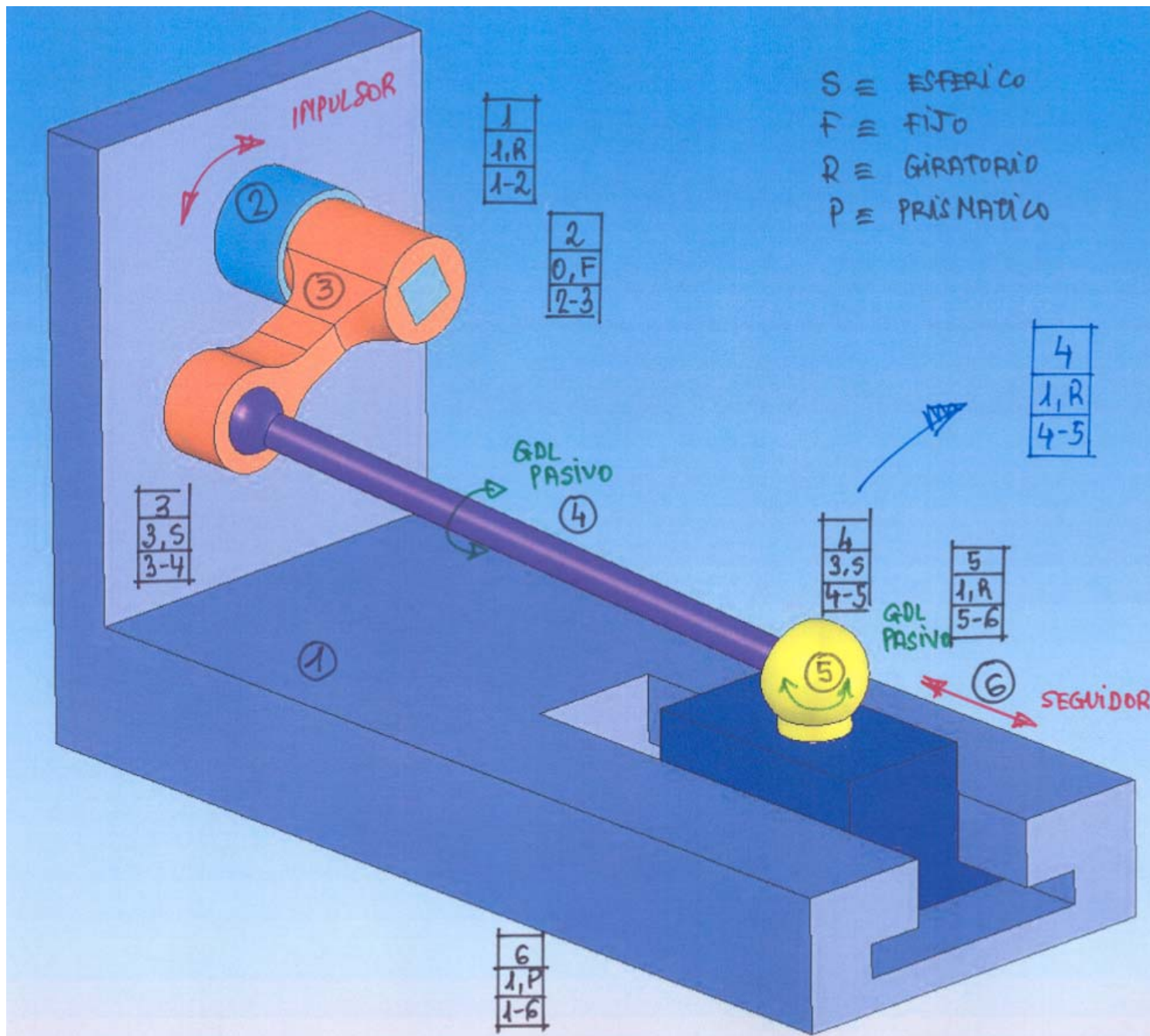
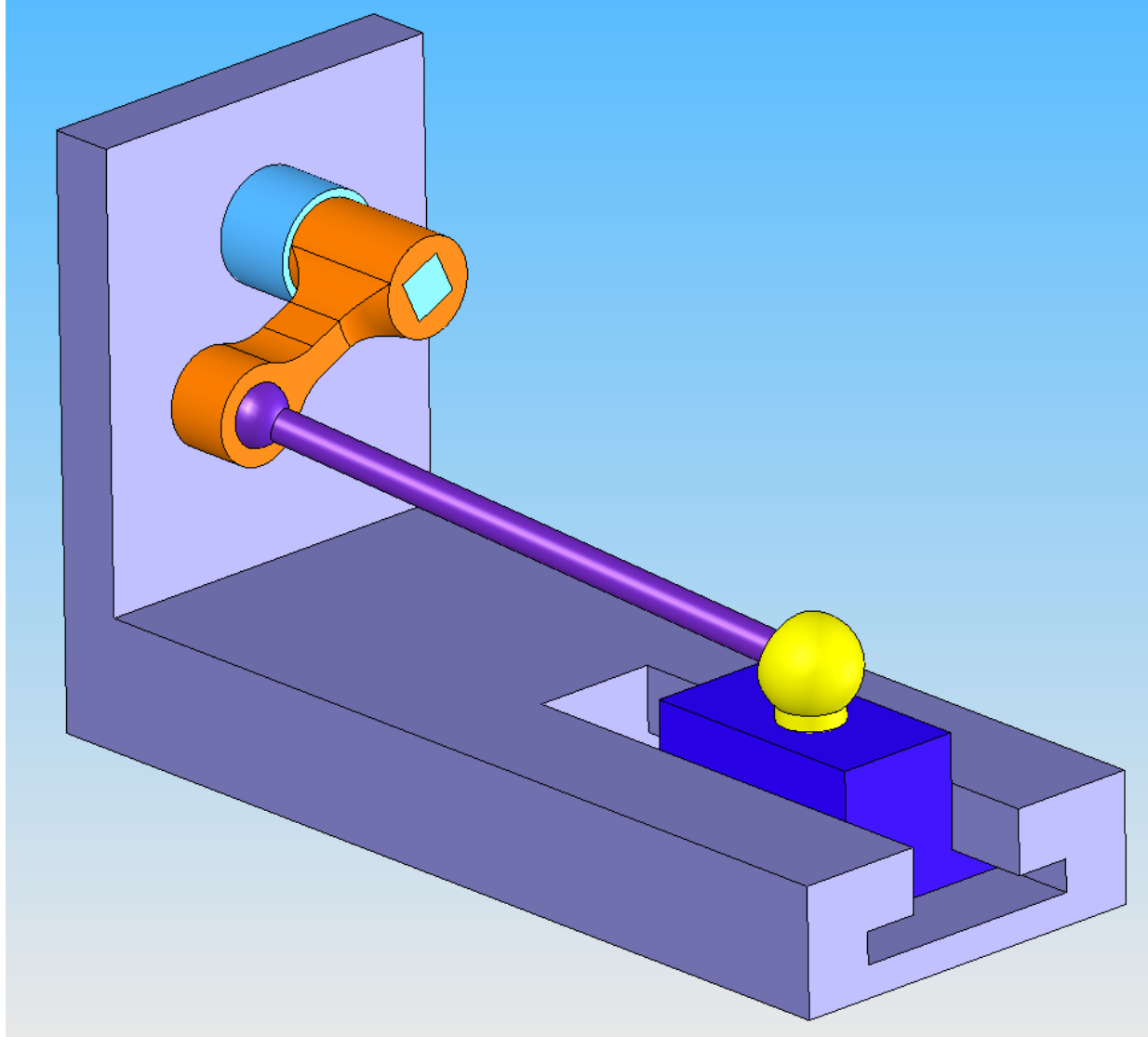


MOVILIDAD MECANISMO SOBRERESTRINGIDO

MOVILIDAD MECANISMO AUTOALINEADOR

$$M = 6 * (4 - 4 - 1) + 1 + 2 + 2 + 1 = 0 \text{ GDL}$$

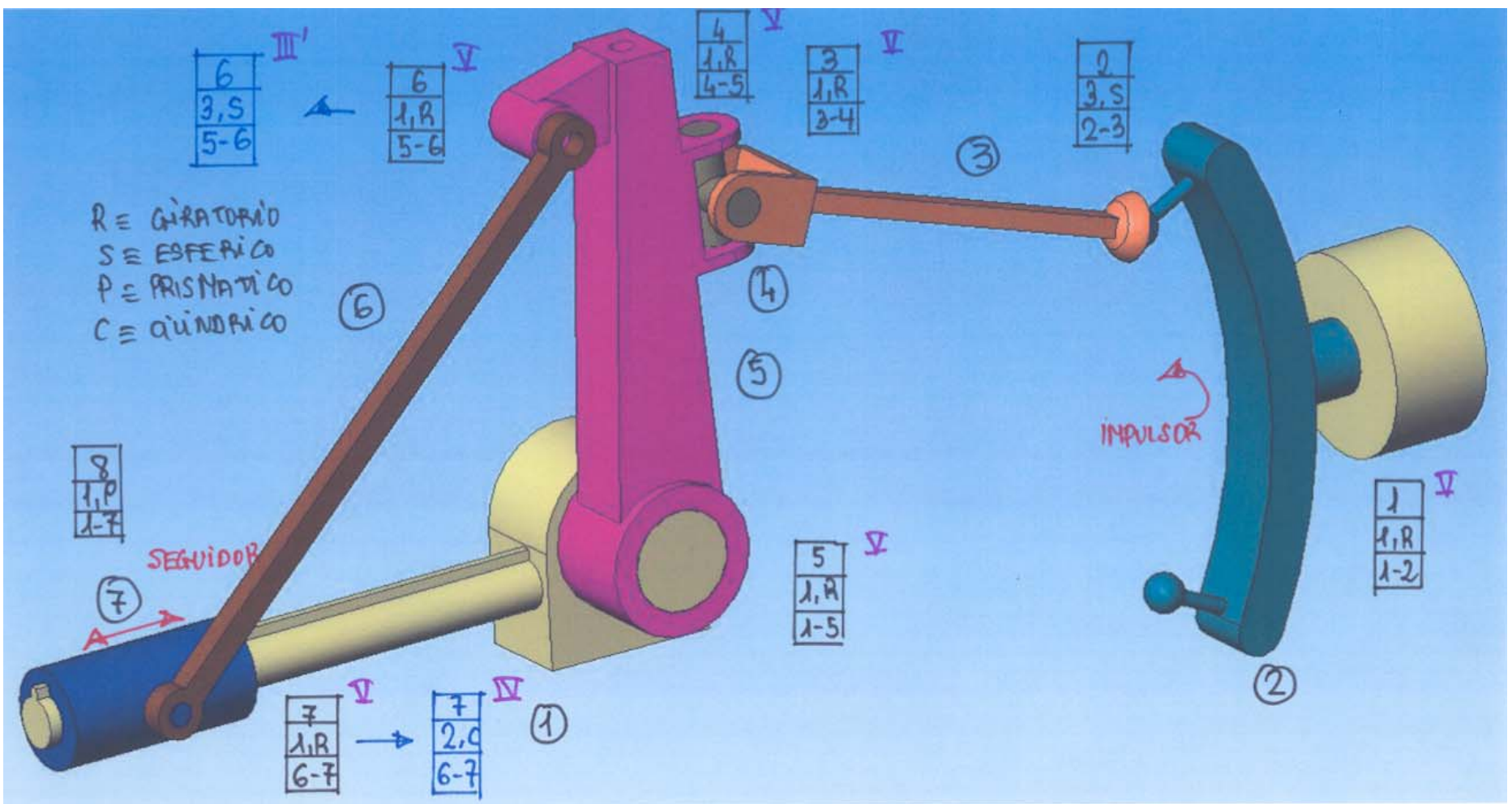
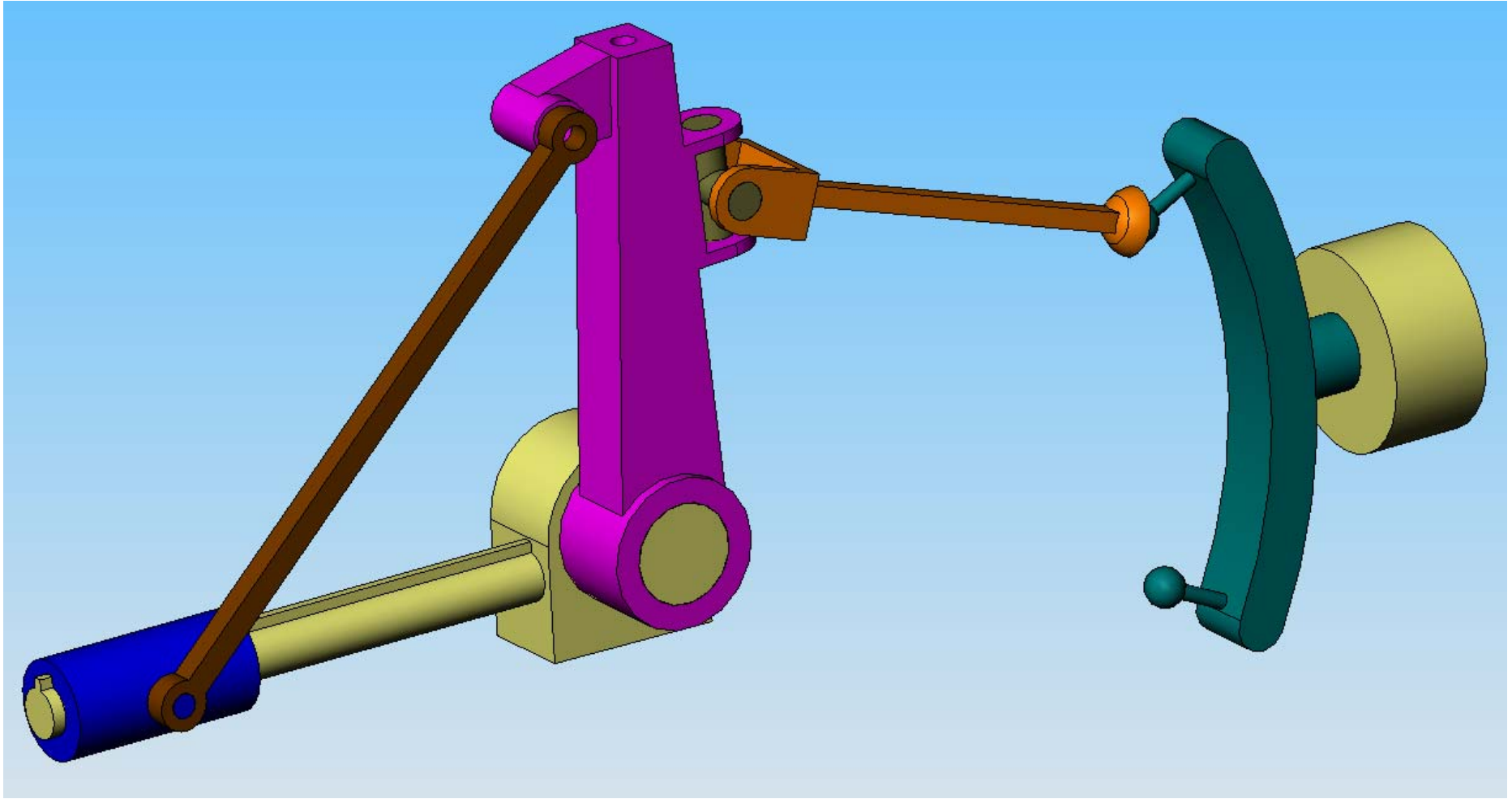
$$M = 6 * (4 - 4 - 1) + 1 + 3 + 2 + 1 = 1 \text{ GDL}$$



MOVILIDAD MECANISMO - CON GRADOS LIBERTAD PASIVOS

MOVILIDAD MECANISMO AUTOALINEADOR

$M = 6 * (6 - 6 - 1) + 1 + 0 + 3 + 3 + 1 + 1 = 3 \text{ GDL}$ $M = 6 * (6 - 6 - 1) + 1 + 0 + 3 + 1 + 1 + 1 = 1 \text{ GDL}$

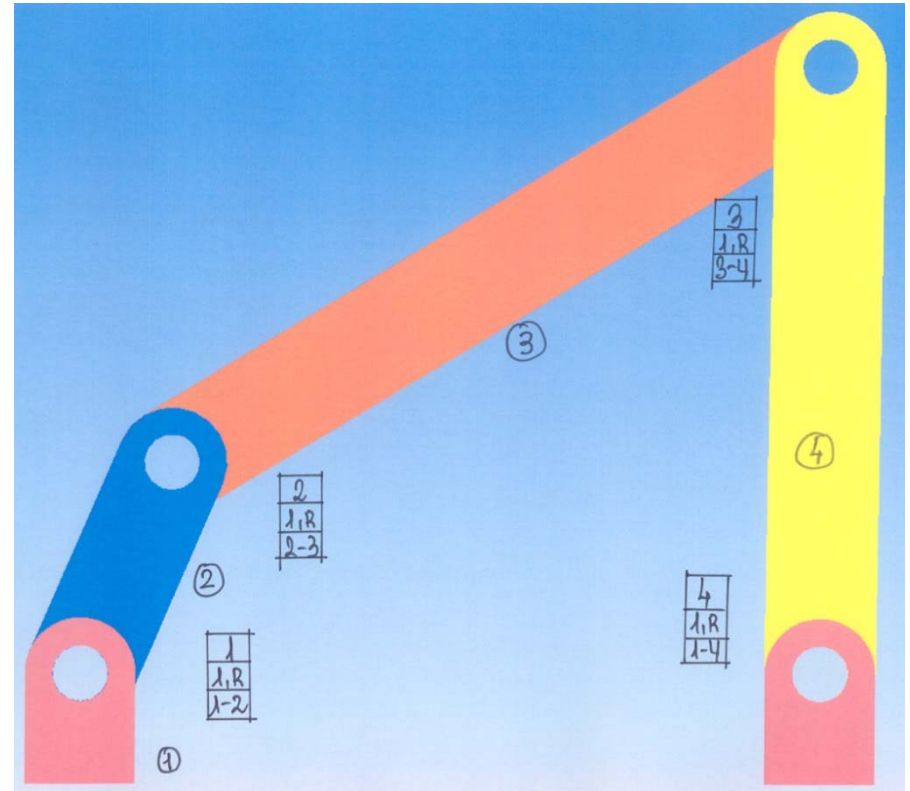
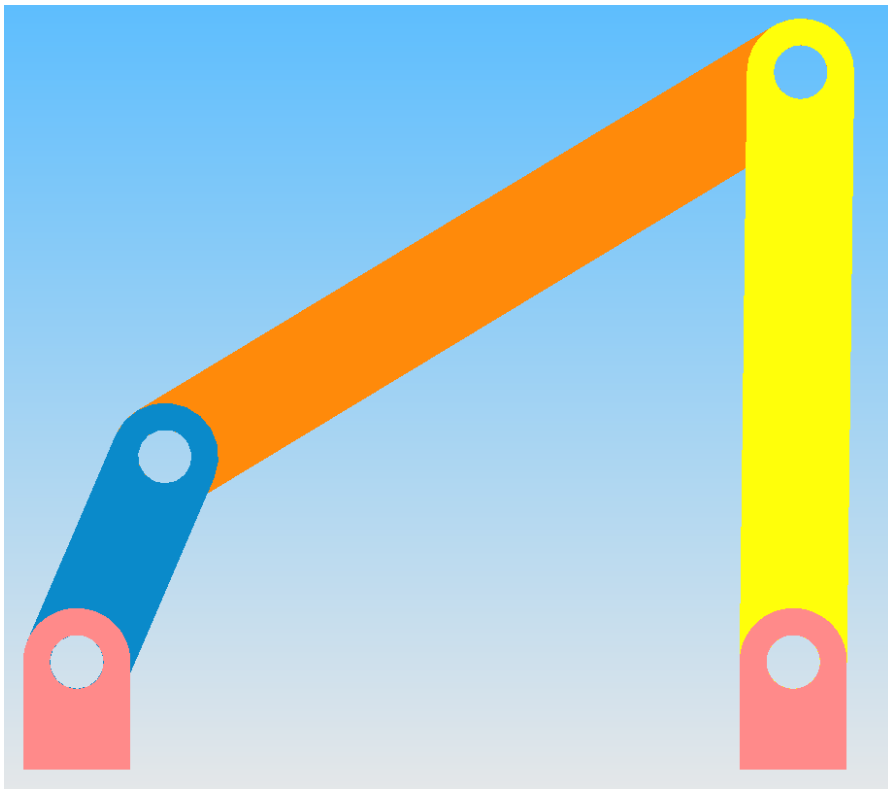


MOVILIDAD MECANISMO SOBRESRESTRINGIDO

MOVILIDAD MECANISMO AUTOALINEADOR

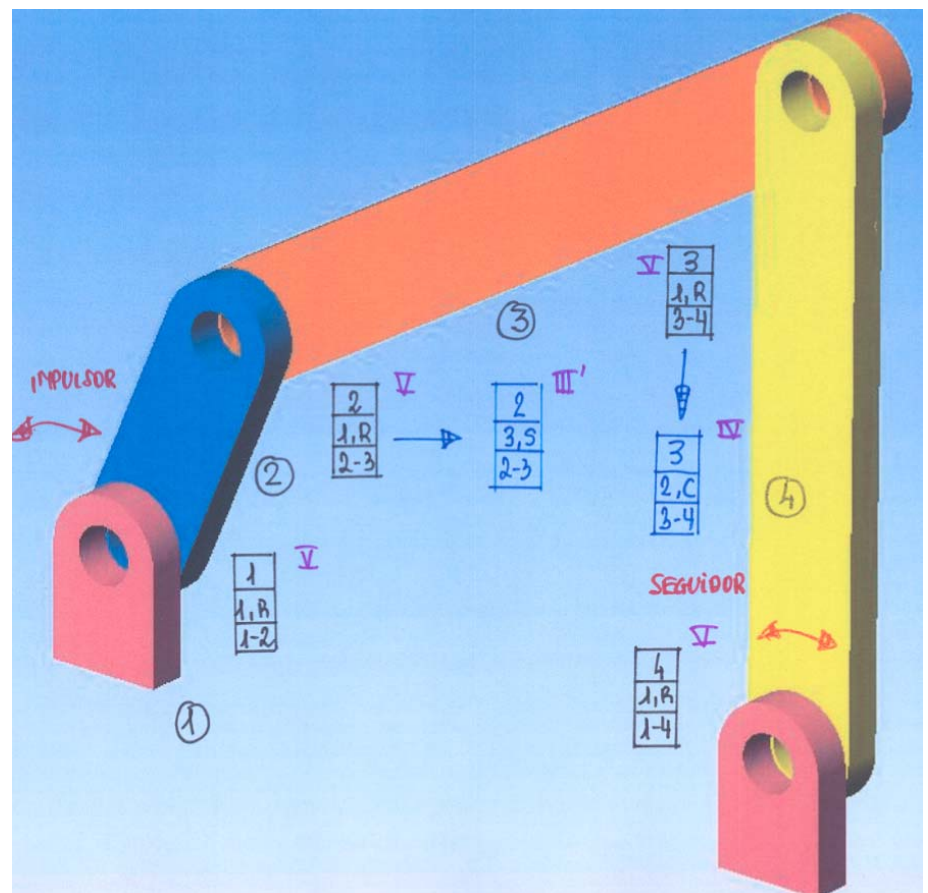
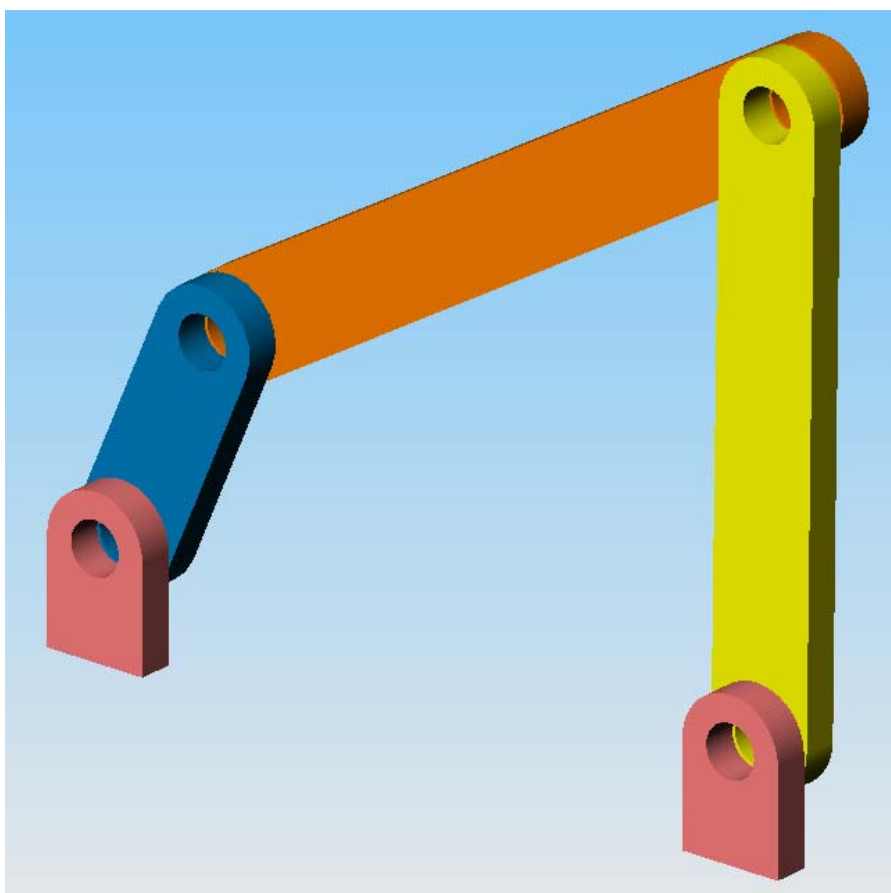
$M = 6 * (7 - 8 - 1) + 1 + 3 + 1 + 1 + 1 + 1 + 1 + 1 = -2$ $M = 6 * (7 - 8 - 1) + 1 + 3 + 1 + 1 + 1 + 3 + 2 + 1 = 1$

COMO MECANISMO PLANO



$$M = 3 * (4 - 4 - 1) + 1 + 1 + 1 + 1 = 1$$

COMO MECANISMO ESPACIAL



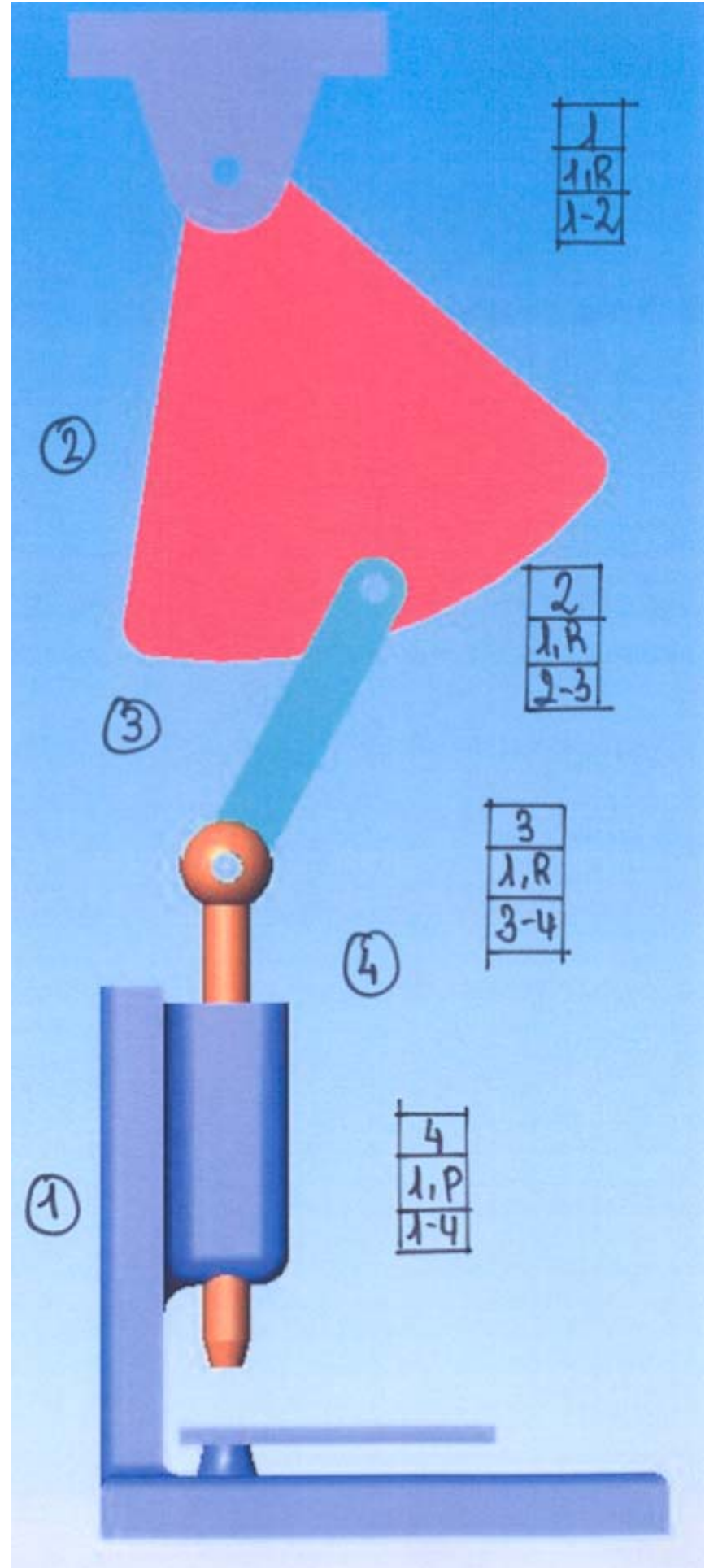
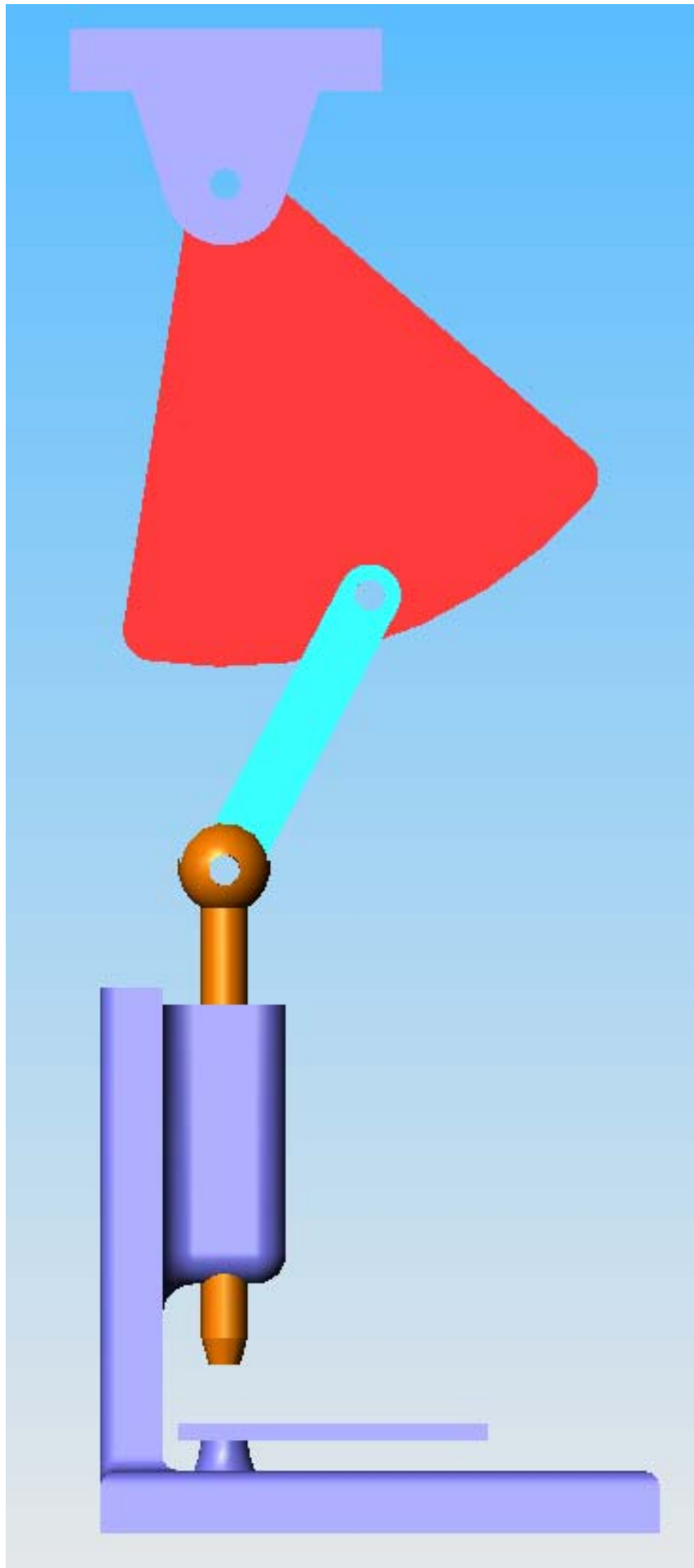
MOVILIDAD MECANISMO SOBRESRESTRINGIDO

$$M = 6 * (4 - 4 - 1) + 1 + 1 + 1 + 1 = -2$$

MOVILIDAD MECANISMO AUTOALINEADOR

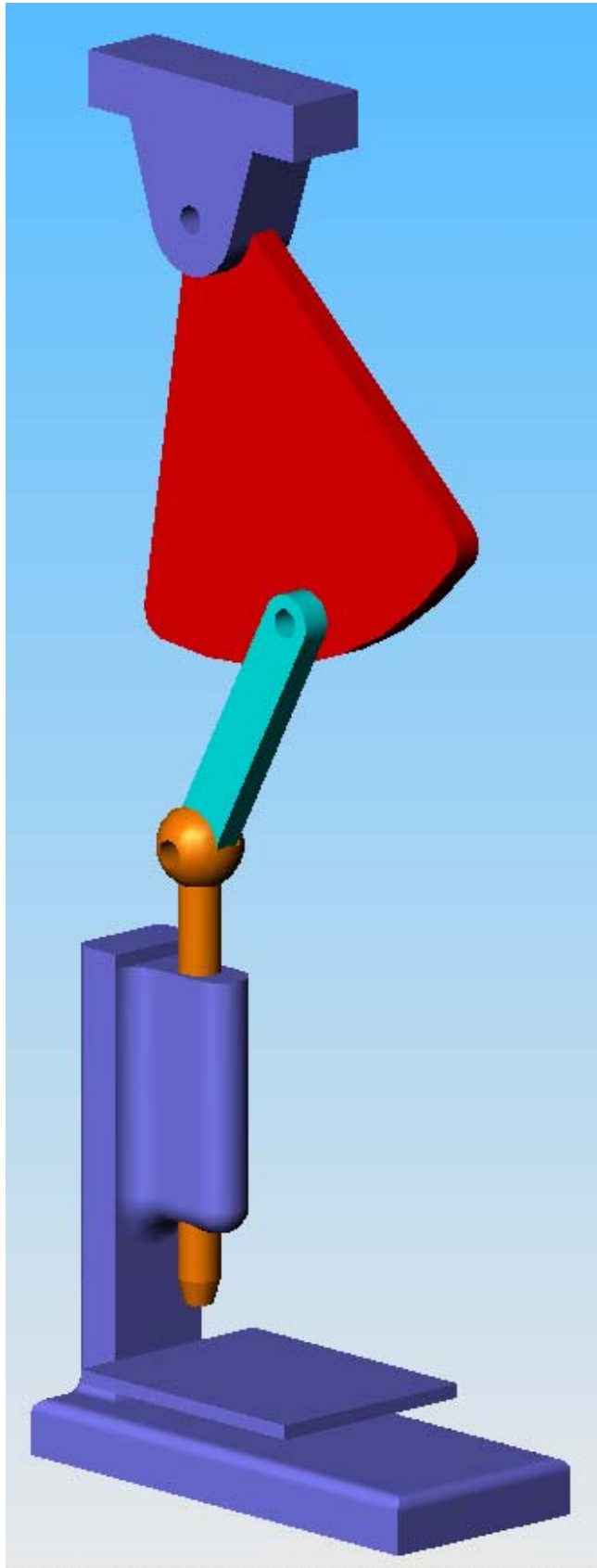
$$M = 6 * (4 - 4 - 1) + 1 + 3 + 2 + 1 = 1$$

COMO MECANISMO PLANO



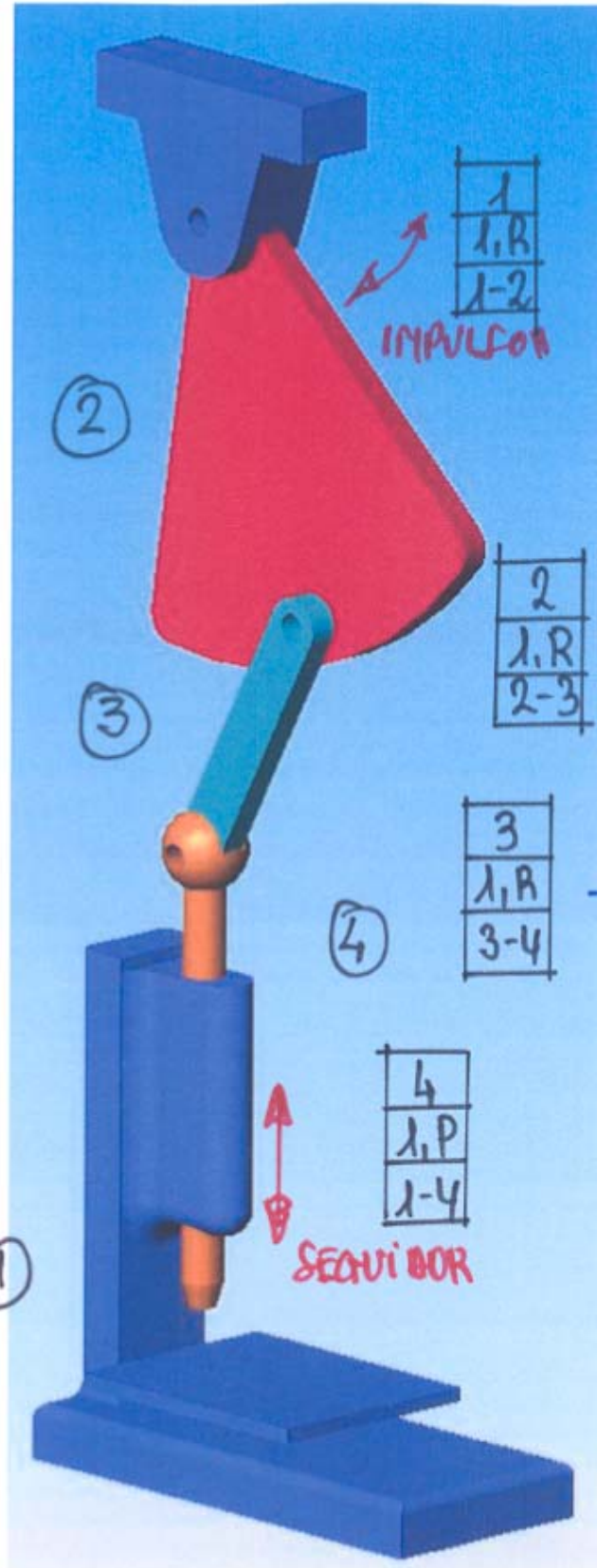
$$M = 3 * (4 - 4 - 1) + 1 + 1 + 1 + 1 = 1$$

COMO MECANISMO ESPACIAL



MOVILIDAD MECANISMO SOBRESRESTRINGIDO

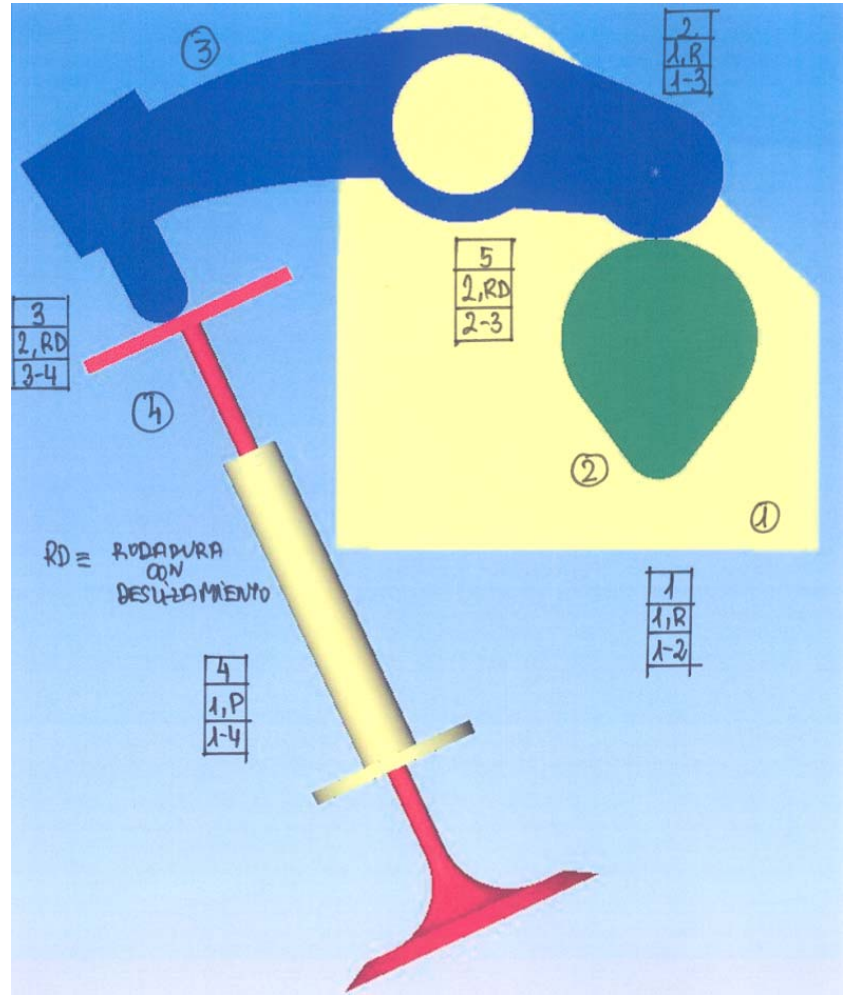
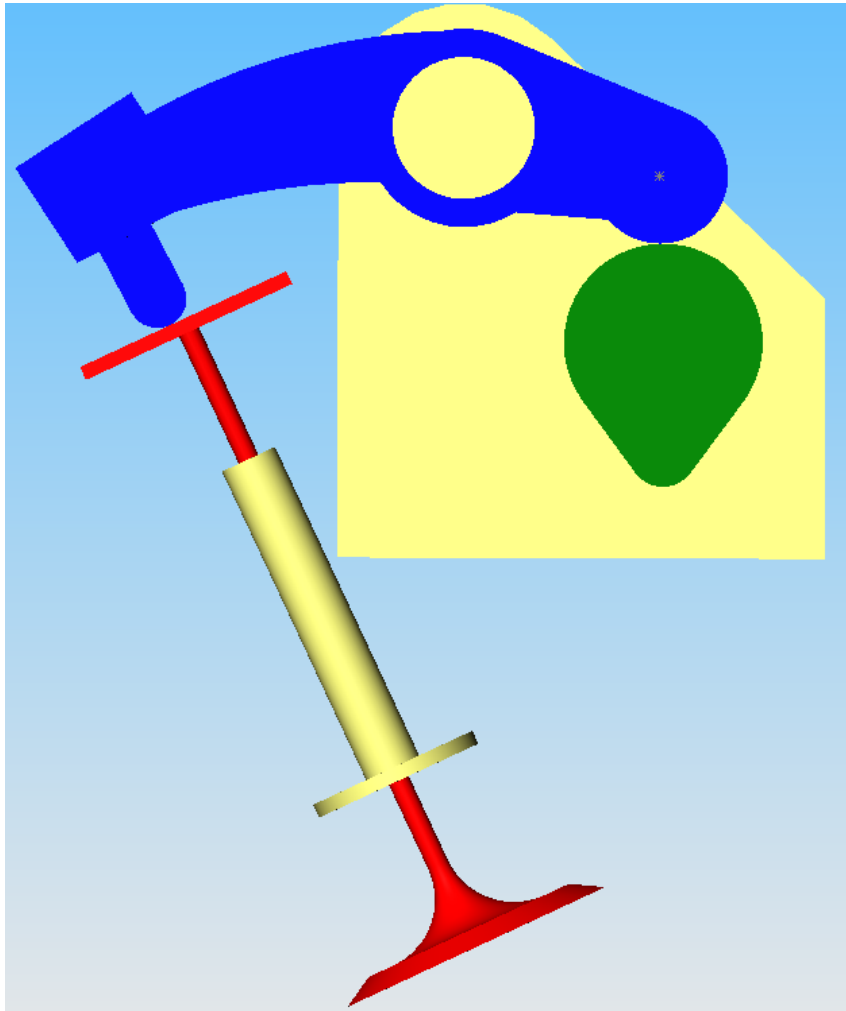
$$M = 6 * (4 - 4 - 1) + 1 + 1 + 1 + 1 = -2$$



MOVILIDAD MECANISMO AUTOALINEADOR

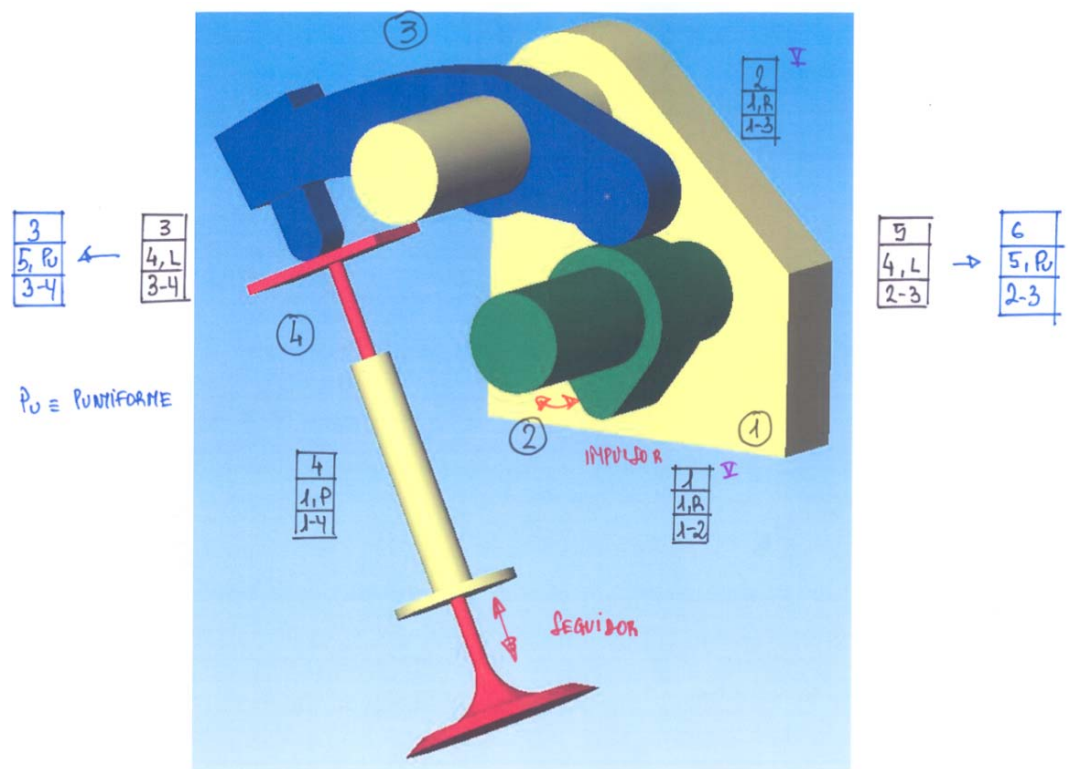
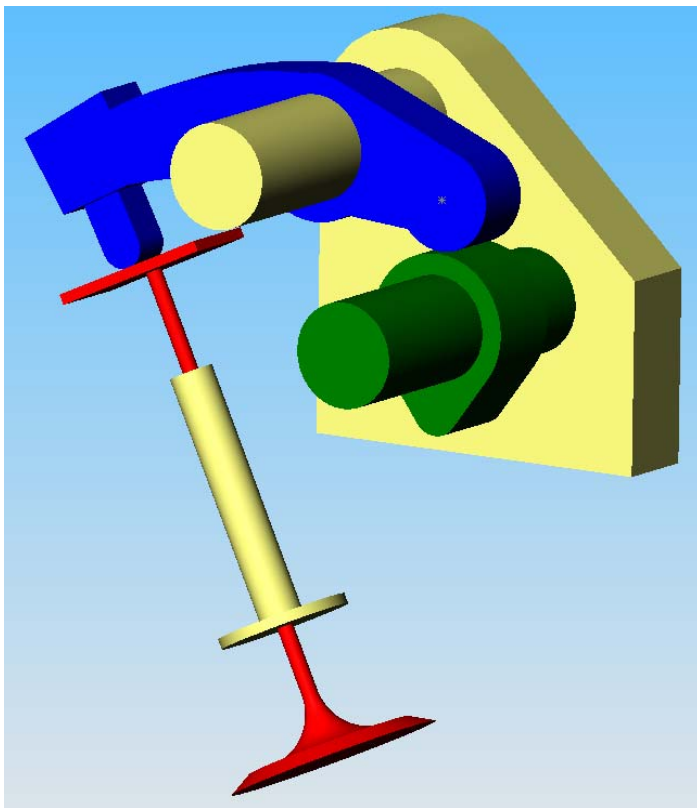
$$M = 6 * (4 - 4 - 1) + 1 + 3 + 2 + 1 = 1$$

LEVA CON SEGUIDOR DE CARA PLANA COMO MECANISMO PLANO



$$M = 3 * (4 - 5 - 1) + 1 + 1 + 2 + 1 + 2 = 1$$

LEVA CON SEGUIDOR DE CARA PLANA COMO MECANISMO ESPACIAL



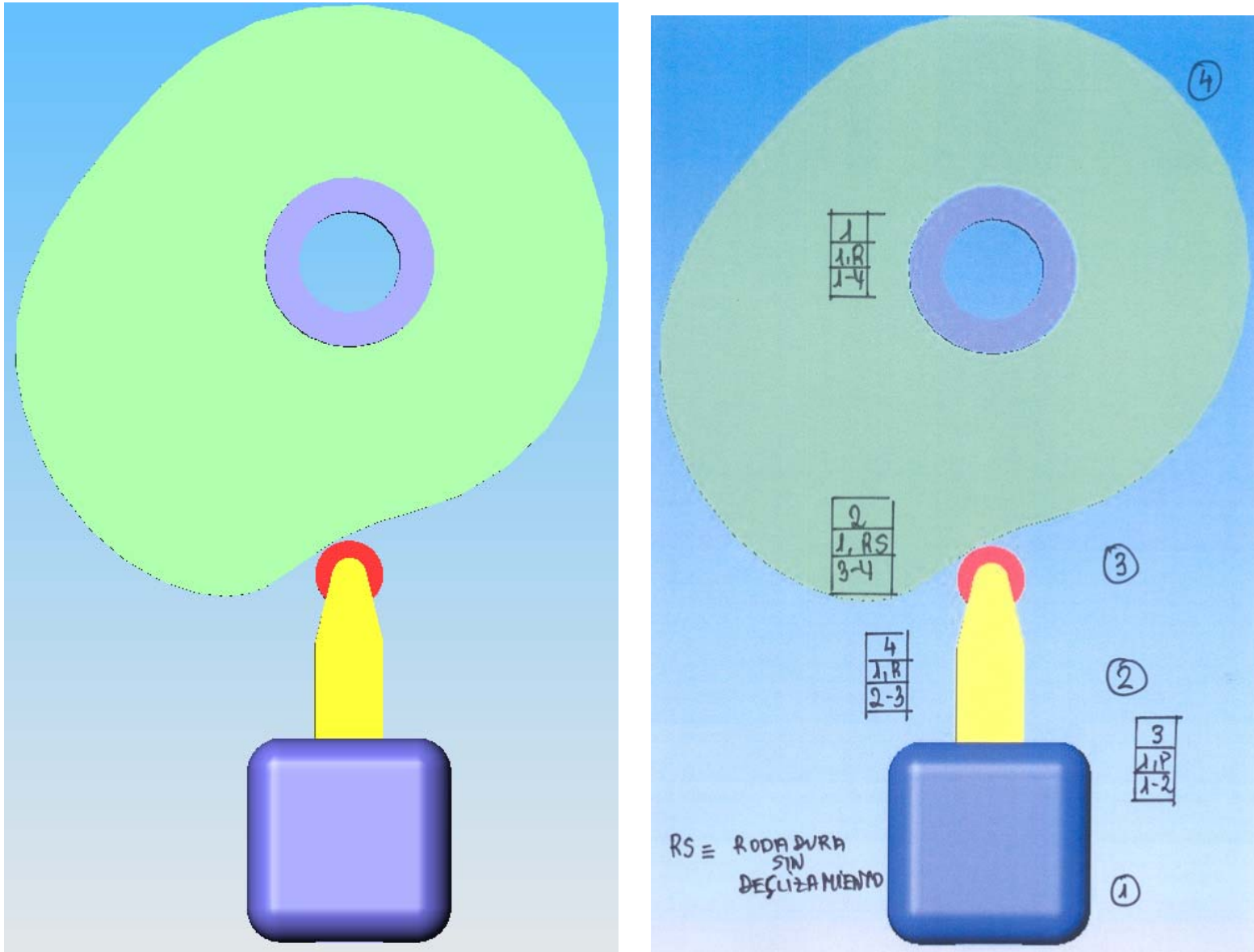
MOVILIDAD MECANISMO SOBRESRESTRINGIDO

$$M = 6 * (4 - 5 - 1) + 1 + 1 + 4 + 1 + 4 = -1$$

MOVILIDAD MECANISMO AUTOALINEADOR

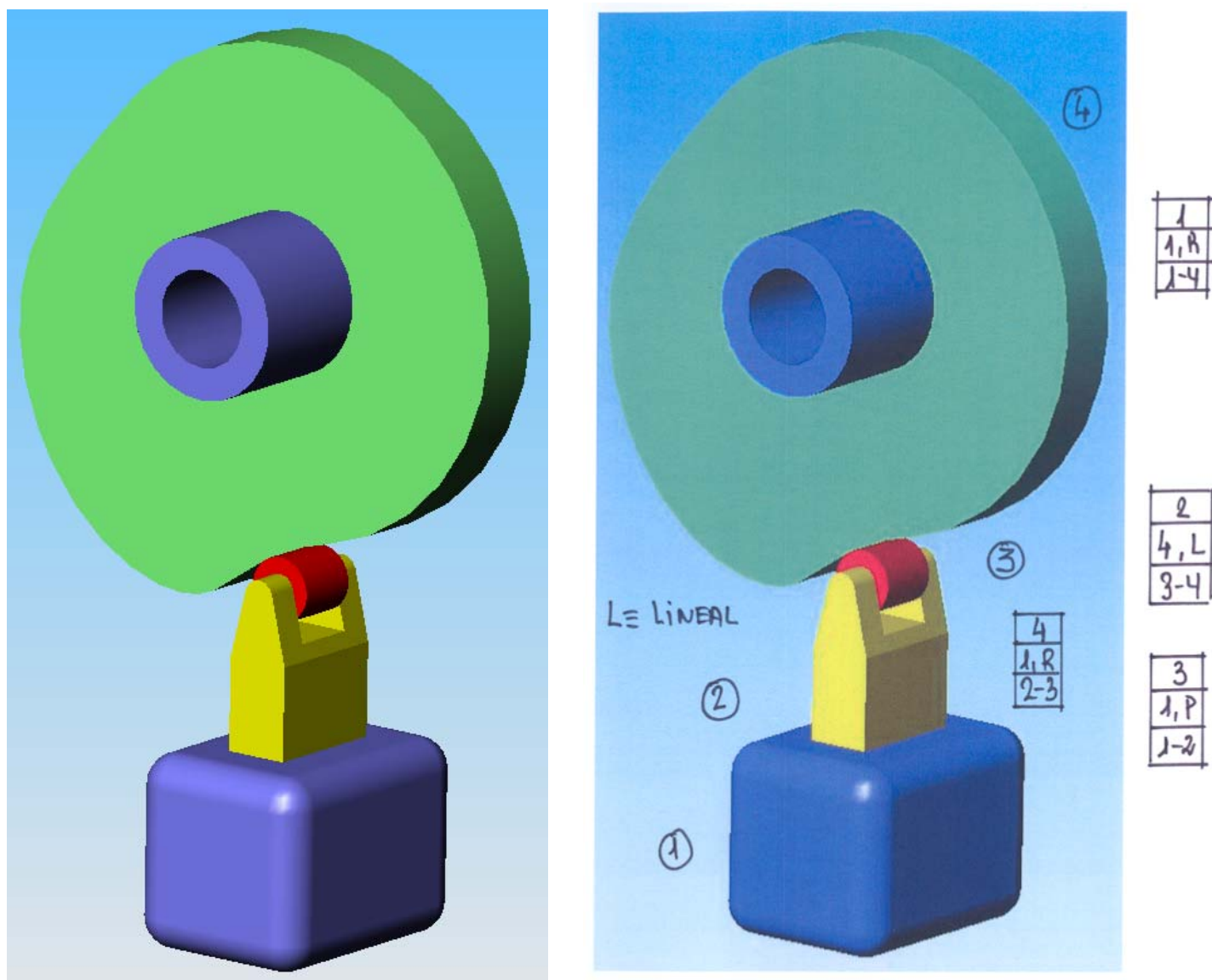
$$M = 6 * (4 - 5 - 1) + 1 + 1 + 5 + 1 + 5 = 1$$

LEVA CON SEGUIDOR DE RODILLO COMO MECANISMO PLANO



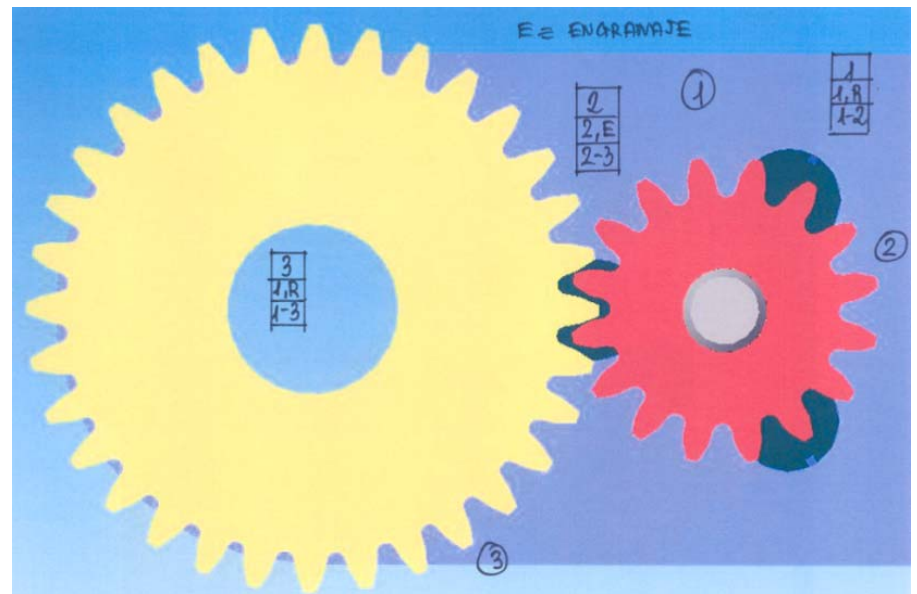
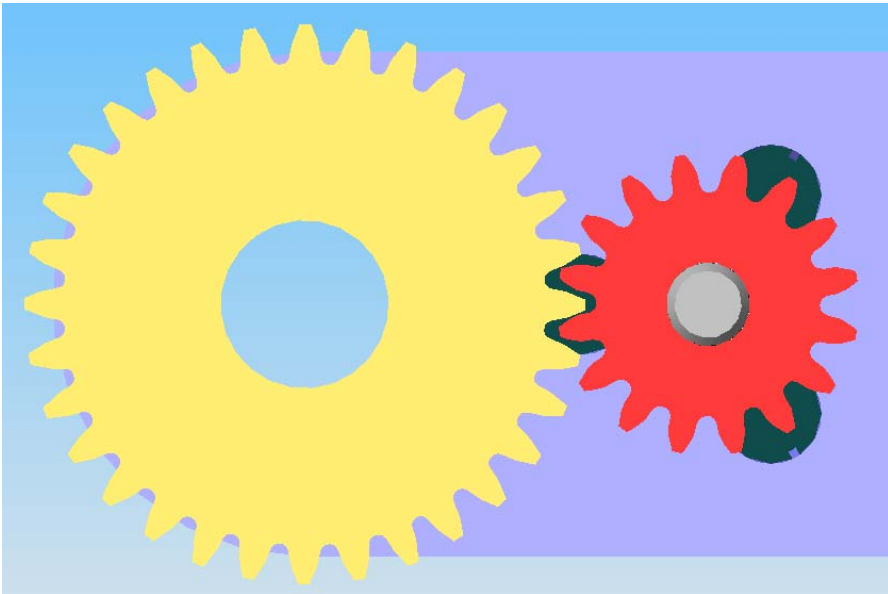
$$M = 3 * (4 - 4 - 1) + 1 + 1 + 1 + 1 = 1$$

LEVA CON SEGUIDOR DE RODILLO COMO MECANISMO ESPACIAL

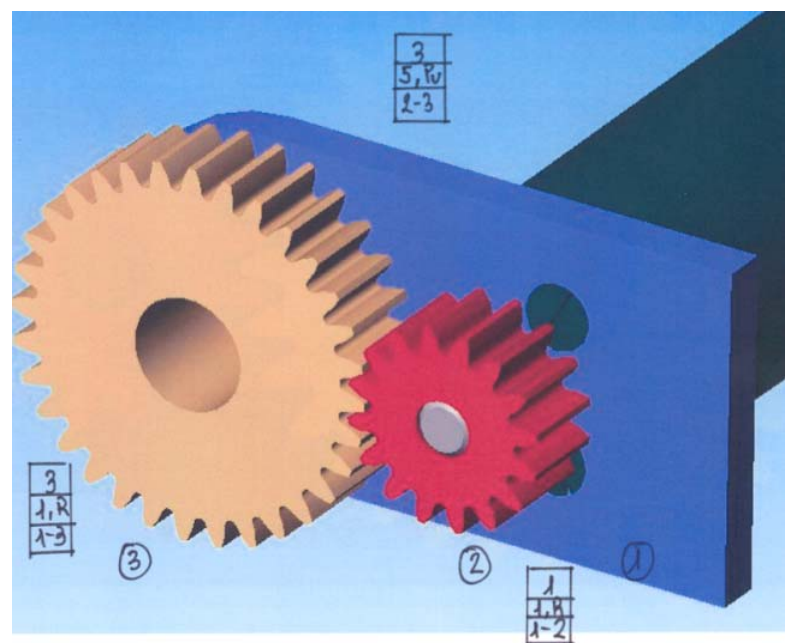
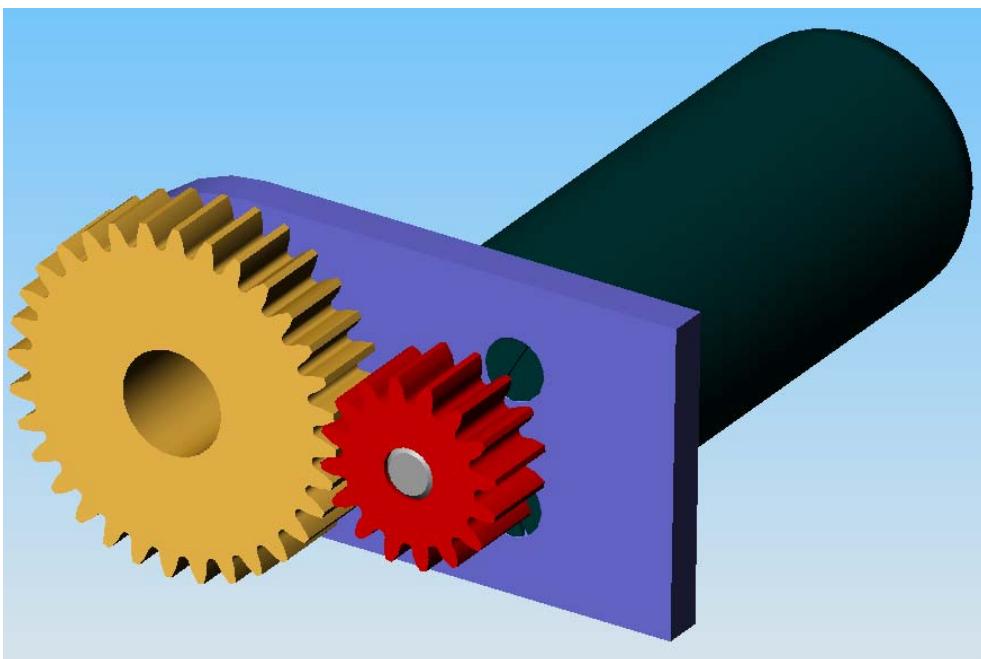


$$M = 6 * (4 - 4 - 1) + 1 + 4 + 1 + 1 = 1$$

ENGRANAJES COMO MECANISMO PLANO

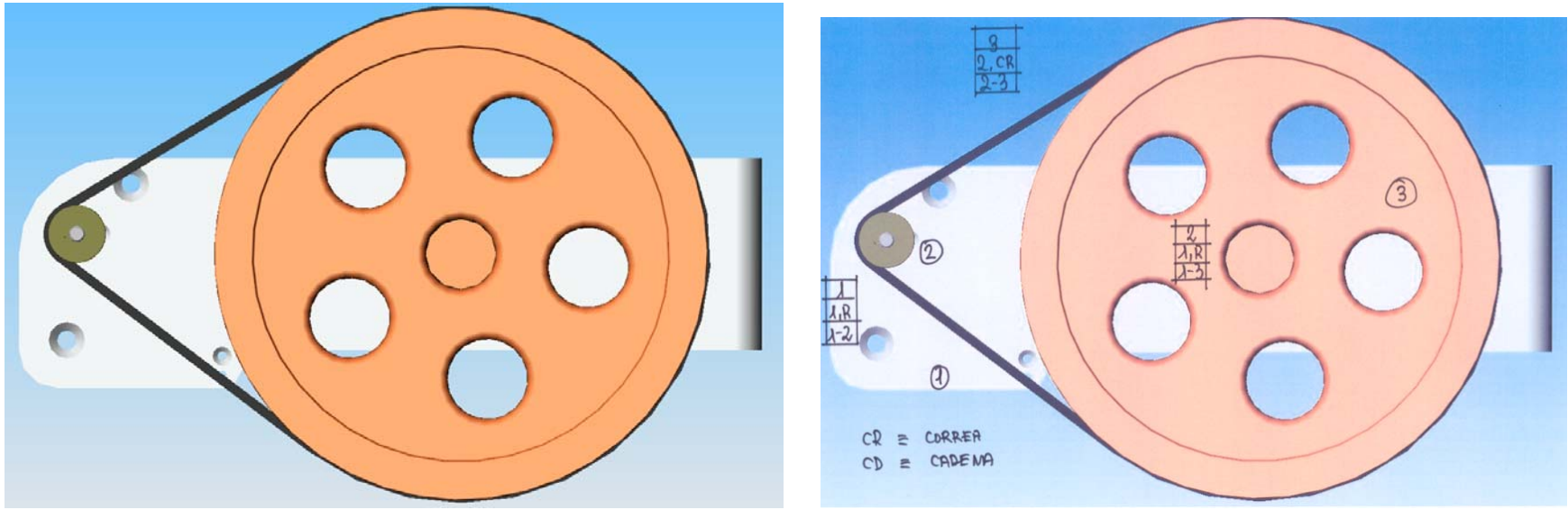


$$M = 3 * (3 - 3 - 1) + 1 + 1 + 2 = 1$$



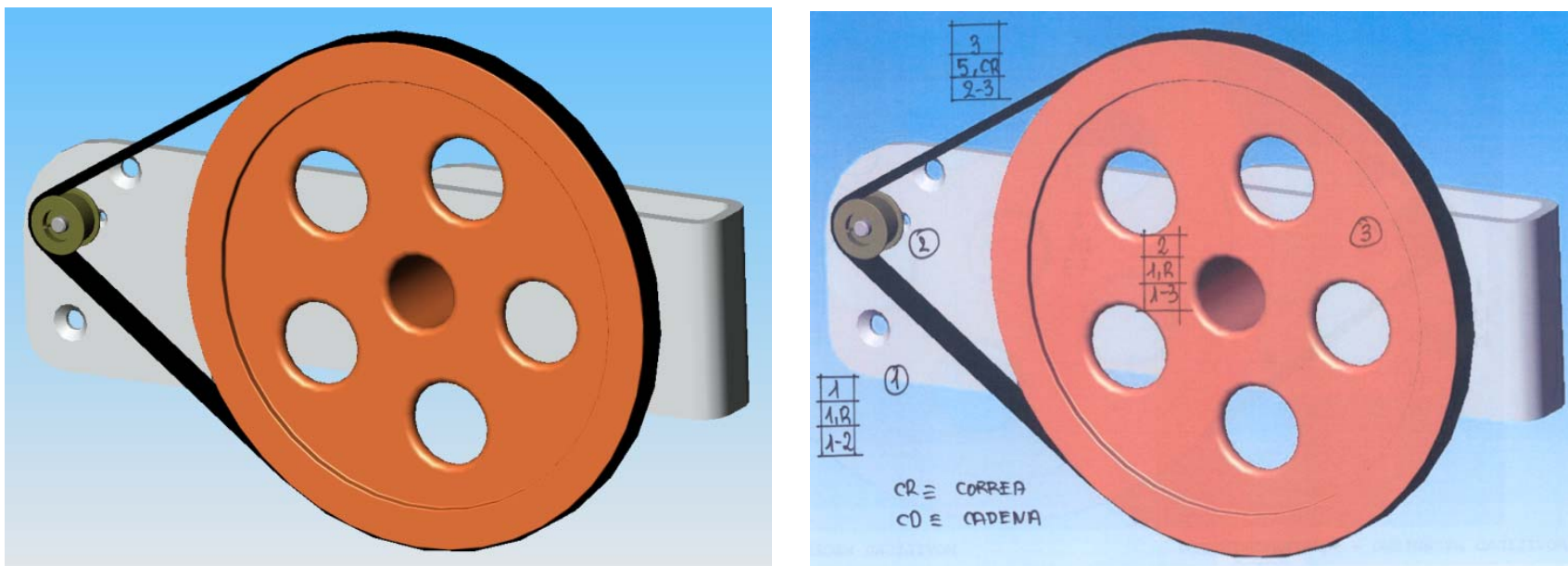
$$M = 6 * (3 - 3 - 1) + 1 + 1 + 5 = 1$$

CORREAS O CADENAS COMO MECANISMO PLANO



$$M = 3 * (3 - 3 - 1) + 1 + 1 + 2 = 1$$

CORREAS O CADENAS COMO MECANISMO ESPACIAL



$$M = 6 * (3 - 3 - 1) + 1 + 1 + 5 = 1$$