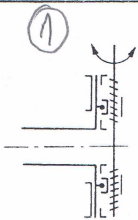
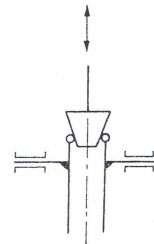
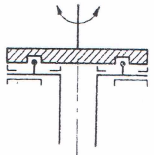
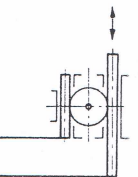
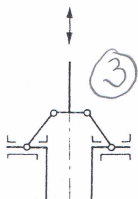
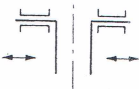
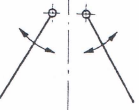
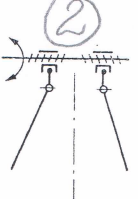
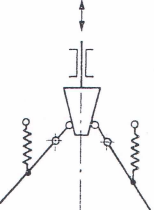
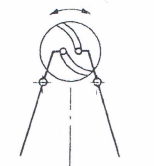
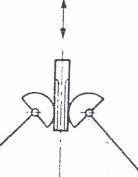
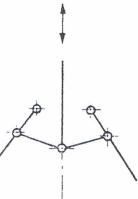
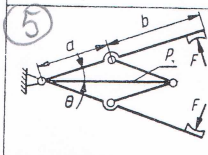
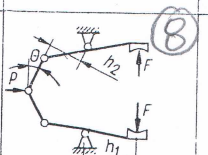
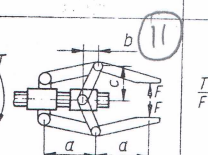
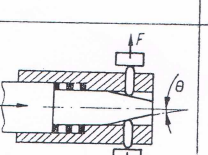
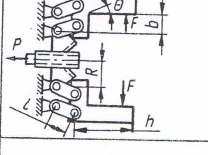
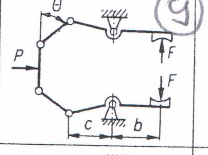
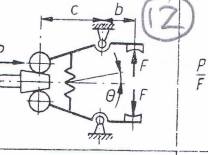
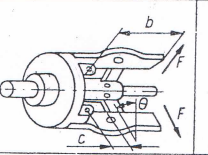
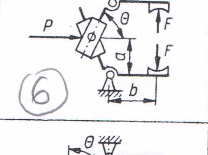
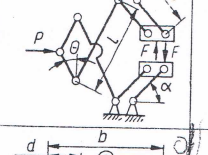
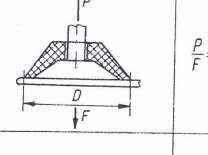
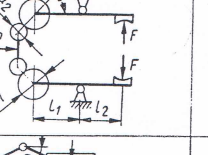
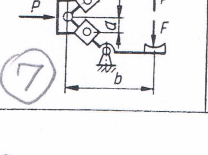
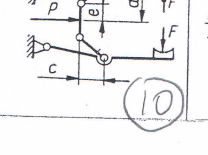
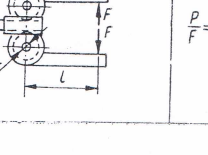
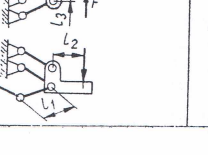


TABLICA 4-2. UKŁADY PRZENIESIENIA NAPĘDÓW W CHWYTAKACH

Układ przeniesienia napędu					Sposób przemieszczania końcówek chwytanych
Śrubowy	Klinowy	Krzywkowy	Zębaty	Dzwigniowy	
					 Równoległy  Niżkowy
					

TABLICA 4-3. PRZYKŁADY KINEMATYCZNYCH ROZWIĄZAŃ CHWYTAKÓW

Schemat kinematyczny	Współczynnik K	Schemat kinematyczny	Współczynnik K	Schemat kinematyczny	Współczynnik K	Schemat kinematyczny	Współczynnik K
	$\frac{P}{F} = \frac{a+b}{a \sin \theta}$		$\frac{P}{F} = \frac{h_1}{h_2}$		$\frac{T}{F} = \frac{2ab}{\pi c}$		$\frac{P}{F} = 3 \tan \theta$
	$\frac{P}{F} = \frac{2l}{R} \cos \theta$		$\frac{P}{F} = \frac{2b}{c} \tan \theta$		$\frac{P}{F} = \frac{2b}{c} \tan \theta$		$\frac{P}{F} = \frac{3b}{c} \tan \theta$
	$\frac{P}{F} = \frac{2b}{a} \tan \theta$		$\frac{P}{F} = \frac{b \sin \theta \cdot \sin \alpha}{1 \sin \alpha \cos(\alpha + \theta)}$		$\frac{P}{F} = \frac{4}{\pi D^2}$		$\frac{P}{F} = 2 \frac{l_2 \cos \theta}{l_1 \sin \theta}$
	$\frac{P}{F} = \frac{2b}{a} \cos^2 \theta$		$\frac{P}{F} = \frac{2bc}{e(d+c)}$		$\frac{P}{F} = \frac{4l}{d}$		$\frac{P}{F} = \frac{l_2}{l_3 \cos^2 \theta}$