

N1893- 90 9.04.90 .7.
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$n \leq 3k$).

$$[2] M(t, x_1, x_2 \dots x_n) \quad M(t, \bar{X})$$

$$D(t, x_1, x_2 \dots x_n) \quad T(t, q, \dot{q}), V(t, q, \dot{q})$$

$(t_2 \bar{X}_2)$

$$(t_1 \bar{X}_1)$$

$$J(t) = \int_{t_1}^{t_2} L(t, q(t), \dot{q}(t)) dt$$

1.

$(k=1)$

R, $n=3$

$$M(t, x_1, x_2, x_3) \quad M(t, x, y, z)$$

$$x_1 = x, x_2 = y, x_3 = z$$

$$J = \frac{\xi}{2f} \int_0^{\xi} \left(\frac{1}{2} m(\dot{x}^2 + \dot{y}^2 + \dot{z}^2) - k_1 x^2 - k_2 y^2 - k_3 z^2 \right) dt$$

$$x(0) = x_0, y(0) = y_0, z(0) = z_0; x\left(\frac{\xi}{2f}\right) = x_{10}, y\left(\frac{\xi}{2f}\right) = y_{10}, z\left(\frac{\xi}{2f}\right) = z_{10}.$$

$$J = \frac{\xi}{2f} \int_0^{\xi} \left(\frac{1}{2} m(\dot{x}^2 + \dot{y}^2) - k_1 x^2 - k_2 y^2 \right) dt$$

The results of the investigation of optimal parameters to the mathematical description in the vibrating machines.

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[1]

$$x(0) = x_0, y(0) = y_0; x\left(\frac{\mathfrak{S}}{2f}\right) = x_{10}, y\left(\frac{\mathfrak{S}}{2f}\right) = y_{10}$$

$$F(t, x, y, \dot{x}, \dot{y}) = \left(\frac{1}{2}m(\dot{x}^2 + \dot{y}^2) - k_1x^2 - k_2y^2\right)$$

$$\frac{\partial F}{\partial x} - \frac{d}{dt} \frac{\partial F}{\partial \dot{x}} = 0, \quad \frac{\partial F}{\partial y} - \frac{d}{dt} \frac{\partial F}{\partial \dot{y}} = 0$$

$$\begin{cases} m\ddot{x} + 2k_1x = 0 \\ m\ddot{y} + 2k_2y = 0 \end{cases}$$

$$x(t) = A \cos(\omega_0 t + \{\}_0);$$

$$y(t) = C \cos(\omega_0 t + \{\}_1);$$

$$\omega_{0i} = \sqrt{\frac{2k_i}{m}}, i = 1, 2; A, C, \{\}_0, \{\}_1$$

$$A = \frac{x_0}{\cos \{\}_0}, \quad \{\}_0 = \text{artg} \left(\frac{\cos \mathfrak{S} - \frac{x_{10}}{x_0}}{\sin \mathfrak{S}} \right), \quad \mathfrak{S} = \sqrt{\frac{k_1 \omega_{01}^2}{2mf^2}}, \quad C = \frac{y_0}{\cos \{\}_1},$$

$$\{\}_1 = \text{artg} \left(\frac{\cos \mathfrak{S} - \frac{y_{10}}{y_0}}{\sin \mathfrak{S}} \right), \quad \mathfrak{S} = \sqrt{\frac{k_2 \omega_{02}^2}{2mf^2}}$$

x, y

$$A = \frac{x_0}{\cos \{\}_0}, \quad C = \frac{y_0}{\cos \{\}_1}.$$

2.

(R)

[2, 3]

$$J = \frac{\mathfrak{S}}{2f} \int_0^{\frac{\mathfrak{S}}{2f}} \left(\frac{1}{2}m(\dot{x}^2 + \dot{y}^2 + \dot{z}^2) - k_1x^2 - k_2y^2 - k_3z^2 \right) dt,$$

$x(t), y(t), z(t)$ ()

$$x^2 + y^2 + z^2 = R^2$$

$$x(0) = x_0, y(0) = y_0, z(0) = z_0; x\left(\frac{\mathfrak{S}}{2f}\right) = x_{10}, y\left(\frac{\mathfrak{S}}{2f}\right) = y_{10}, z\left(\frac{\mathfrak{S}}{2f}\right) = z_{10}$$

z

$$J = \frac{\mathfrak{S}}{2f} \int_0^{\frac{\mathfrak{S}}{2f}} \left(\frac{1}{2}m(\dot{x}^2 + \dot{y}^2) - k_1x^2 - k_2y^2 \right) dt \quad x^2 + y^2 = R^2$$

$$x(0) = x_0, y(0) = y_0; x\left(\frac{\mathfrak{S}}{2f}\right) = x_{10}, y\left(\frac{\mathfrak{S}}{2f}\right) = y_{10}.$$

$$F_L(t, x, y, \dot{x}, \dot{y}) = \left(\frac{1}{2}m(\dot{x}^2 + \dot{y}^2) - k_1x^2 - k_2y^2 + \right) (t) \cdot (x^2 + y^2 - R^2)$$

$$\begin{cases} m\ddot{x} + 2k_1x - 2x\} (t) = 0 \\ m\ddot{y} + 2k_2y - 2y\} (t) = 0 \\ x^2 + y^2 = R^2 \end{cases}$$

(t, ξ, η) ,

$$J = \frac{\check{S}R^2m}{4f} \int_0^{\check{S}} (\xi^2 + \eta^2 \sin^2 \xi) dt$$

$$\xi(0) = \xi_0, \eta(0) = \eta_0; \xi\left(\frac{\check{S}}{2f}\right) = \xi_{10}, \eta\left(\frac{\check{S}}{2f}\right) = \eta_{10}$$

$$\begin{cases} \eta(t) = \frac{t^2}{2} - \frac{\eta_0 \check{S}^2 + 2f^2}{2f\check{S}} t + \eta_0 \\ \xi(t) - t^2 \sin 2\xi = 0 \end{cases}$$

$$\xi(t) \quad [4]$$

3.

[3]

$$c_1 \dot{x}; \quad c_2 \dot{x}^2 \operatorname{sign} \dot{x}; \quad c_3 \operatorname{sign} \dot{x}$$

$$W(t) = c_1 \dot{x} + c_2 \dot{x}^2 \operatorname{sign} \dot{x} + c_3 \operatorname{sign} \dot{x}$$

$$z \quad 1,$$

$$J = \frac{\check{S}}{2f} \int_0^{\check{S}} \left(\frac{1}{2} m(\dot{x}^2 + \dot{y}^2) - k_1 x^2 - k_2 y^2 - c_1 \dot{x} - c_2 \dot{x}^2 \operatorname{sign} \dot{x} - c_3 \operatorname{sign} \dot{x} \right) dt$$

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