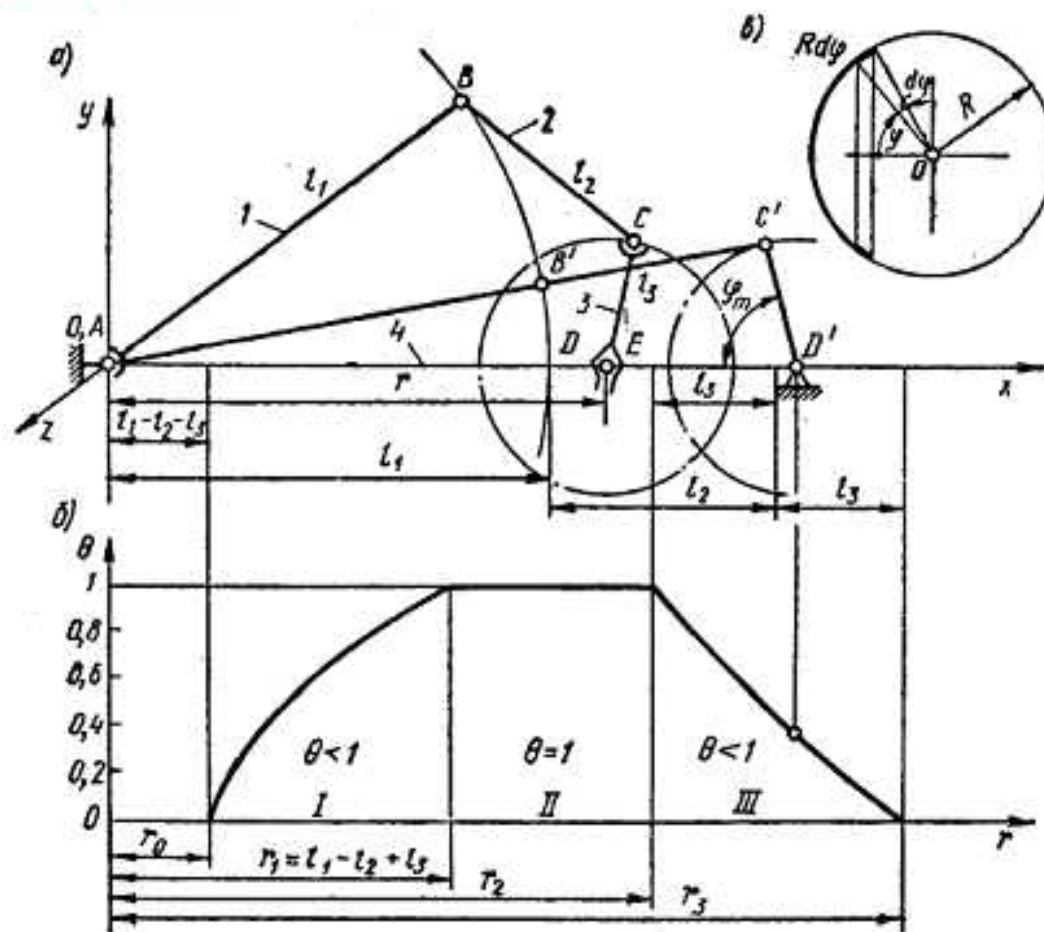




(

).
.

6.1-расм а да $p=AD'$ учун $\cos\varphi_m \approx 0,24$ ва $K_\theta = 0,38$. Бўғинлари 6.1-расм, а да тасвирланганидек ўлчамларга ега бўлган манипулятор учун $K_\theta = \theta(p)$ боғлиқлик графиги 6.1-расм, б да келтирилган. Бундай графиклар mavjud манипуляторни тадқиқ этиш учун гина емас, балки олдиндан белгиланган шартлар асосида манипуляторларнинг кинематик схемаларини лойихалаш учун ҳам зарур.



6.1-расм.

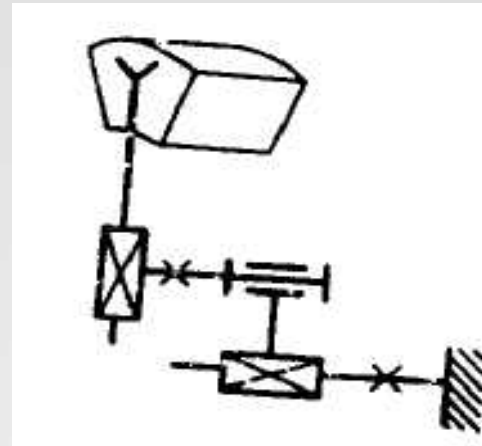
• 2.

«

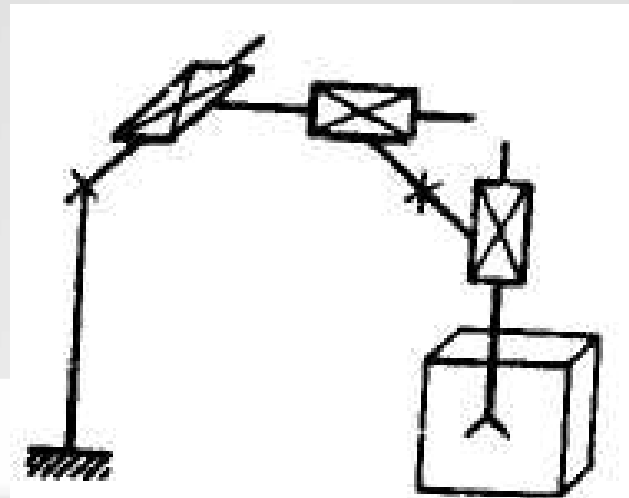
»

• 3

• 6.2-



6.3-



• C

$(\alpha, \delta, \varphi)$

3

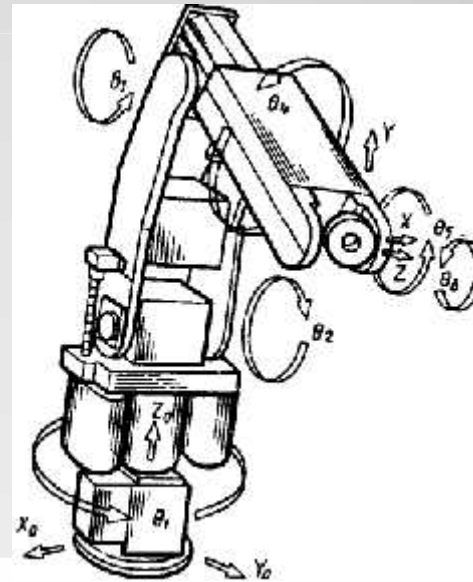
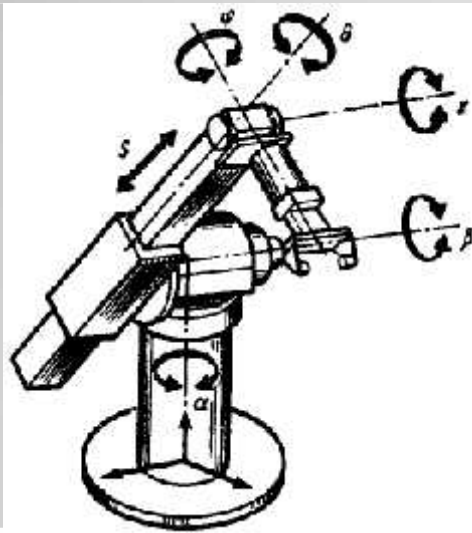
(θ, γ, β)

6.4-

. 6.5-

(θ_1, θ_2)

()



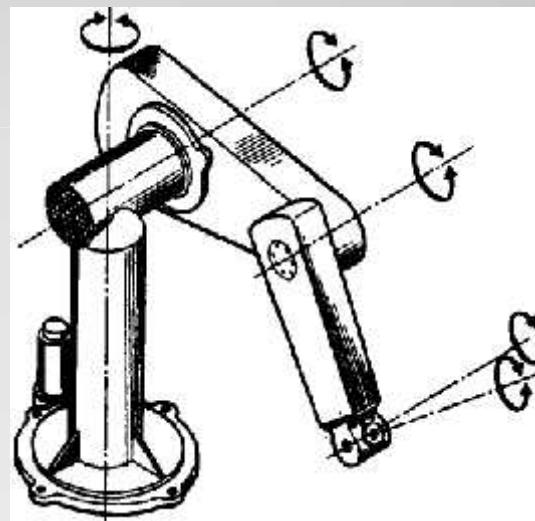
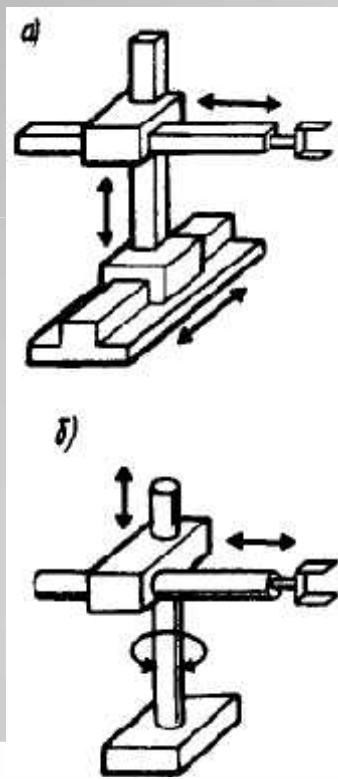
• 6.6-

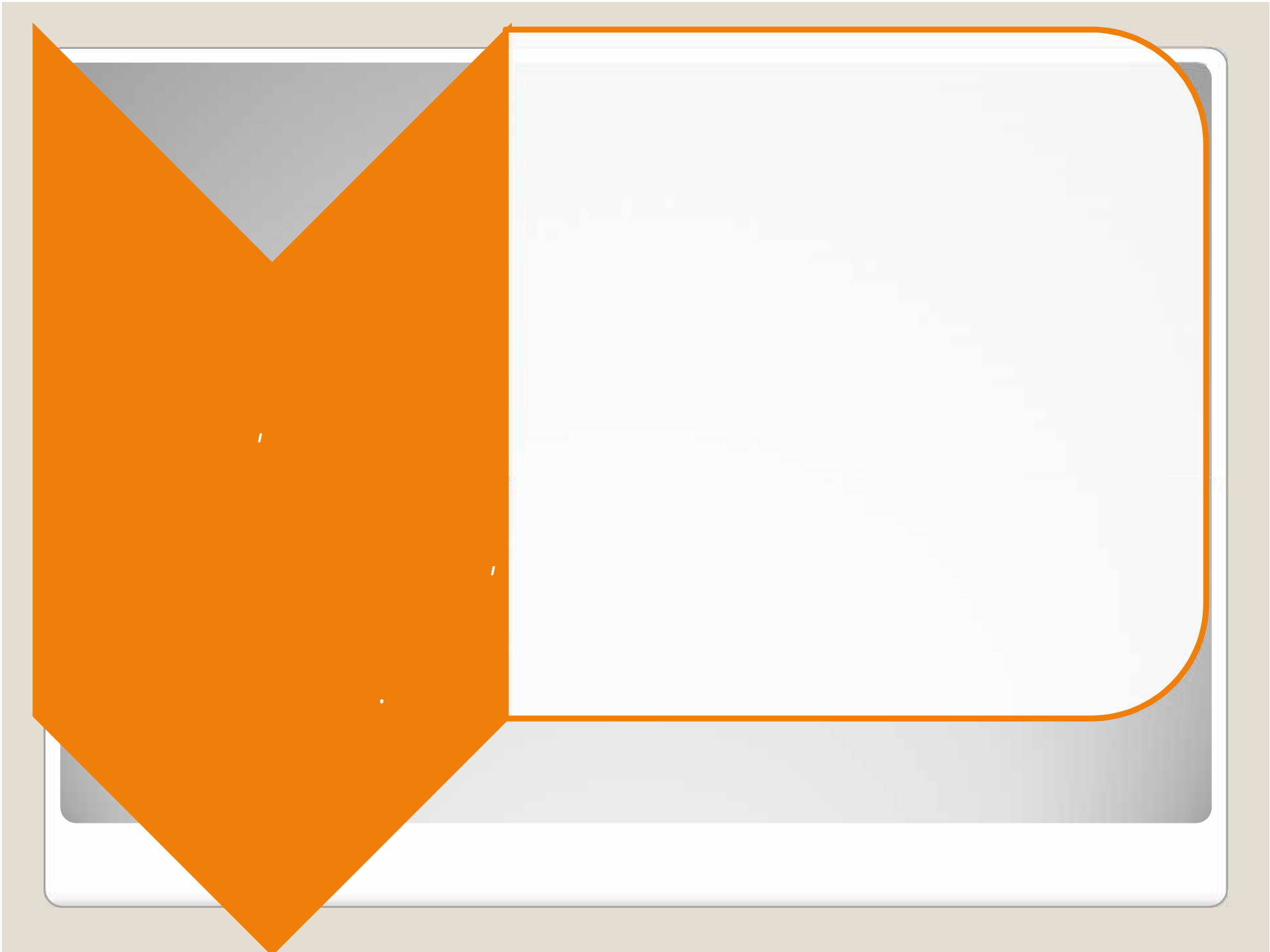
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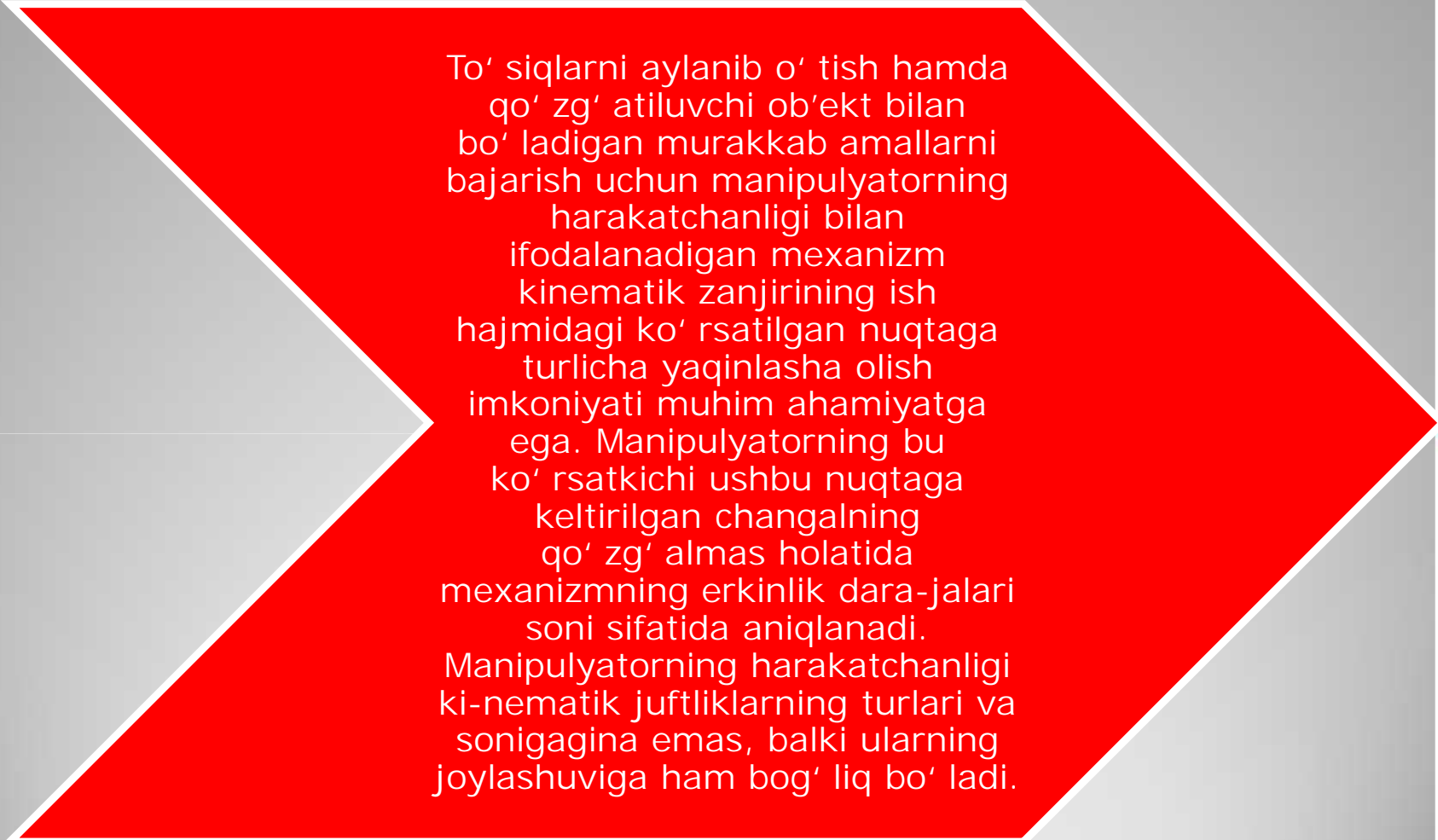
(),

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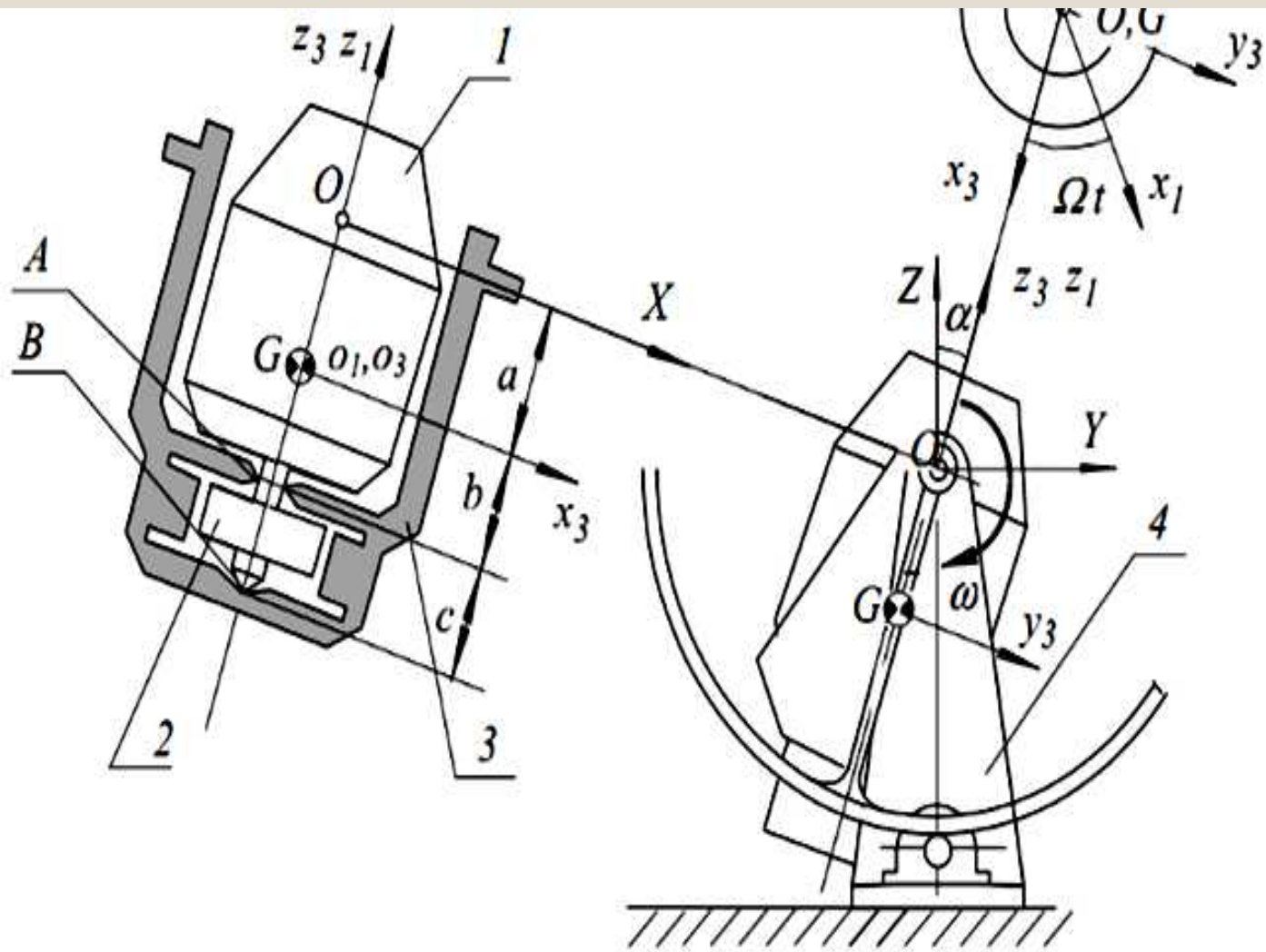
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To' siqlarni aylanib o' tish hamda
qo' zg' atiluvchi ob'ekt bilan
bo' ladigan murakkab amallarni
bajarish uchun manipulyatorning
harakatchanligi bilan
ifodalanadigan mexanizm
kinematik zanjirining ish
hajmidagi ko' rsatilgan nuqtaga
turlicha yaqinlasha olish
imkoniyati muhim ahamiyatga
ega. Manipulyatorning bu
ko' rsatkichi ushbu nuqtaga
keltirilgan changalning
qo' zg' almas holatida
mexanizmning erkinlik dara-jalari
soni sifatida aniqlanadi.
Manipulyatorning harakatchanligi
ki-nematik juftliklarning turlari va
sonigagina emas, balki ularning
joylashuviga ham bog' liq bo' ladi.



6.7-