

1.

1.1.

$\text{modus, modulus, } : \text{ modello - , } \text{modelo -}$
 $\text{, modell - , model - , Modell - ,}$

1.2.

()
 () , ()
 () - ()
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), ()
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() ,

(,) .

() (,) ,

(,) -

$$m \frac{d^2 \xi(t)}{dt^2} = -\psi \xi(t), \quad (1.1.1)$$

$\xi(t) -$; $\psi -$; $m -$; $\psi \xi(t) -$, $t ; m -$

;

;

$$\frac{\psi}{m} = \omega_0^2, \quad \xi(t) = z,$$

(1.1.1)

$$\frac{d^2 z}{dt^2} + \omega_0^2 z = 0. \quad (1.1.2)$$

$t - q(t),$

$- L,$

$C,$

$$L \frac{d^2 q(t)}{dt^2} + \frac{q(t)}{C} = 0. \quad (1.1.3)$$

$$\frac{1}{LC} = \omega_0^2, \quad q(t) = z$$

(1.1.2).

(1.1.2),

1.

2.

3.

$$\begin{aligned}
& \begin{array}{l} - \\ - \end{array} \begin{array}{l} n - \\ n - \end{array} \begin{array}{l} A, \\ B, \end{array} \begin{array}{l} l_{1A}, l_{2A}, \dots, l_{nA}; \alpha_{1A}, \alpha_{2A}, \dots, \alpha_{nA} \\ l_{1B}, l_{2B}, \dots, l_{nB}; \alpha_{1B}, \alpha_{2B}, \dots, \alpha_{nB} \\ \vdots \end{array} \\
& \left. \begin{array}{l} \frac{l_{1A}}{l_{2B}} = \frac{l_{2A}}{l_{2B}} = \dots = \frac{l_{nA}}{l_{nB}} = m_l; \\ \frac{\alpha_{1A}}{\alpha_{1B}} = \frac{\alpha_{2A}}{\alpha_{2B}} = \dots = \frac{\alpha_{nA}}{\alpha_{nB}} = m_\alpha = 1. \end{array} \right\} \quad (1.1.4)
\end{aligned}$$

(1.1.4) () m_l m_α , (1.1.4) - m_l m_α .
Oxy :

$$\begin{aligned}
& \begin{array}{l} x_{iA}, y_{iA} \\ x_{iB}, y_{iB} \end{array} \\
& \frac{x_{iA}}{x_{iB}} = m_x, \frac{y_{iA}}{y_{iB}} = m_y, m_x = m_y, \quad (1.1.5)
\end{aligned}$$

$$\begin{array}{l} x_i \\ (A \quad B) \end{array} \quad (1.1.5)$$

$$\begin{aligned}
& \frac{z_{iA}}{z_{iB}} = m_z, \quad (1.1.6) \\
& m_x = m_y = m_z.
\end{aligned}$$

$$\begin{aligned}
& x, y, z. \\
& \dots \\
& (x_{iA}, y_{iA}, z_{iA}) \quad (x_{iB}, y_{iB}, z_{iB}) \quad (1.1.5) \quad (1.1.6)
\end{aligned}$$

$$\begin{aligned}
& \frac{x_{iA}}{x_{iB}} = m_x, \frac{y_{iA}}{y_{iB}} = m_y, \frac{z_{iA}}{z_{iB}} = m_z \\
& m_x \neq m_y = m_z.
\end{aligned}$$

()
 A
 $F(P_1, P_2, \dots, P_n) = 0$
 P_1, P_2, \dots, P_n ,
 x_1, x_2, \dots, x_n , P_1, P_2, \dots, P_n x_1, x_2, \dots, x_n .
 B,
 $f(R_1, R_2, \dots, R_n) = 0$.
 P_1, P_2, \dots, P_n , R_1, R_2, \dots, R_n .

$$\begin{aligned}
& \frac{P_1}{R_1} = m_1, \frac{P_2}{R_2} = m_2, \dots, \frac{P_n}{R_n} = m_n, \quad (1.1.7) \\
& A \quad B \quad P_i, \quad R_i, \\
& m_1, m_2, \dots, m_n
\end{aligned}$$

m_i

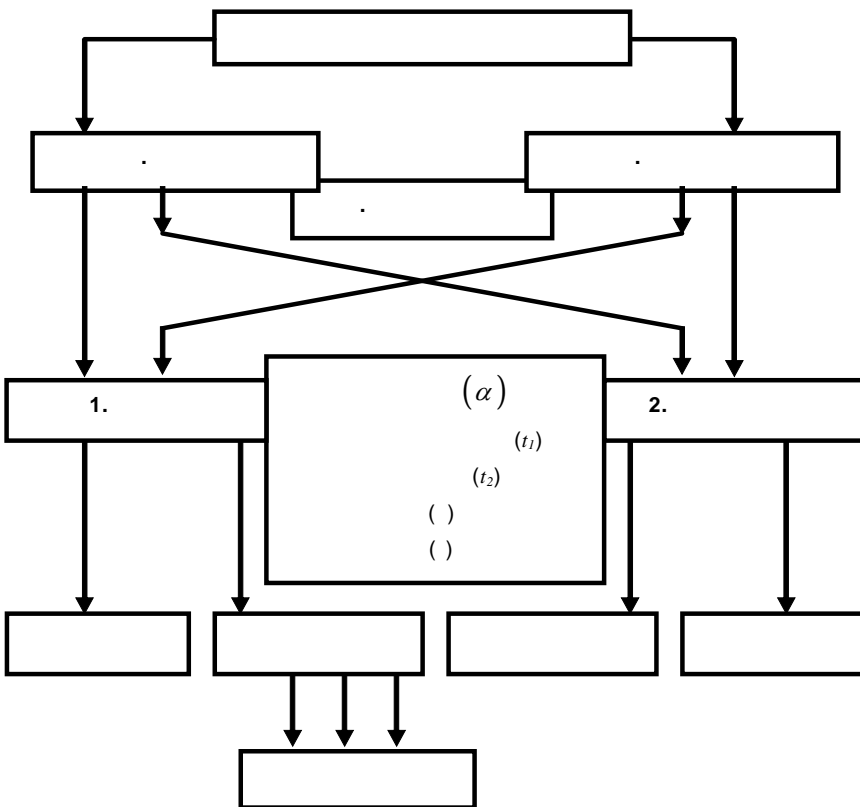
x_1, x_2, \dots, x_n

(1.1.7)

1.3.

(1.1.7)

$m_i = \text{const}, m_i = \text{var}, m_i = g(P_{i-r}, P_{i+k}, \dots)$



. 1.1.1

(1)

(2)

. 1.1.1.

