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[4-7].

[1],

$$K = \int_0^{\infty} v \left\{ |\Xi|_n \geq \varepsilon \right\} d\varepsilon$$

[1, 3, 8, 9].

[4-7]

$$H_0 = \langle \varphi_0(\vec{\Theta}, t) = \theta_0 \rangle,$$

$$H_k = \langle \varphi_1(\vec{\Theta}, t) = \theta_{1k} t^k \rangle, k=1 \dots n.$$

$$: H_k \leq H_0 \quad k = 0 \dots n$$

$$(\mu_{\hat{\Phi}_{12}}, \mu_{t_{12}}).$$

$$(\mu_{\hat{\Phi}_{11}}, \mu_{t_{11}})$$

$$0 = \left| \mu_{\hat{\Phi}_{11}} - \mu_{\hat{\Phi}_{12}} \right|.$$

$$\begin{cases} \theta_{1k}^{[1]} * \mu_{t_{11}}^k = \mu_{\hat{\Phi}_{11}}, \\ \theta_{1k}^{[2]} * \mu_{t_{12}}^k = \mu_{\hat{\Phi}_{12}}, \\ k = 1 \dots n. \end{cases}$$

[3, 6]:

$$K_k = \frac{1}{2} \left( \left| \mu_{\hat{\Phi}_{11}} - \frac{\mu_{\hat{\Phi}_{12}} * \mu_{t_{11}}^k}{\mu_{t_{12}}^k} \right| + \left| \mu_{\hat{\Phi}_{12}} - \frac{\mu_{\hat{\Phi}_{11}} * \mu_{t_{12}}^k}{\mu_{t_{11}}^k} \right| \right).$$

$$\theta_{k1} t^{k1}$$

$$\varphi_2(\vec{\Theta}, t) = \theta_{1k} t^{k1} + \theta_{2k} t^k;$$

 $k=1 \dots n; k_1 \quad k.$ 

[2-3].

$$(\mu_{\hat{\Phi}_{22}}, \mu_{t_{22}}) \quad (\mu_{\hat{\Phi}_{23}}, \mu_{t_{23}}),$$

$$(\mu_{\hat{\Phi}_{21}}, \mu_{t_{21}})$$

[3, 5, 7, 8].

[3],

$$\min_{\tau} K(\tau), \tau \in [T_1, T_2]$$

$$\tau_0 = \arg \min_{\tau} K(\tau)$$

$$Z_{(t_i)} = Q(t) - \widehat{M}eQ(t_i), \quad i = 1, 2;$$

[5].

$$Q(t_1), Q(t_2),$$

$$Q(t_3), Q(t_4)$$

[10, 11].

$$Z_{(t_i)} = Q(t_j) - \widehat{M}eQ(t_j), \quad ij = 1, 2, 3, 4;$$

$$\widehat{M}e_{R1}Z = \frac{Z_1 + Z_2}{2}; \quad \widehat{M}e_{R1}t = \frac{t_1 + t_2}{2};$$

$$\widehat{M}e_{R1}Z = \frac{Z_3 + Z_4}{2}; \quad \widehat{M}e_{R1}t = \frac{t_3 + t_4}{2};$$

[12].

$$\Delta 1 = \left| \frac{Z_1 + Z_2 + Z_3 + Z_4}{2} \right|$$

$$t_0 = \frac{t_2 + t_3}{2}.$$

$$a_1 = Z_1 - \frac{Z_2 - Z_1}{t_2 - t_1} * t_1, \quad b_1 = \frac{Z_2 - Z_1}{t_2 - t_1}$$

[4]

$$a_2 = Z_3 - \frac{Z_4 - Z_3}{t_4 - t_3} * t_3, \quad b_2 = \frac{Z_4 - Z_3}{t_4 - t_3}.$$

$\Delta 1,$

$$\Delta 2 = \left| Z_1 + \frac{Z_2 - Z_1}{2} \left( 1 + \frac{t_1 - t_0}{t_2 - t_1} \right) - Z_3 + \frac{Z_4 - Z_3}{2} \left( \frac{t_3 - t_2}{t_4 - t_3} \right) \right|$$

$\Delta 2,$

$\Delta 2$

$\Delta 1.$

$\Delta 1$

$\Delta 1 > \Delta 2,$

$\Delta 1 > \Delta 2 -$

[6],

$\frac{1}{2}\Delta$ .

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[4, 7, 12]

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7.11.2008

I.

## GENERALIZATION OF PROCEDURES OF EXPOSURE OF STRUCTURAL CHANGES OF MODELS OF DRIFT OF THE RATIONED ARMAMENT AND MILITARY TECHNIQUE PARAMETER

A. O. Levchenko

*In the article generalization of procedures of verification of hypotheses on appearance of structural changes of models of drift of the rationed parameter at presence of one, two, three and four counting out after regulation is conducted. Preliminary for a location of area of application of procedures of verification of hypotheses about appearance structural procedure is considered of construction in the class of eventual sedate rows of analytical model of drift is considered, optimum in sense of a maximum of cappa-criterion of reproduced and a minimum of index of compactness on the stage of structural authentication following the method of successive complication of a model. As a result procedures are got in the article, the aggregate of which will allow to realize algorithms informative procedures of the automatic systems of accompaniment with prognostication for introduction of control with prognostication in a kind, most characteristic for organization of exploitation in Armed Forces of Ukraine e.*

**Keywords:** drift model, armament parameter, automatic systems.

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