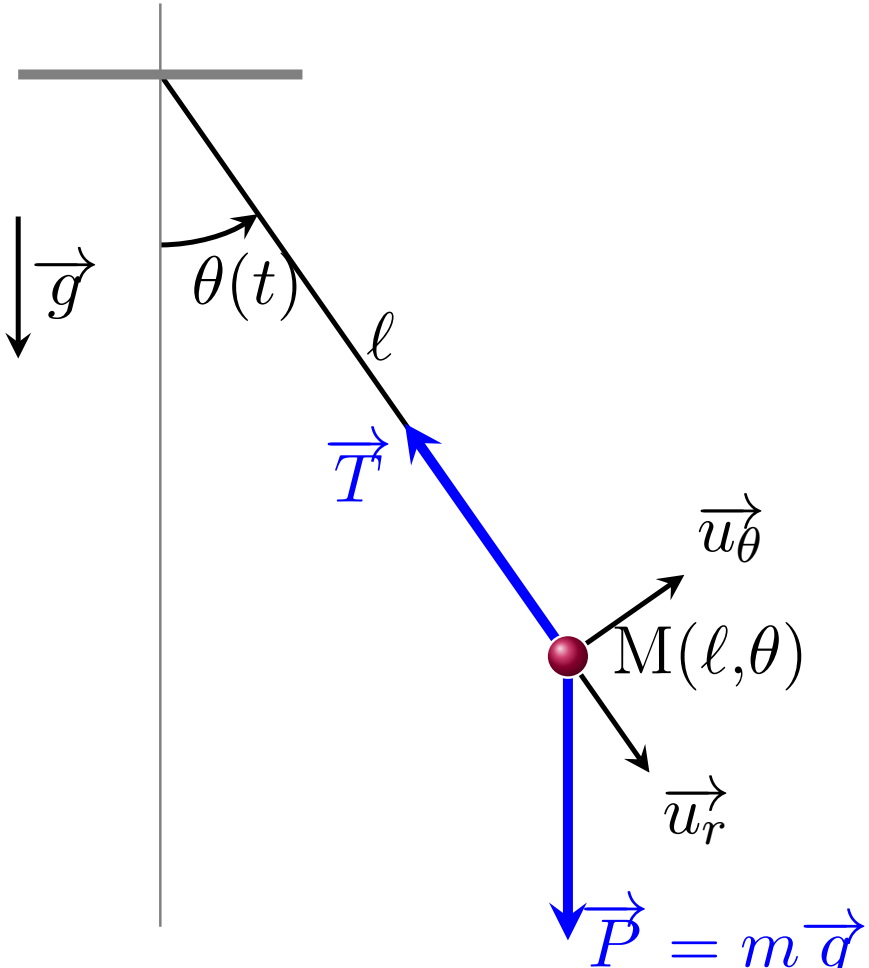
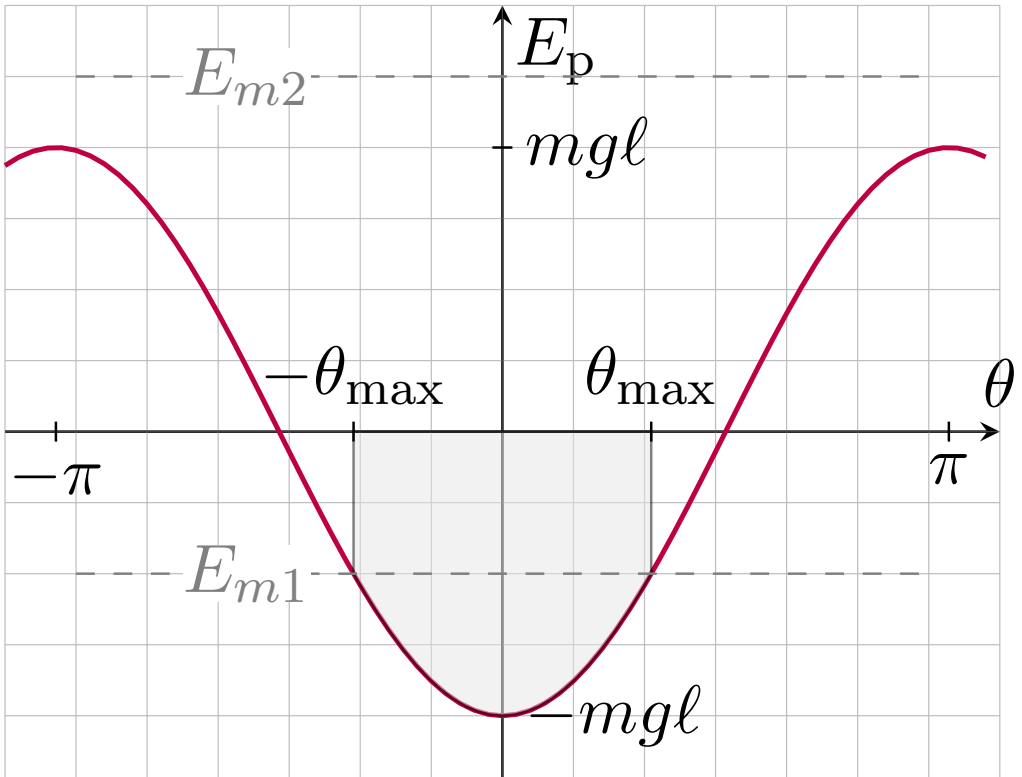
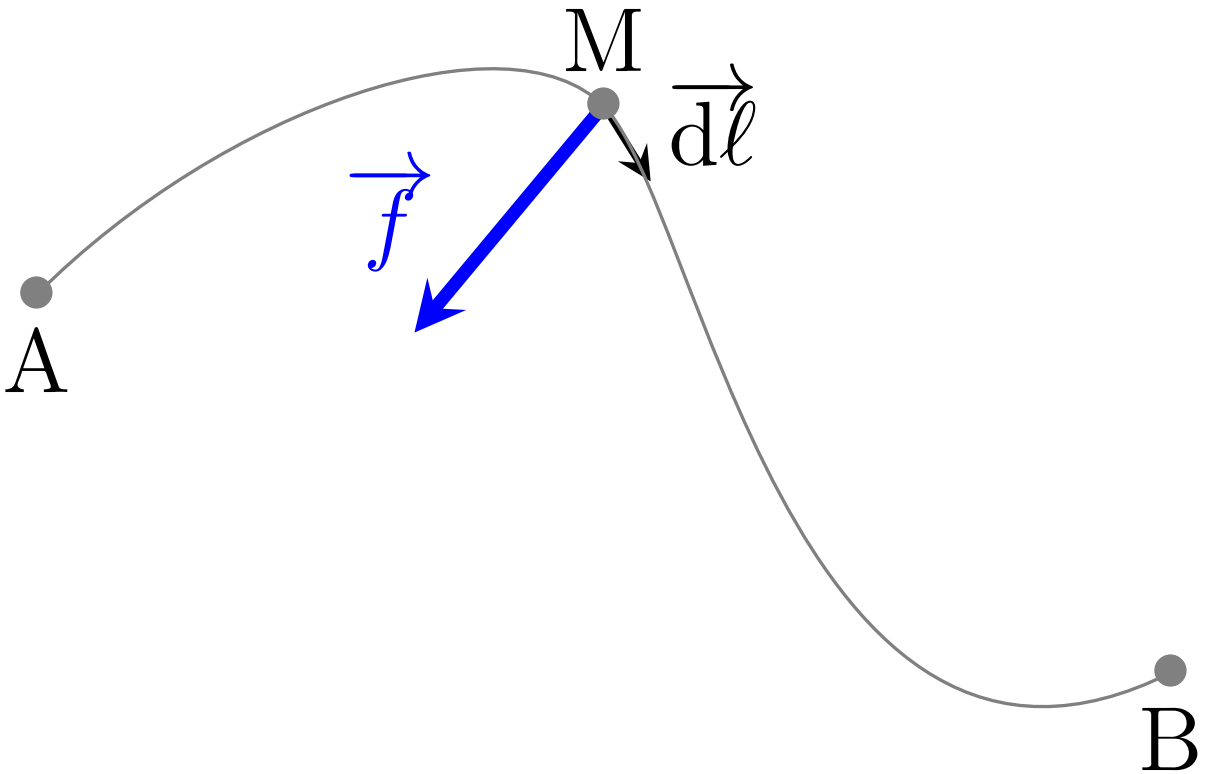
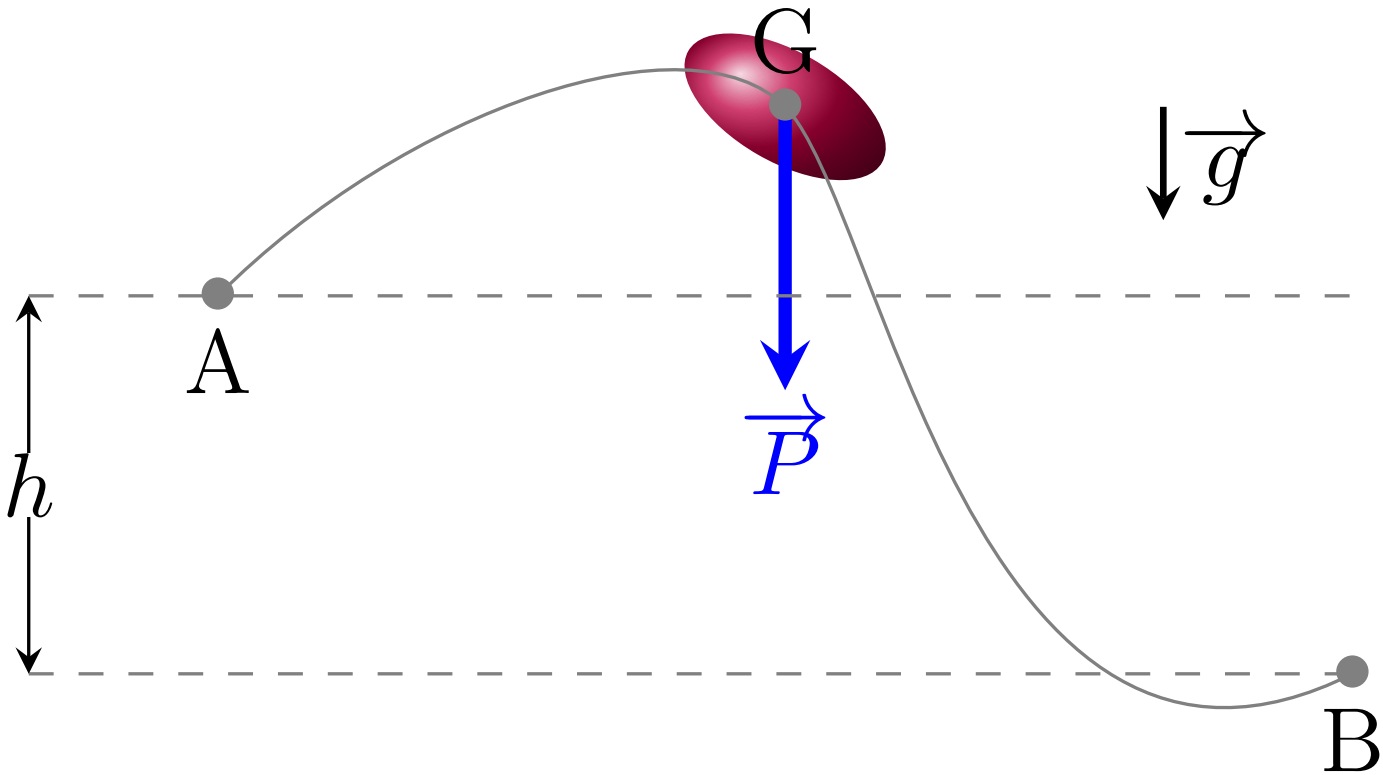
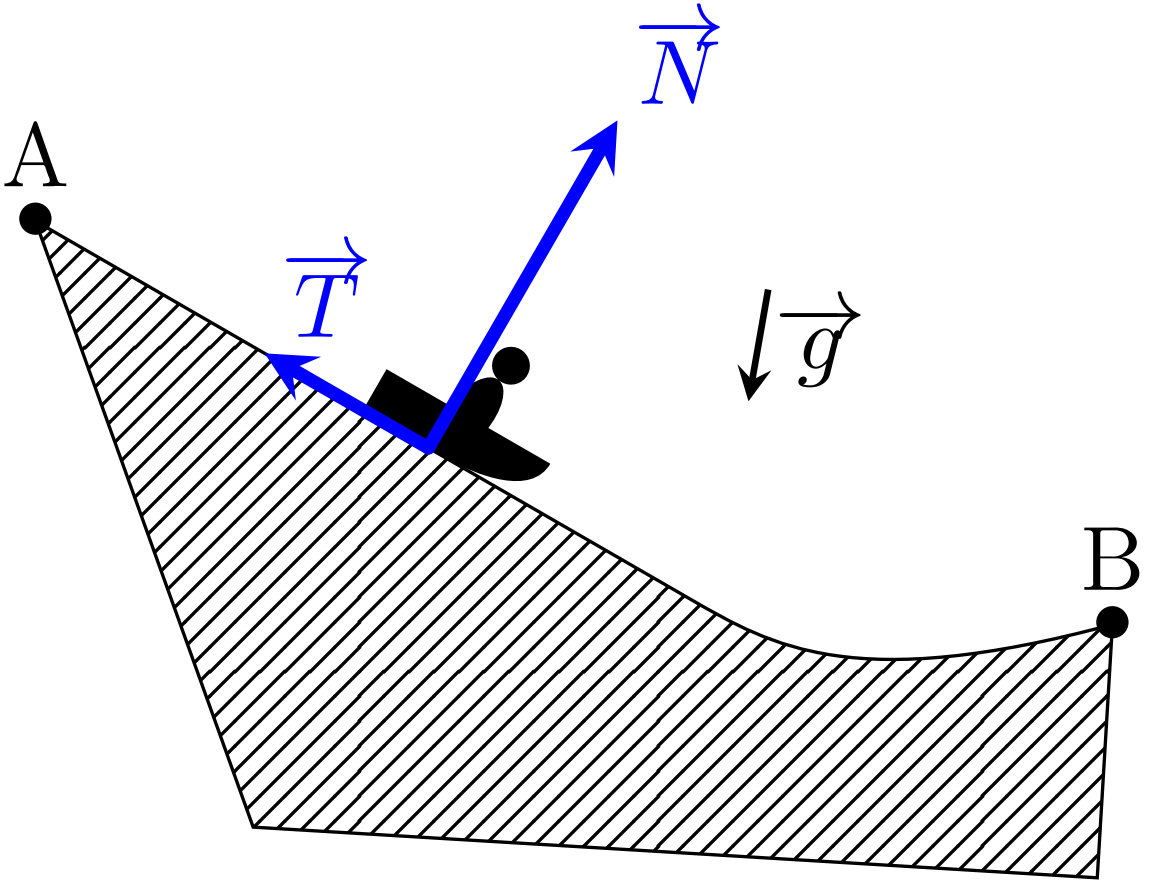
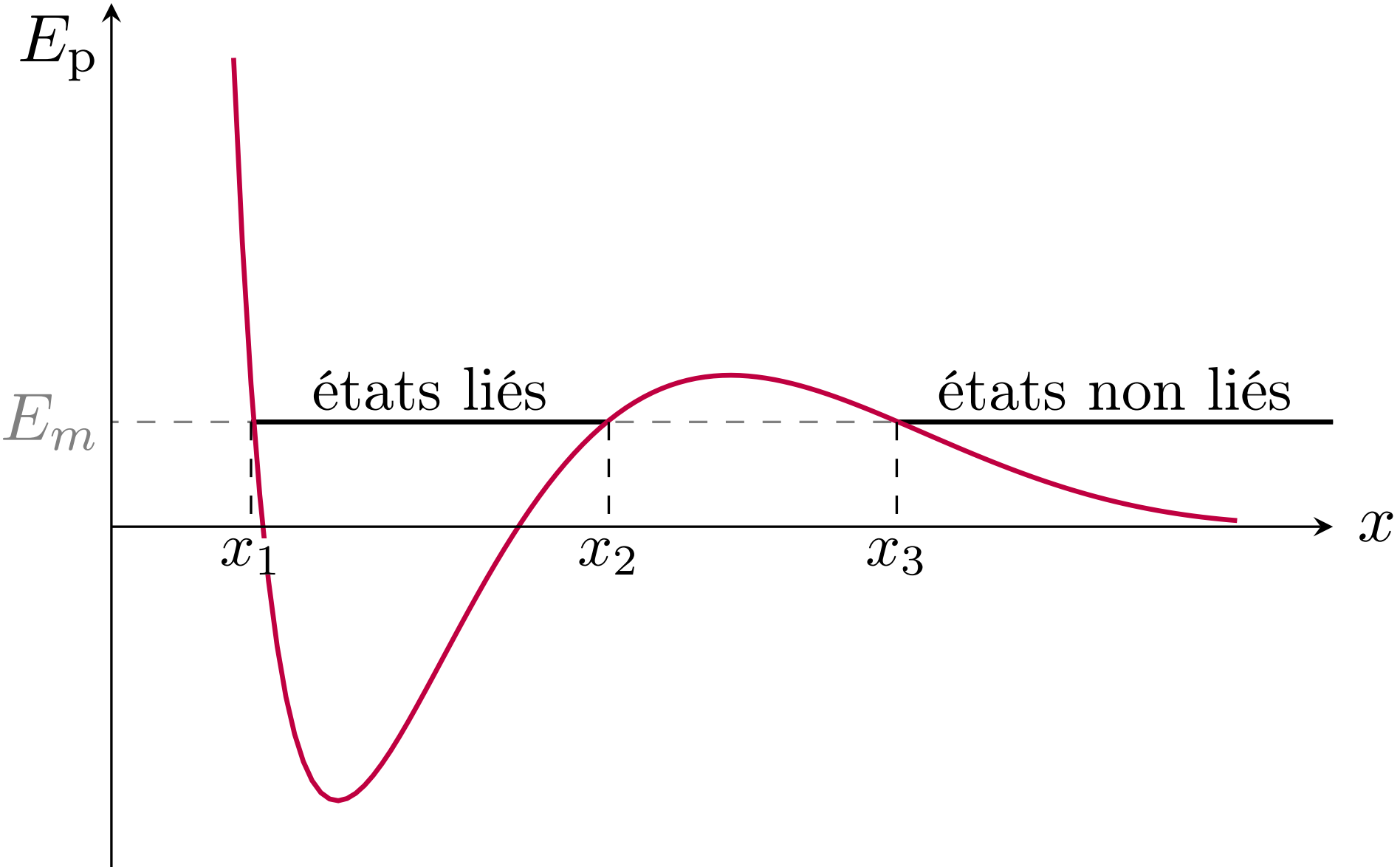

$\vec{g}$
$\theta(t)$
$\ell$
$\vec{T}$
$\vec{u_\theta}$
M($\ell$,$\theta$)
$\vec{u_r}$
$\vec{P} = m\vec{g}$

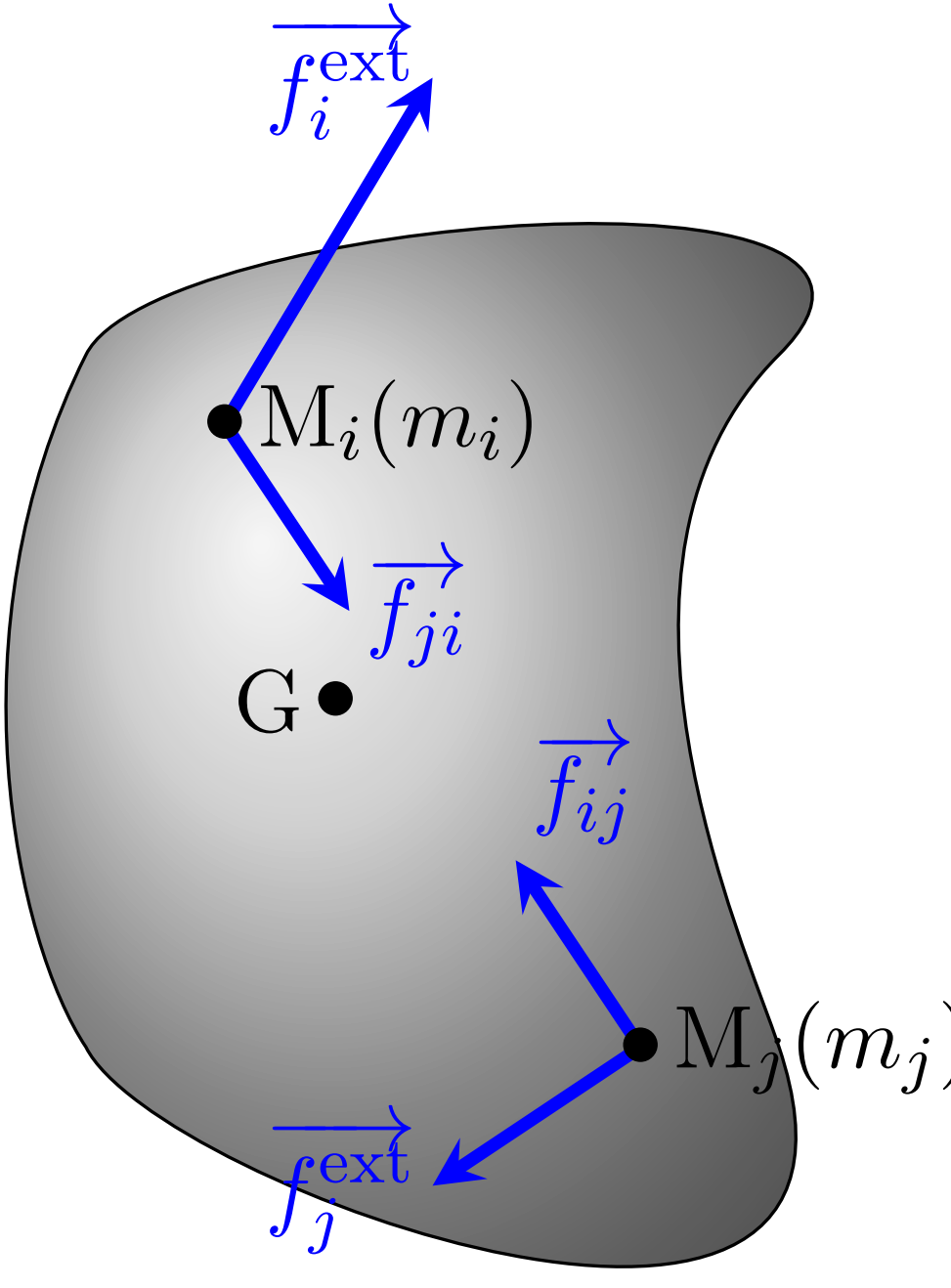

$E_{\mathrm{p}}$
$E_{m2}$
$mg\ell$
$-\theta_{\max}$
$\theta_{\max}$
$\theta$
$-\pi$
$\pi$
$E_{m1}$
$-mg\ell$


M
$\overrightarrow{d\ell}$
$\overrightarrow{f}$
A
B


G
$\vec{g}$
A
$\vec{P}$
$h$
B


$\overrightarrow{N}$
A
$\overrightarrow{T}$
$\overrightarrow{g}$
B


$E_\mathrm{p}$
$E_m$
états liés
états non liés
$x$
$x_1$
$x_2$
$x_3$


$\overrightarrow{f_i^{\text{ext}}}$
$\mathrm{M}_i(m_i)$
$\overrightarrow{f_{ji}}$
G
$\overrightarrow{f_{ij}}$
$\mathrm{M}_j(m_j)$
$\overrightarrow{f_j^{\text{ext}}}$