

CAE

$$l_2^2 = l_3^2 + S^2 - 2l_3S \cos \varphi_{3S} . \quad (7)$$

3S:

$$\varphi_{3S} = \arccos \frac{l_3^2 - l_2^2 + S^2}{2l_3S} . \quad (8)$$

$$\varphi_3 = \arccos \frac{l_3^2 - l_2^2 + S^2}{2l_3S} - \arctg \frac{l_4 \sin \varphi_4}{l_4 \cos \varphi_4 - l_1} . \quad (9)$$

S

AOE:

$$S = \sqrt{l_4^2 + l_1^2 - 2l_4l_1 \cos \varphi_4} . \quad (10)$$

S

$$\varphi_3 = f(\varphi_4):$$

$$\varphi_3 = \arccos \frac{l_3^2 - l_2^2 + l_4^2 + l_1^2 - 2l_4l_1 \cos \varphi_4}{2l_3 \sqrt{l_4^2 + l_1^2 - 2l_4l_1 \cos \varphi_4}} - \arctg \frac{l_4 \sin \varphi_4}{l_4 \cos \varphi_4 - l_1} . \quad (11)$$

$$\varphi_3 = \arccos \frac{l_3^2 - l_2^2 + l_4^2 + l_1^2 - 2l_4l_1 \cos(\varphi_4 - \beta)}{2l_3 \sqrt{l_4^2 + l_1^2 - 2l_4l_1 \cos(\varphi_4 - \beta)}} - \arctg \frac{l_4 \sin(\varphi_4 - \beta)}{l_4 \cos(\varphi_4 - \beta) - l_1} . \quad (12)$$

$$\varphi_3 = \arccos \frac{l_3^2 - l_2^2 + l_4^2 + l_1^2 - 2l_4l_1 \cos(\varphi_4 + \beta)}{2l_3 \sqrt{l_4^2 + l_1^2 - 2l_4l_1 \cos(\varphi_4 + \beta)}} - \arctg \frac{l_4 \sin(\varphi_4 + \beta)}{l_4 \cos(\varphi_4 + \beta) - l_1} . \quad (13)$$

$$\alpha = |\varphi_3 - \varphi_3 - \beta| . \quad (14)$$

$$\alpha = \left| \varphi_3 - \varphi_3 + \beta \right|. \quad (15)$$

New Holland SuperSteer –13

Заключение.

1.

2.

, 2021. – – –250. . – :

3.

4.

5. T4 F/N/V – AXLES & TRACTION – : <https://agriculture.newholland.com/apac/en-nz/equipment/products/tractors-telehandlers/t4fnv/details/axles-traction>. –

Аннотация.

Ключевые слова: