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**PERSPECTIVE MODEL OF MOTOR-VEHICLE FORMING
FOR ARMED FORCES OF UKRAINE IN MODERN CONDITIONS**

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In the article the existent model of motor-car materiel of Ukrainian Armed Forces is considered and the new, compatible model row of military vehicles, which meet modern requirements is offered.

Keywords: model, full drives trucks, technical descriptions.

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$$u_{tt} + 2Vu_{xt} - (\alpha^2 - V^2)u_{xx} - \gamma^2 u_{yy} = 0. \quad (1)$$

(1) , - , $u(t, x, y)$ -

t, x, y -

, V -

(1)

$$u(t, x, y)|_{x=0} = u(t, x, y)|_{x=l} = 0, \quad (2)$$

(1), (2)

(1)

(2)

$$u(t, x, y) = a \cos(\kappa x + \delta y + \omega t + \varphi) + b \cos(\chi x - \delta y - \omega t + \psi) \quad (3)$$

- , a, b -
 κ, χ - , δ -

:

$$1. \quad (1)$$

$$2.$$

(1)

$$\begin{aligned} \omega^2 + 2V\omega\kappa - (\alpha^2 - V^2)\kappa^2 - \gamma^2\delta^2 &= 0, \\ \omega^2 - 2V\omega\chi - (\alpha^2 - V^2)\chi^2 - \gamma^2\delta^2 &= 0. \end{aligned} \quad (4)$$

(3)

$$u(t, x, y)|_{x=0} = 0,$$

$$a = b, \quad \varphi = -\psi.$$

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$$u(t, x, y)|_{x=l} = 0,$$

$$\cos(\kappa l + \delta y + \omega t + \varphi) - \cos(\chi l - \delta y - \omega t - \varphi) = 0. \quad (5)$$

κ, χ, δ

l ,

$$\cos(\kappa l + \delta y) - \cos(\chi l - \delta y) \equiv 0,$$

$$\sin(\kappa l + \delta y) + \sin(\chi l - \delta y) \equiv 0. \quad (6)$$

(6)

κ, χ

$$\kappa + \chi = \frac{2k\pi}{l}, k = 1, 2, \dots \quad (7)$$

(4)

(7)

$$\kappa = \frac{k\pi}{l} \left(1 + \frac{V}{\alpha} \sqrt{1 + \frac{\delta^2 \gamma^2 l^2}{(\alpha^2 - V^2) k^2 \pi^2}} \right),$$

$$\chi = \frac{k\pi}{l} \left(1 - \frac{V}{\alpha} \sqrt{1 + \frac{\delta^2 \gamma^2 l^2}{(\alpha^2 - V^2) k^2 \pi^2}} \right),$$

$$\omega = \frac{k\pi}{l} \left(\frac{\alpha^2 - V^2}{\alpha} \sqrt{1 + \frac{\delta^2 \gamma^2 l^2}{(\alpha^2 - V^2) k^2 \pi^2}} \right). \quad (8)$$

$$\delta = \frac{m\pi}{b} \quad (b = 1, 2, \dots)$$

$$u(t,x,y) = a \left[\cos \left(\frac{k\pi}{l} \left(1 + \frac{V}{\alpha} \Delta \right) x + \frac{m\pi}{b} y + \frac{k\pi\alpha^2 - V^2}{l\alpha} \Delta t + \phi \right) - \cos \left(\frac{k\pi}{l} \left(1 - \frac{V}{\alpha} \Delta \right) x + \frac{m\pi}{b} y + \frac{k\pi\alpha^2 - V^2}{l\alpha} \Delta t + \phi \right) \right]$$

$$\Delta = \sqrt{1 + \frac{\gamma^2 l^2 m^2}{(\alpha^2 - V^2) k^2 b^2}}$$

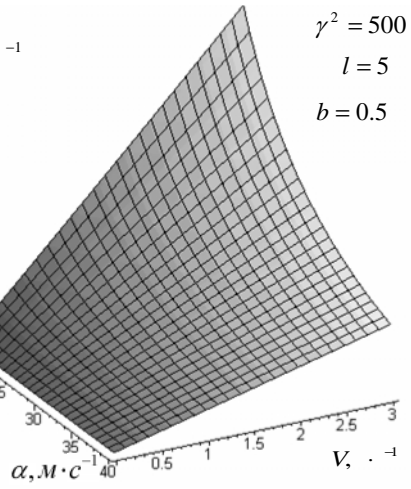
$V < \alpha$,

1-2

κ, χ

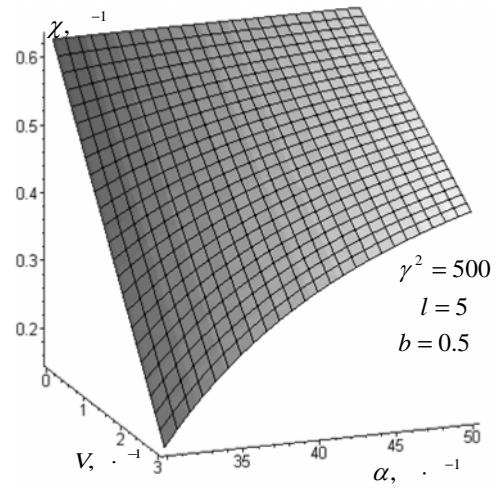
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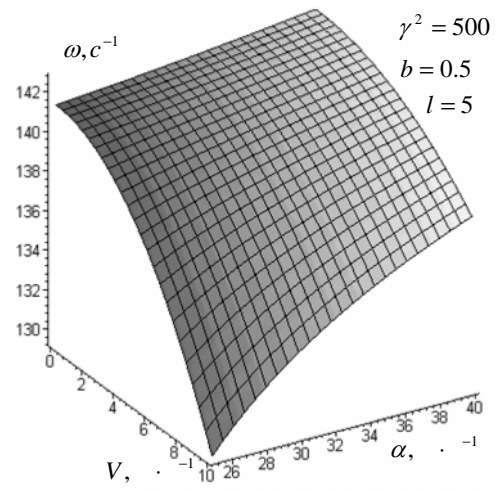
1.

κ
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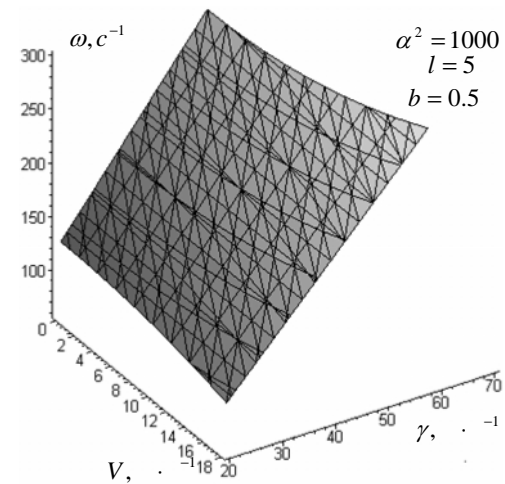
2.

χ V α



3.

ω
 V α



4.

ω V γ

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WAVE THEORY OF MOTION IN THE INVESTIGATION OF VIBRATION OF FLEXIBLE ELEMENTS DRIVEGEAR AND TRANSPORT IN VIEW OF LONGITUDINAL MOTION

.B. Sokil, O.I. Khytriak

A method of investigation of dynamic processes in the two-dimensional systems (flexible cell drive systems, and transportation), which are characterized by a constant component of the velocity of longitudinal motion is developed. It is based on the wave theory of movement. The relations that define the basic characteristics of waves are obtained. They can be the basis of design calculations of the elements of continuous machines, which are widely used in technological processes of manufacturing industries including military production.

Keywords: *nonlinear oscillation, amplitude, frequency, asymptotic method.*