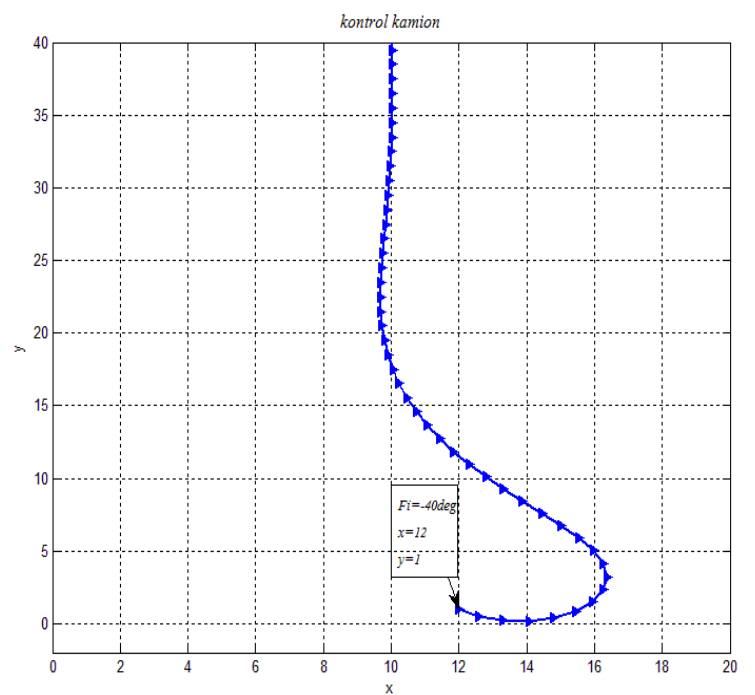
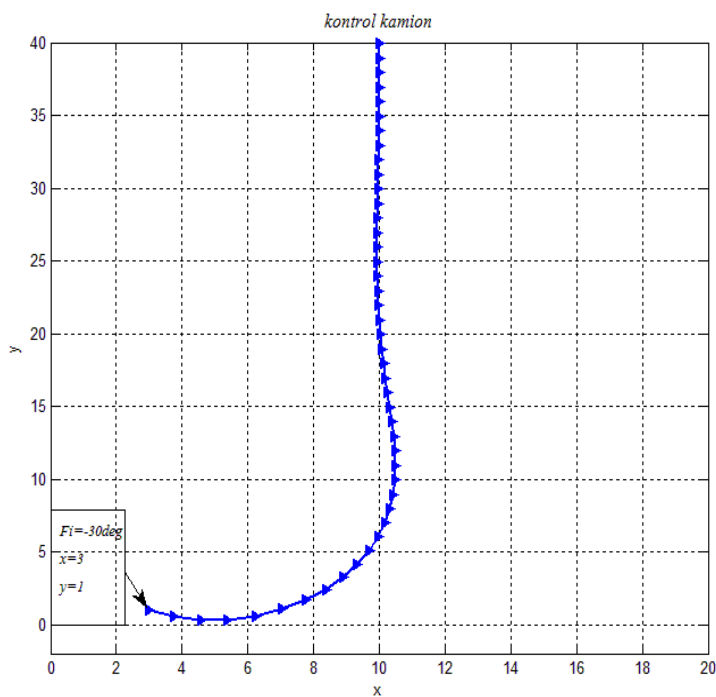
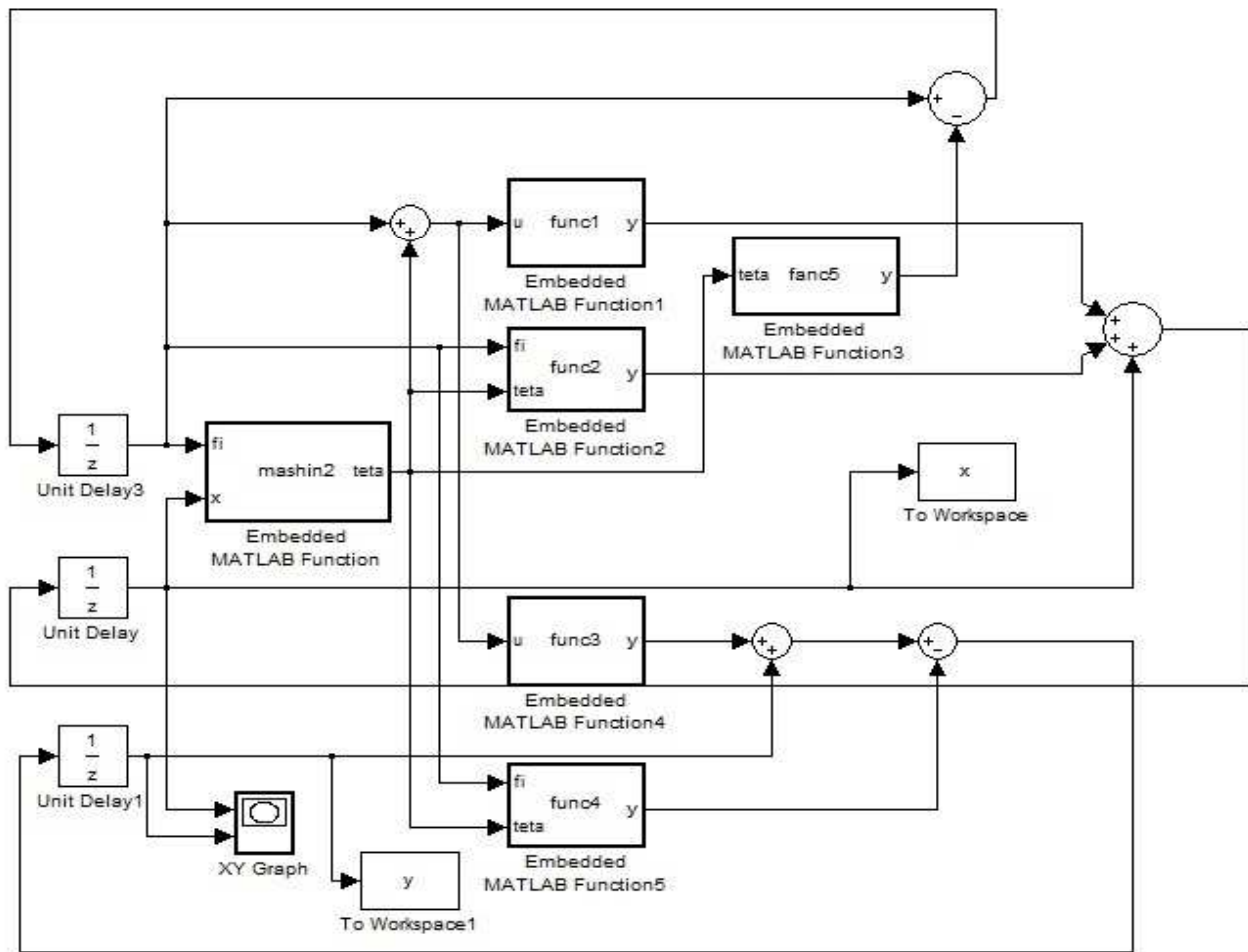


## فصل دوازدهم: کنترل کامیون باری



```

function teta=mashin2(fi,x)
sum1=0;sum2=0;
y=[-26.6    -40     0      0      0;
   -26.6    -40    -40    -40    -40;
    13.3  -13.3   -26.6   -40  -26.6;
    26.6   26.6     0   -26.6  -26.6;
    26.6     40   26.6   13.3  -13.3;
     0      40    40    40   26.6;
     0      0     0    40   26.6];
t=[ 1  1  0  0  0;
    1  1  1  1  1;
    1  1  1  1  1;
    1  1  1  1  1;
    1  1  1  1  1;
    0  1  1  1  1;
    0  0  0  1  1];
a=-45;
for i=1:7
    if abs(fi-a)<=45
        r=1-(abs(fi-a)/45);
    else
        r=0;
    end
    a=a+45;
    b=2;
    for j=1:5
        if abs(x-b)<=4
            s=1-(abs(x-b)/4);
        else
            s=0;
        end
        b=b+4;
        c1=r*s*y(i,j);
        sum1=sum1+c1;
        c2=r*s*t(i,j);
        sum2=sum2+c2;
    end
end
teta=sum1/sum2;
end

```

```

function y = func1(u)
u=u*(pi/180);
y=cos(u);

```

```

function y = func2(fi,teta)
fi=fi*(pi/180);
teta=teta*(pi/180);
y=sin(fi)*sin(teta);

```

```

function y = func3(u)
u=u*(pi/180);
y=sin(u);

```

```

function y = func4(fi,teta)
fi=fi*(pi/180);
teta=teta*(pi/180);
y=cos(fi)*sin(teta);

```

```

function y = fanc5(teta)
teta=teta*(pi/180);
teta=asin(.5*sin(teta));
y=(180/pi)*teta;

```