

## Symbols

$A_L$	link assortment
$C_{pi}$	degrees of constraint of <i>i</i> -type joint for a planar mechanism
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$D_V$	revolute joints vertical to ground
$D_H$	revolute joints horizontal to ground
$F$	degrees of freedom
$F_p$	degrees of freedom for a planar mechanism
$F_s$	degrees of freedom for a spatial mechanism
$G_p$	nonrevolute joints incident to two members with perpendicular axial direction
$G_e$	nonrevolute joints incident to two members with parallel axial direction and with external connection
$G_i$	nonrevolute joints incident to two members with parallel axial direction and with internal connection
$J_A$	cam joint
$J_C$	cylindrical joint
$J_F$	flat joint
$J_G$	gear joint
$J_J$	pin-in-slot joint
$J_O$	rolling joint
$J_P$	prismatic joint
$J_R$	revolute joint
$J_S$	spherical joint
$J_T$	upper stopping joint
$J_W$	wrapping joint
$J_X$	fixed joint
$K_A$	cam
$K_{Af}$	follower
$K_B$	belt
$K_C$	chain
$K_F$	frame, ground link
$K_G$	gear
$K_H$	screw
$K_I$	piston

$K_K$	sprocket
$K_{Li}$	kinematic link of type $i$ -type
$K_O$	roller
$K_P$	slider
$K_R$	rope
$K_S$	spring
$K_T$	actuator
$K_U$	pulley
$K_W$	wheel
$K_Y$	cylinder
$L_i$	link with $i$ incident joints
$m$	maximum number of joints incident to a link
$M_T$	topology matrix
$N_L$	number of links or members
$N_{Li}$	number of links with $i$ incident joints
$N_J$	number of joints
$N_{Ji}$	number of $i$ -type joints

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