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[1].

[2, 3]

$$\frac{dT}{dl} = \frac{f D^2}{2 \cdot G} \left[S \cdot Y \cdot \Delta H - K_{TX} (T -) - (-) \right] \quad (1)$$

$$\frac{dT}{dl} = \frac{f D^2}{2 \cdot G} \quad (-) \quad (2)$$

$$\frac{dT}{dl} = \frac{f D^2}{2 \cdot G} \quad (-) \quad (3)$$

$$\frac{dY}{dl} = \frac{dC^*}{dl} C_B - \frac{1}{G} \frac{dC_B}{dl} \quad (4)$$

$$\frac{dC}{dl} = \frac{f D^2}{2} S Y \quad (5)$$

C - , , - ; , , , ; G -
 , / ; G - , / ; G_x - , / ; C , C ,
 C - , / ; Δ - , / ; ,
 - , / ² ; D - , ; Y -
 , / ³ ; - SO_3 , / ³ ; * -
 SO_3 , / ³ ; l - , ; S -
 , / .

$$\frac{dC}{d\ddagger} = -K_1 \cdot C_A \cdot C_B^* \quad (6)$$

$$\frac{dC_R}{d\ddagger} = K_1 \cdot C_A \cdot C_B^* - K_2 \cdot C_R \cdot C_B^* \quad (7)$$

$$\frac{dC_S}{d\ddagger} = K_2 \cdot C_R \cdot C_B^* \quad (8)$$

- ; R - ; S - ; K_1 , K_2 -

MATLAB.

