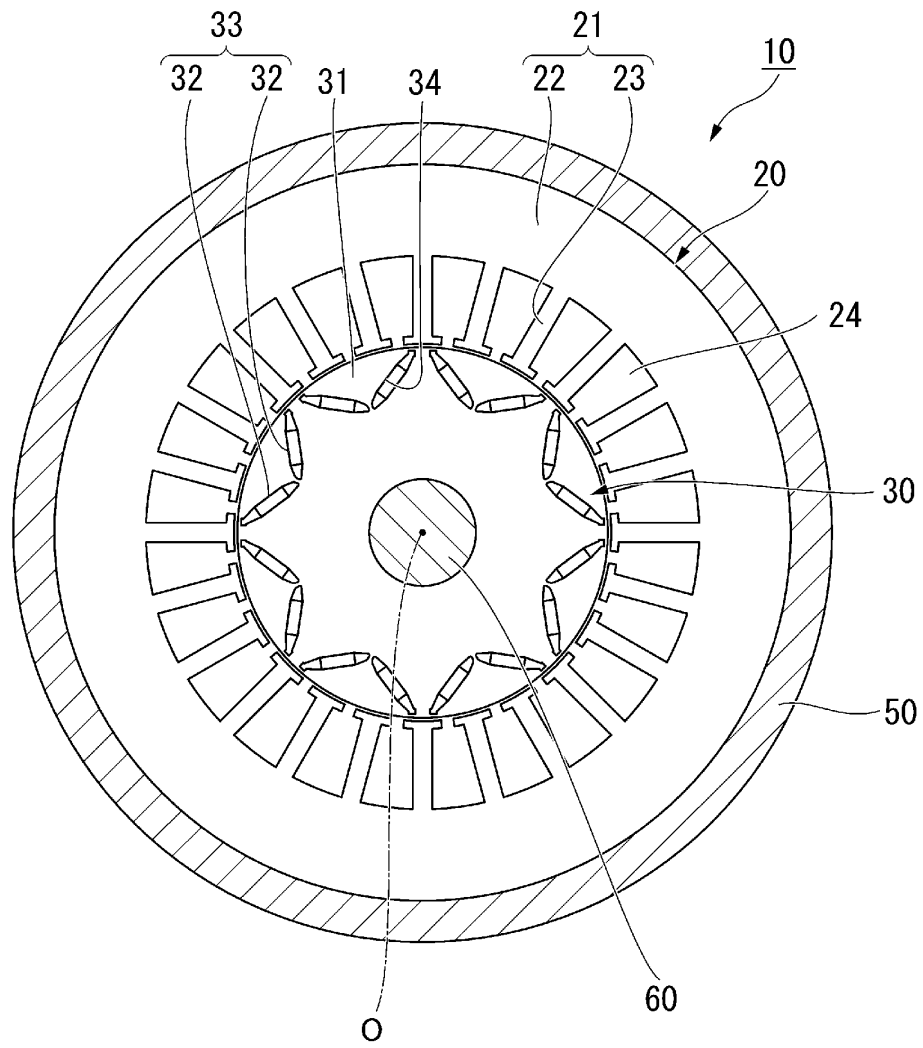


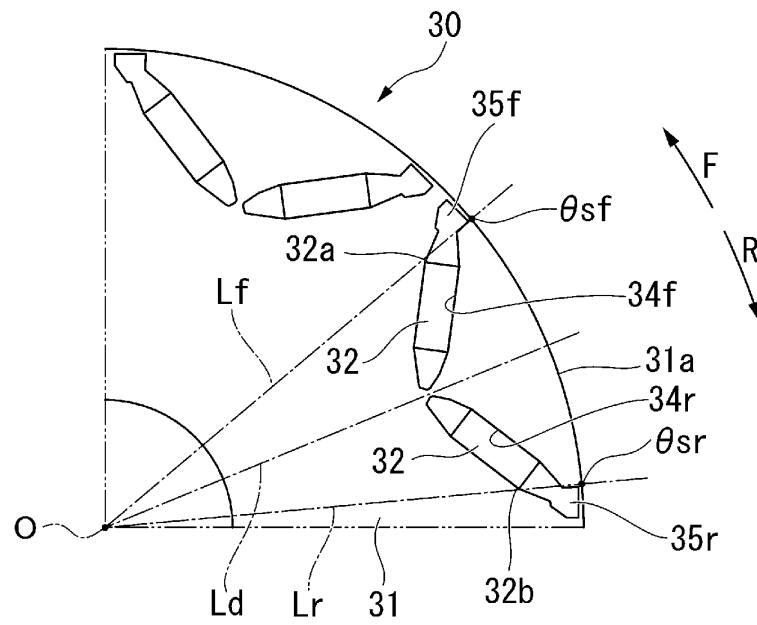
[図1]



[illegible]

Figure 1 is a schematic diagram of a mechanical assembly 30, showing a cross-section of a rotating body with multiple curved segments and a central shaft. The diagram includes various labels for components and dimensions. Key components include segments 32, 33, 34 (34f), 34 (34r), 35 (35f), 35 (35r), 35fo, 35ro, 36, 37 (37f), 37 (37r), 37fa, 37ra, and 37fo. Dimensions and angles are indicated by Lq, Ld, 60, and F. A coordinate system with origin O is shown at the bottom left, with a horizontal axis and a vertical axis. A curved line 31a is also labeled.

[図4]



[図5]

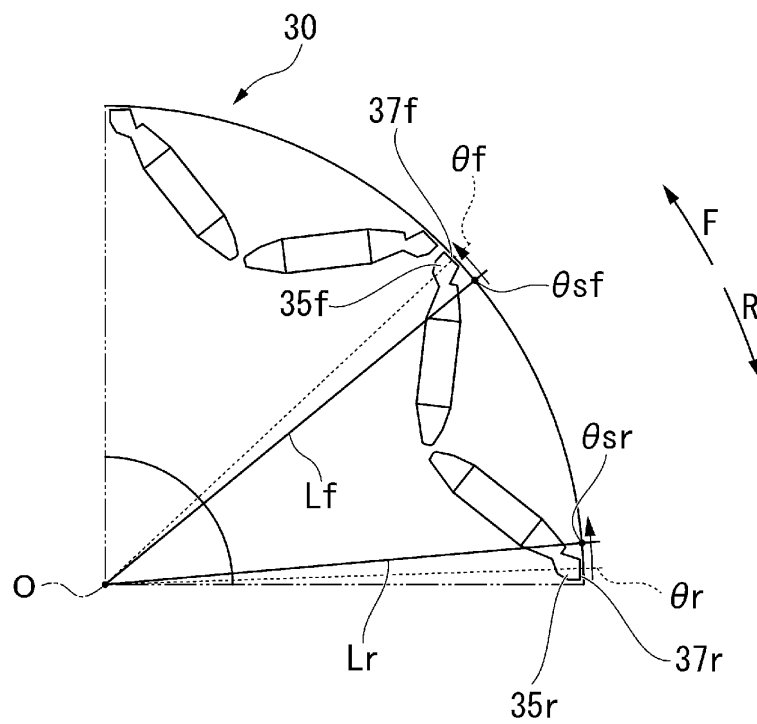
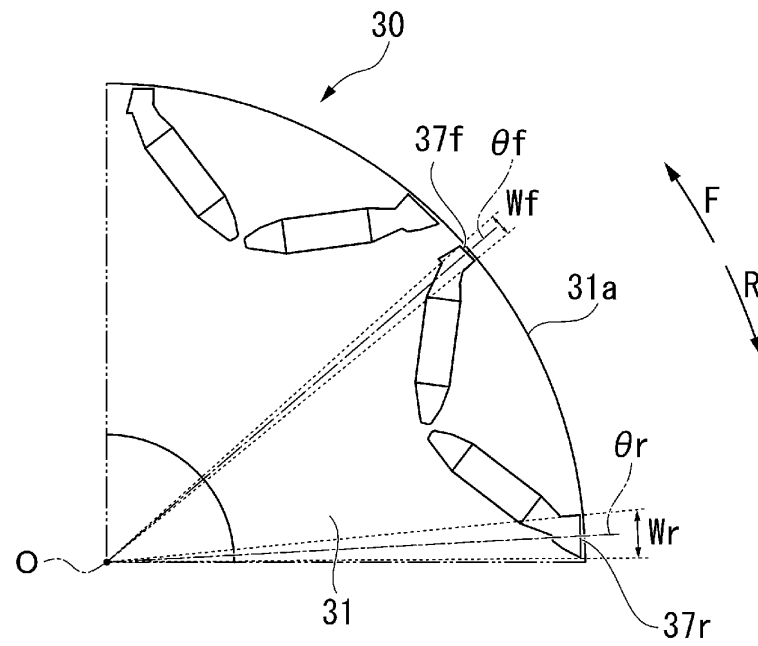


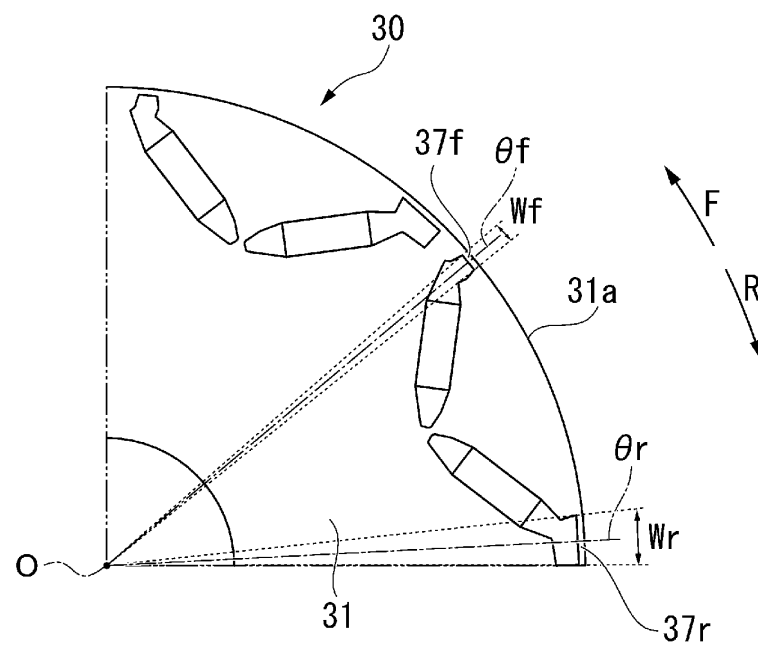
Diagram illustrating a curved structure 30, possibly a flexible arm or a chain of segments, under forces F and R . The structure is composed of segments 35f, 35fo, 35r, and 35ro. The segments are connected at joints 37f and 37r. The structure is shown in a curved configuration, with a dashed line 31 representing a reference axis. The angle between the segments is labeled 31a. The distance from the origin O to the joint 37f is labeled W_f , and the distance from the origin O to the joint 37r is labeled W_r . The force F is applied at joint 37f, and the force R is applied at joint 37r. The segments are labeled 35f, 35fo, 35r, and 35ro. The structure is labeled 30.

Diagram illustrating a curved surface 30, which is divided into segments 31. A specific segment 31a is shown with a normal vector 37f at an angle θ_f and a distance W_f . Another segment 31 is shown with a normal vector 37r at an angle θ_r and a distance W_r . External forces F and R are indicated.

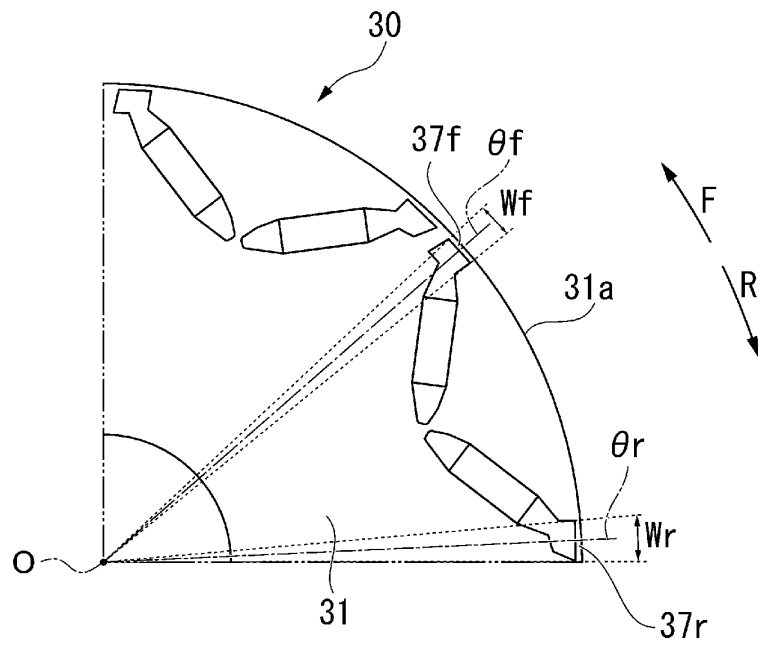
[図8]



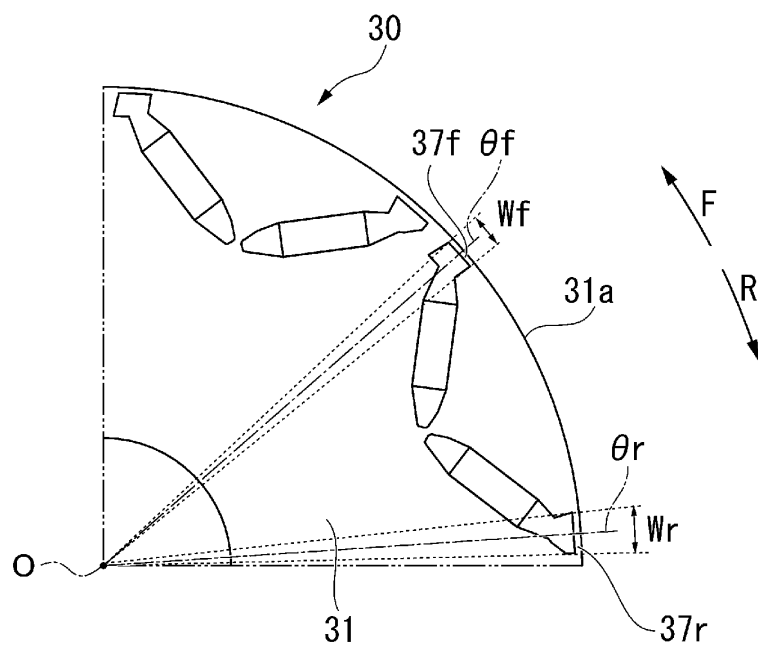
[図9]



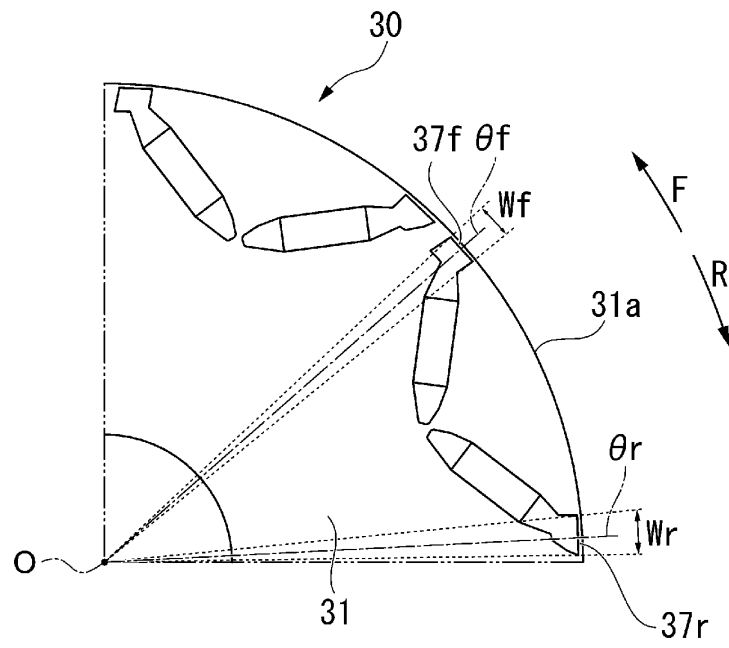
[図10]



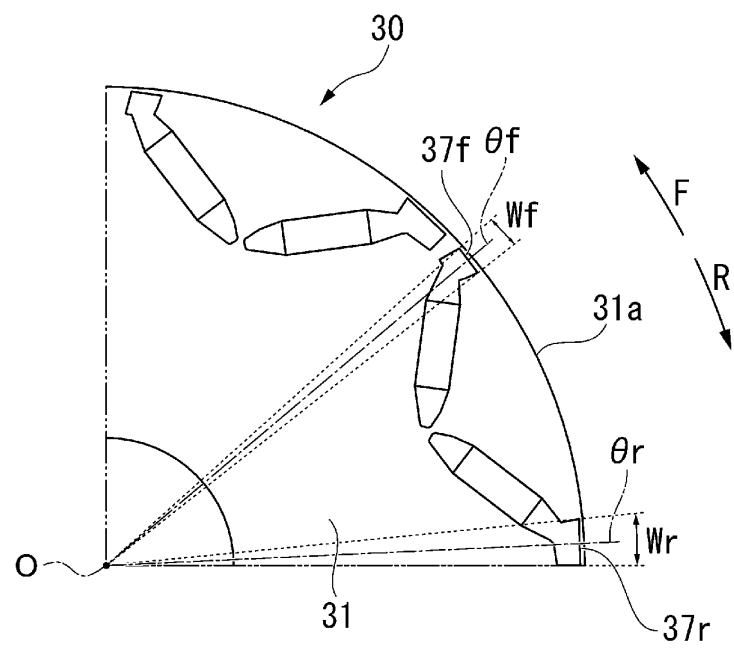
[図11]



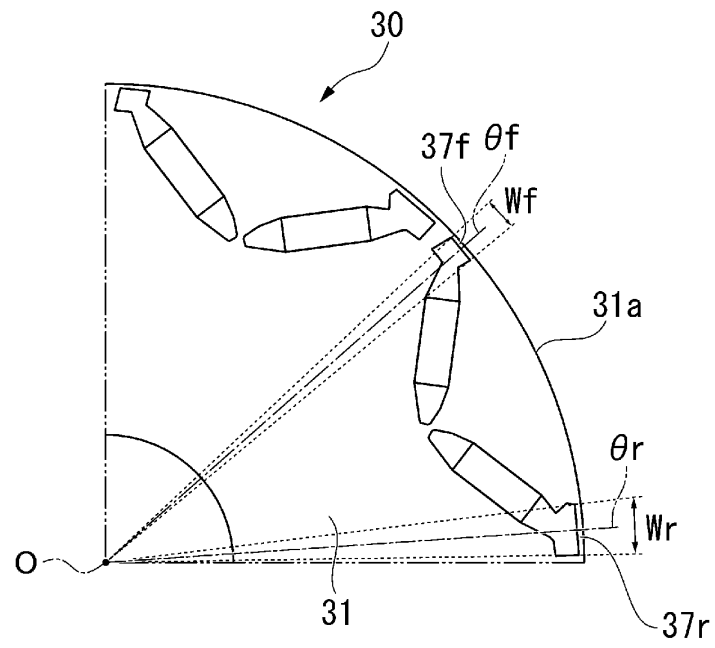
[図12]



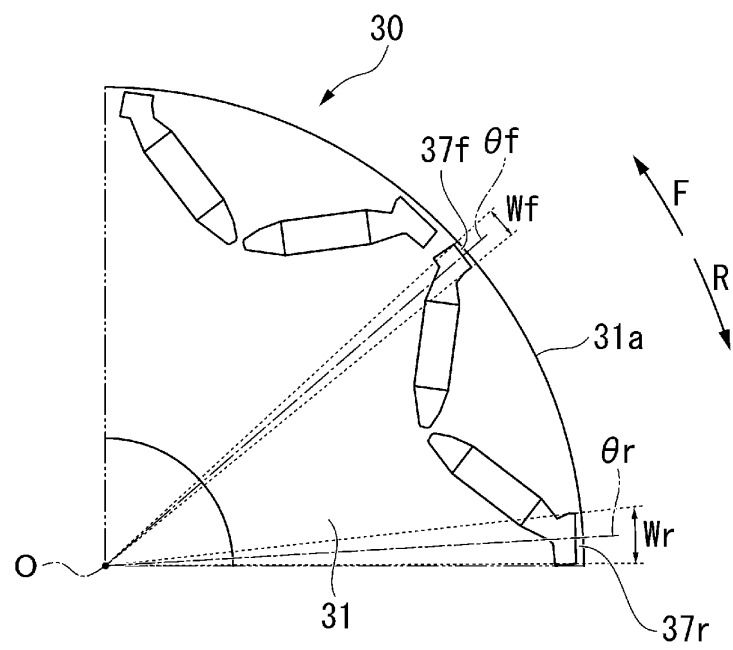
[図13]



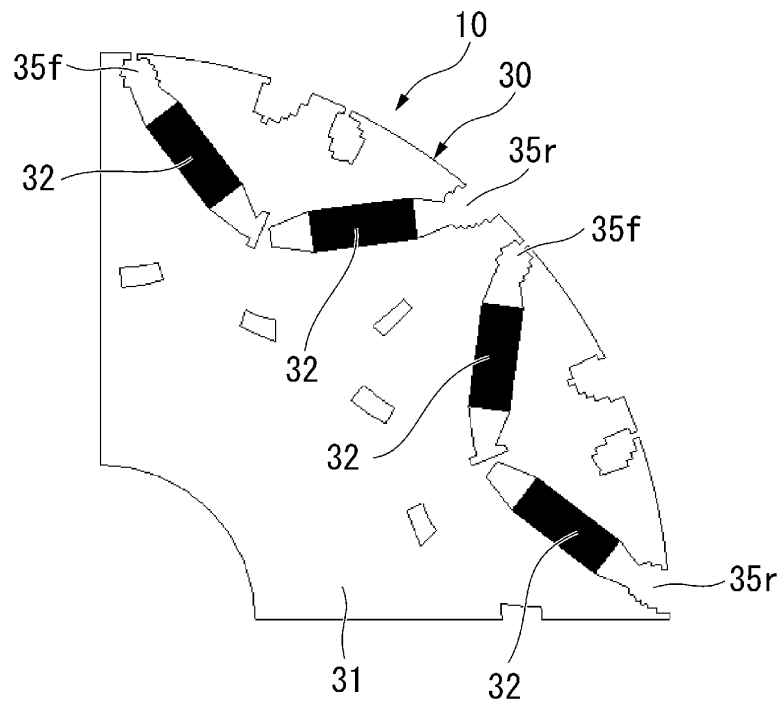
[図14]



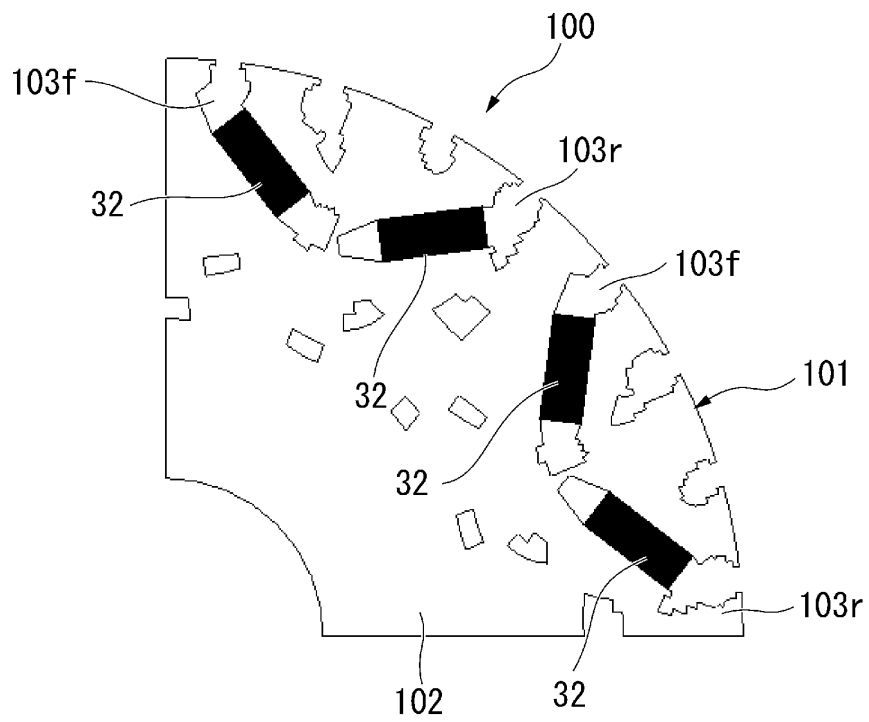
[図15]



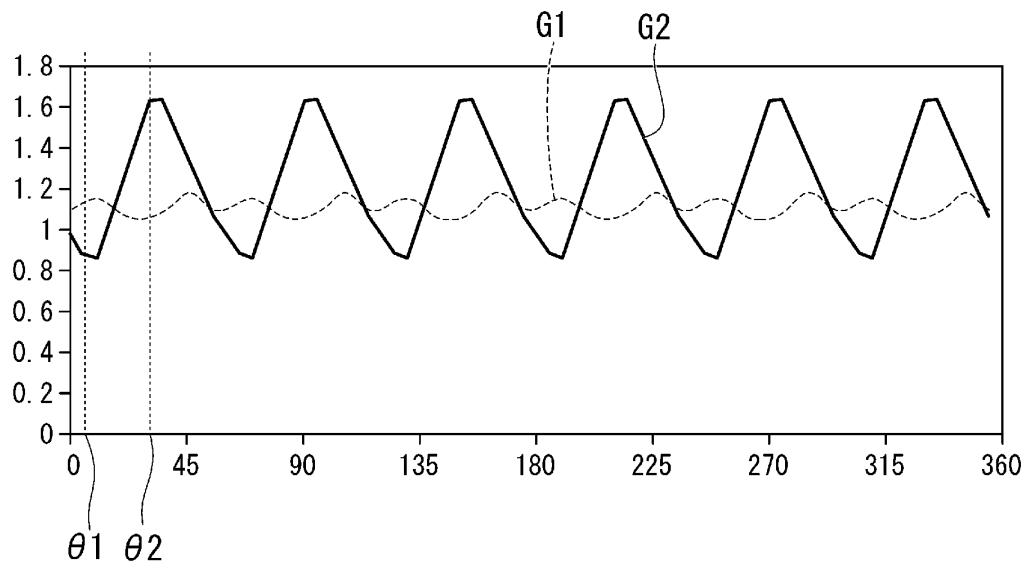
[図16]



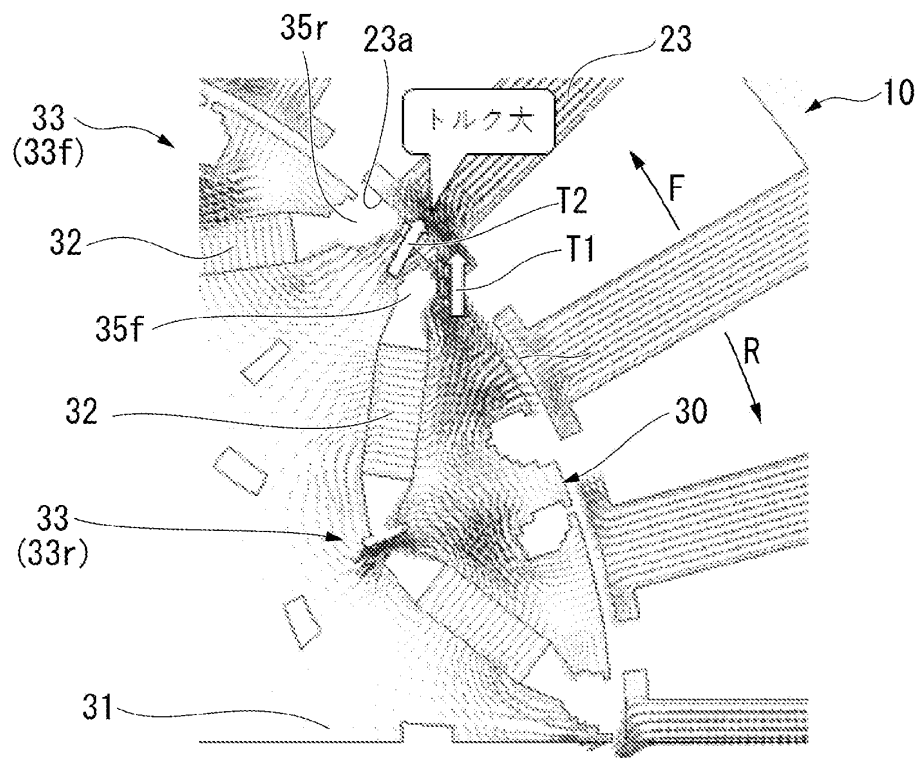
[図17]



[図18]



[図19]



[図22]

