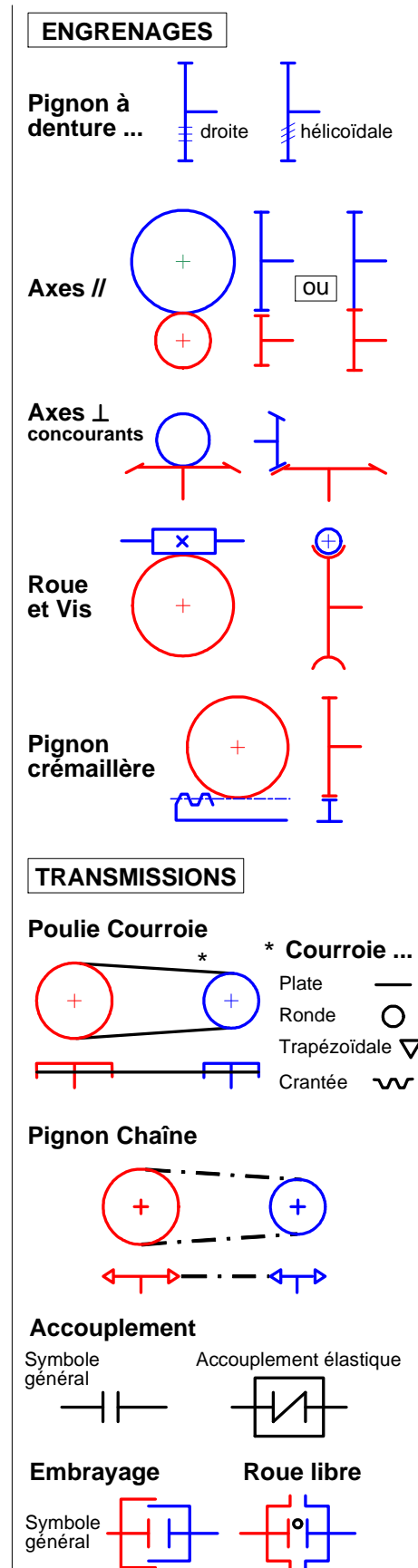
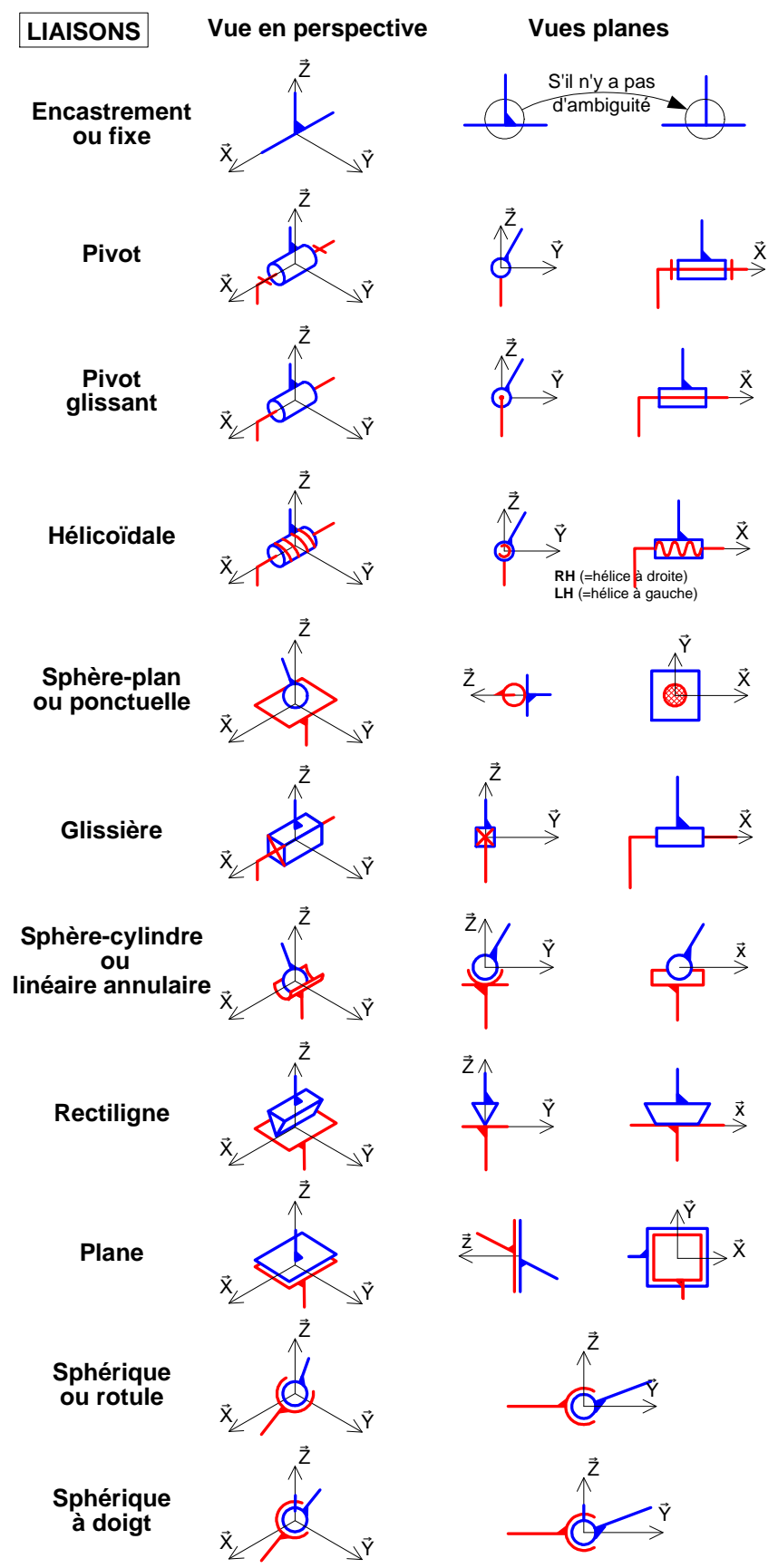


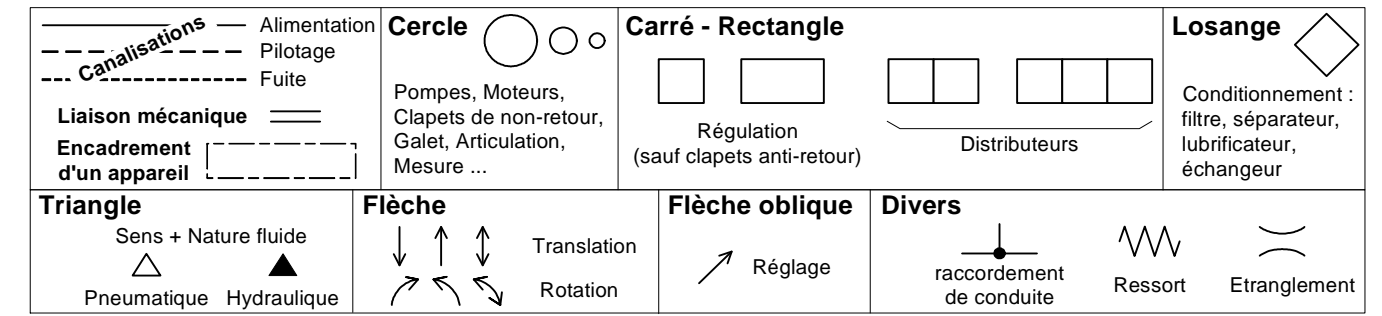


**SYMBOLES HYDRO-PNEUMATIQUES**

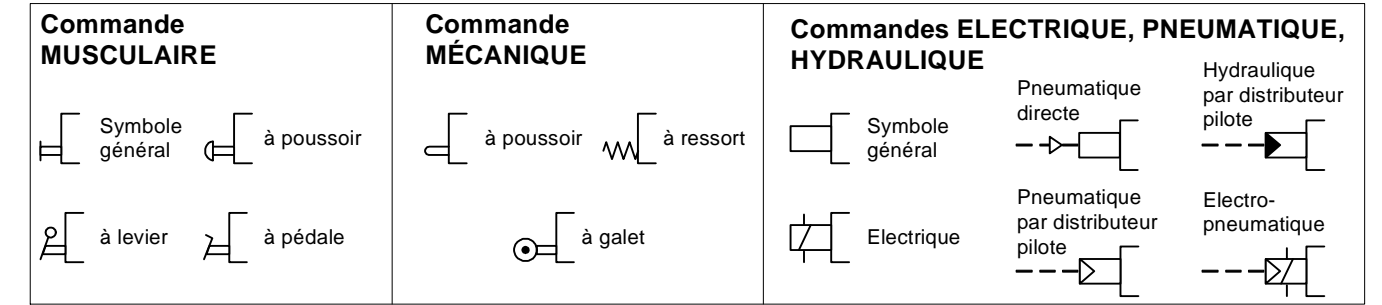
**SYMBOLES DES ÉLÉMENTS MÉCANIQUES**



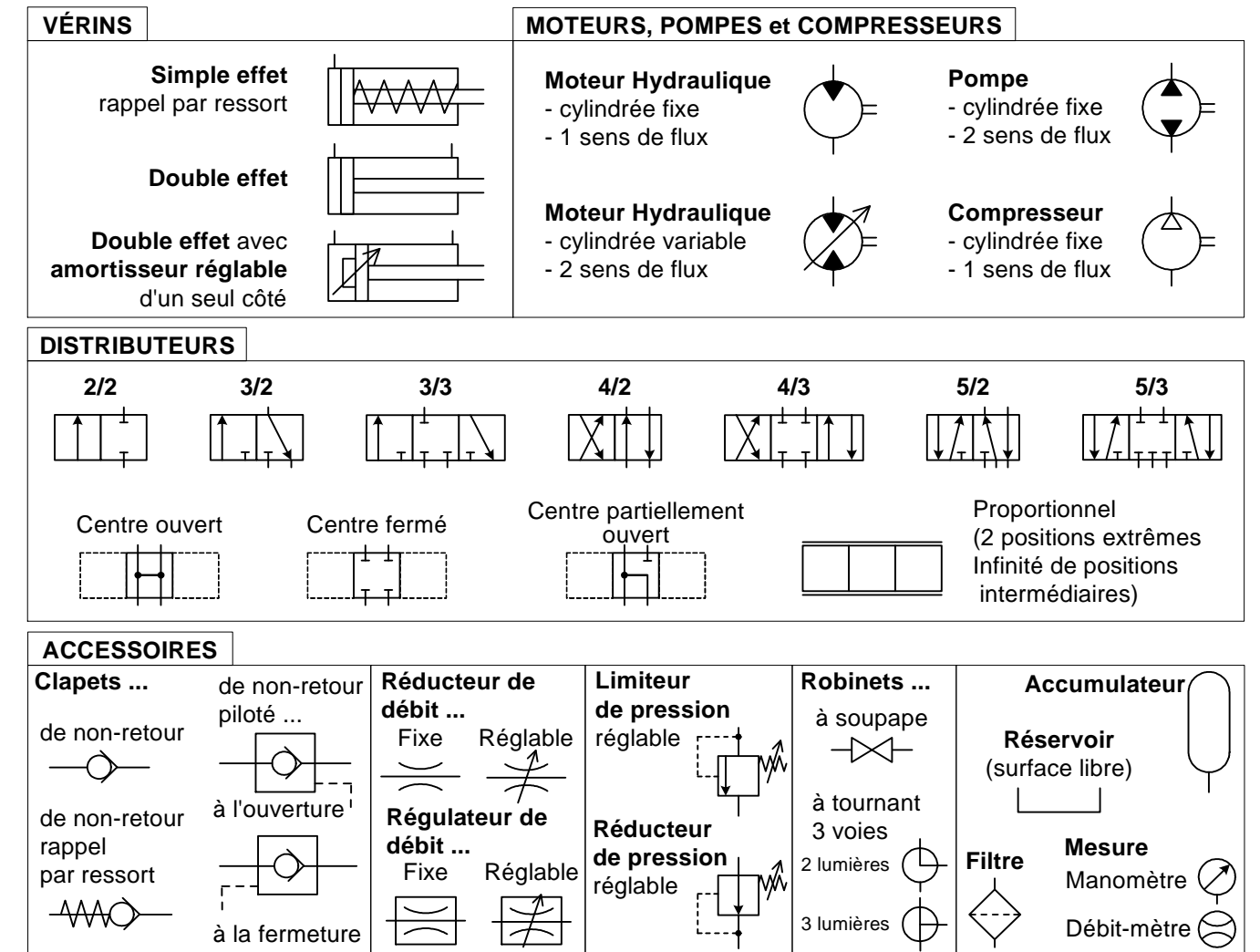
**Signes de base**



**Commandes**



**Actionneurs - Préactionneurs - Accessoires**





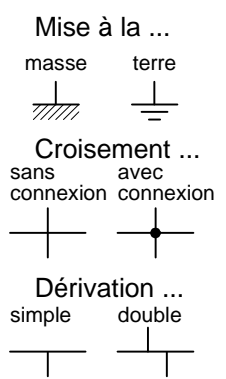
*Ne pas emporter ce document,  
le laisser en salle de préparation*

### SYMBOLES ÉLECTRIQUES

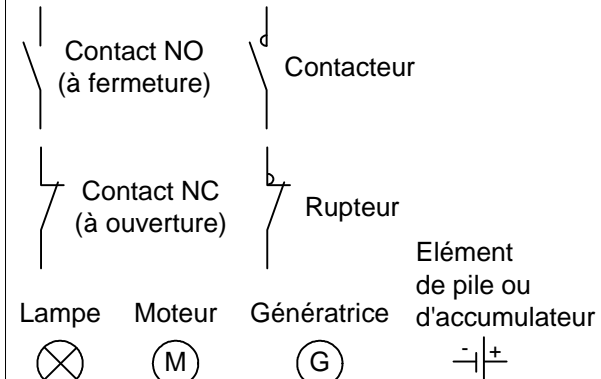
#### COURANTS, CONDUCTEURS, CONNEXIONS

Courant ...  
continu DC  
alternatif AC

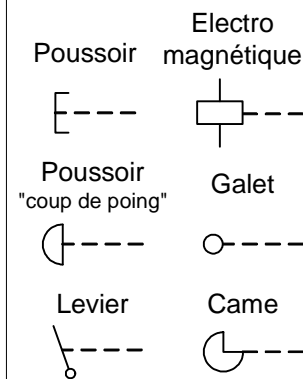
Conducteur ...  
circuit de ...  
puissance   
commande



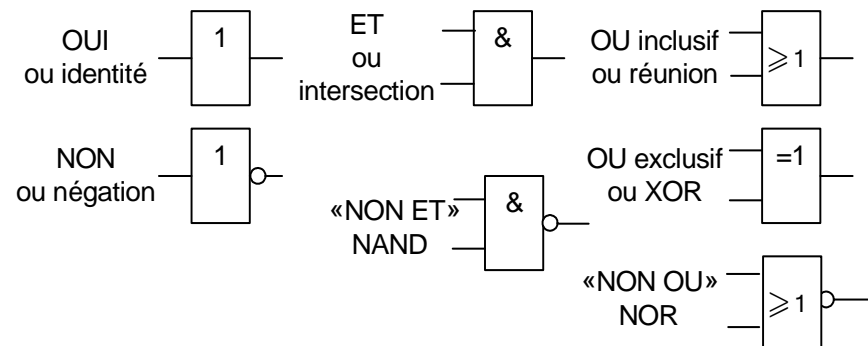
#### COMPOSANTS



#### COMMANDE



### FONCTIONS LOGIQUES



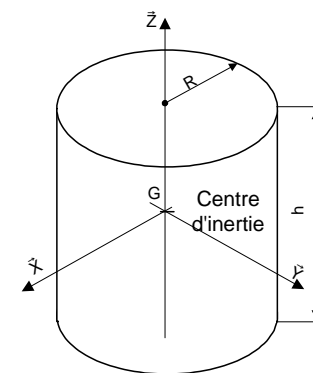
### TRANSFORMÉES DE LAPLACE

Fonctions temporelles	Transformée de LAPLACE	Fonctions temporelles	Transformée de LAPLACE
Impulsion unitaire (Dirac) $\delta(t)$	1	Sinus $u(t) \cdot \sin \omega t$	$\frac{\omega}{p^2 + \omega^2}$
Echelon unitaire (dit "de position") $u(t)$ $u(t) = 1$ si $t > 0$	$\frac{1}{p}$	Cosinus $u(t) \cdot \cos \omega t$	$\frac{p}{p^2 + \omega^2}$
Rampe unitaire (dite "de vitesse") $u(t) \cdot t$	$\frac{1}{p^2}$	Sinus amorti $u(t) \cdot e^{-at} \cdot \sin \omega t$	$\frac{\omega}{(p+a)^2 + \omega^2}$
Polynôme $u(t) \cdot t^n$	$\frac{n!}{p^{n+1}}$	Cosinus amorti $u(t) \cdot e^{-at} \cdot \cos \omega t$	$\frac{p+a}{(p+a)^2 + \omega^2}$
Exponentielle $u(t) \cdot e^{-at}$	$\frac{1}{p+a}$		
$u(t) \cdot t \cdot e^{-at}$	$\frac{1}{(p+a)^2}$		
$u(t) \cdot \frac{t^{n-1}}{(n-1)!} \cdot e^{-at}$	$\frac{1}{(p+a)^n}$		

### MATRICES D'INERTIE DE VOLUMES ÉLÉMENTAIRES

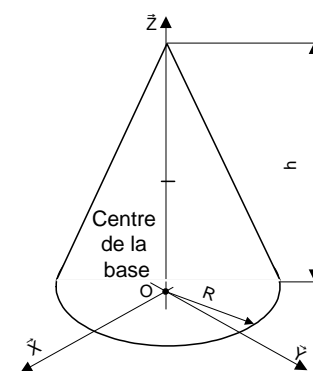
$m$  = masse du solide étudié

#### CYLINDRE de révolution



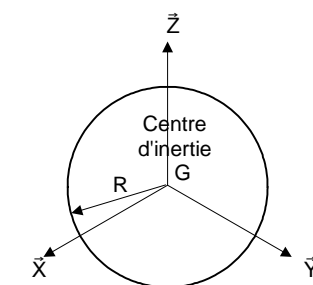
$$\begin{bmatrix} \frac{mR^2}{4} + \frac{mh^2}{12} & 0 & 0 \\ 0 & \frac{mR^2}{4} + \frac{mh^2}{12} & 0 \\ 0 & 0 & \frac{mR^2}{2} \end{bmatrix}_{(G, \vec{x}, \vec{y}, \vec{z})}$$

#### CÔNE de révolution



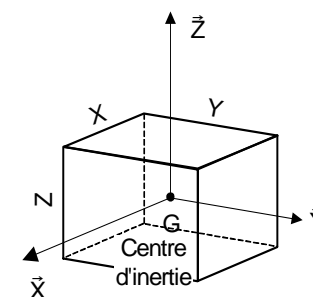
$$\begin{bmatrix} \frac{3mR^2}{20} + \frac{mh^2}{10} & 0 & 0 \\ 0 & \frac{3mR^2}{20} + \frac{mh^2}{10} & 0 \\ 0 & 0 & \frac{3mR^2}{10} \end{bmatrix}_{(O, \vec{x}, \vec{y}, \vec{z})}$$

#### SPHÈRE



$$\begin{bmatrix} \frac{2mR^2}{5} & 0 & 0 \\ 0 & \frac{2mR^2}{5} & 0 \\ 0 & 0 & \frac{2mR^2}{5} \end{bmatrix}_{(G, \vec{x}, \vec{y}, \vec{z})}$$

#### PARALLÉLÉPIPÈDE



$$\begin{bmatrix} \frac{m(Y^2 + Z^2)}{12} & 0 & 0 \\ 0 & \frac{m(X^2 + Z^2)}{12} & 0 \\ 0 & 0 & \frac{m(X^2 + Y^2)}{12} \end{bmatrix}_{(G, \vec{x}, \vec{y}, \vec{z})}$$