

ISSN 2181-8622

Manufacturing technology problems



Scientific and Technical Journal Namangan Institute of Engineering and Technology

INDEX  COPERNICUS
I N T E R N A T I O N A L

**Volume 9
Issue 4
2024**



ON DELAYED TECHNOLOGICAL OBJECTS AND THEIR CHARACTERISTICS

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Abstract: The article provides information about delayed objects, the causes of their delay, and methods of reducing delay time.

Keywords: Delay, mathematical model, signal, equation, time, delayed object, process, initial time.

Introduction. In the nature, there is a feature of technical devices, economic systems and many other processes that their future state depends on their previous state, that is, their history. It is known that in order to study any processes and phenomena it is necessary to build their mathematical model [1,3]. In this case the series variables of the research object are created with the participation of input variables in other words, controlling effects or controllers and output coordinates, controlled variables, intermediate variables [2,4]. The following expressions are used to create mathematical models: $(y \ t) = \{y \ (t), \dots, (1)\}$ - coordinates of the object; $u(t) = \{u(t), \dots, (t)\}$ - control keys; $f(t) = \{f(t), \dots, f(1)\}$ perturbations, $x(t) = \{x(t), \dots, x(t)\}$ interval variables. The concept of "delayed object" means that the research object has channels where signals are caught, that is, the signals of the object arrive at the control body with a certain time delay, time delay and

$$0 = \tau_0 < \tau_1 < \dots < \tau_l - \text{for } x(t) \text{ from variables;}$$

$$0 = \theta_0 < \theta_1 < \dots < \theta_r - \text{for variables (1).}$$

The mathematical model of the object whose signals are delayed expresses the analytical interrelationship between its essence and variables, and when using the accepted expressions, it has the following form:

$$F_0(y(t), x(t), u(t), f(t), \tau_1, \theta_1, \dots, \tau_l, \theta_r) = 0, \quad (1)$$

when observing an object for continuous moments of time

$$F_0(y(kT), x(kT), u(kT), f(kT), \tau_1, \theta_1, \dots, \tau_l, \theta_r) = 0, \quad k = 0, 1, \dots, \quad (2)$$

where $t = kT$ (T-discretion step), F_0 – operator. The subject of our further research will be focused on dynamic objects, that is, events, phenomena, processes that change over time. For this reason, the expressions (1), (2) are in the form of differential, integral or difference equations. (1) represents continuous objects whose signals are delayed, and (2) represents discrete objects whose signals are delayed. Objects whose execution

parameters are clear and fixed are called "deterministic" objects. Conversely, objects that are likely to occur are called "stochastic objects" [1-3].

Methods and results. Below, we specify the operator equations (1), (2) define the meaning of the variable $x(t)$.

The concept of "state" is usually interpreted as the minimum information about the previous state of an object in order to judge its future state. In connection with the introduction of the concept of state, we describe the properties that the model of the delayed object should have [3,4]:

1. The output signal at a certain time depends strictly on the input signals and is determined by the current state.
2. The state at the next time instant t depends strictly on the input signal in the time interval $[t_0, t)$ (or $[t_0 - \theta_r, t)$ interval $u(t, t_0 - \theta_r)$) and the state $x(t_0, t_0 - \tau_l)$ in the interval $[t_0 - \tau_l, t_0]$. We express these two conditions with two equations of state:

$$y(t) = g_1(x(t), u(t)), \quad (3)$$

$$x(t) = g_2(x(t_0, t_0 - \tau_l), u(t, t_0 - \theta_r)), \quad (4)$$

where g_1 , and g_2 are functions with the same meaning.

The above considerations that apply directly to continuous objects can also be applied to discrete objects. We note that the minimum number of variables $x(kT)$ constitutes the state vector of the system. For this, it is necessary to find such as g_1 and g_2 such that the following equations are valid:

$$y(kT) = g_1(x(kT), u(kT)), \quad (5)$$

$$x[(k+1)T] = g_2(x(kT), \dots, x[(k - \tau_l)T], u(kT), \dots, u[(k - \theta_r)T]), \quad (6)$$

where $y(kT)$ is the output coordinate vector of the object (kT) at time instant $u(kT)$ is the vector of control effects at time instant (here and then, when looking at discrete objects, we assume that the delay time is a multiple of the discreteness period T , therefore, τ_l and θ_r are assumed to be given in relative units; k_0T - initial time instant.

The difference between the state equations written for continuous objects (3), (4) and those written for discrete objects (5), (6) is explained by the characteristics of discrete objects. The following two recurrent proportional systems of equations are essentially discrete analogues of the first two.

The state of a discrete object (with delayed and non-delayed signals) at an arbitrary instant of time is described by the finite quantity parameters, accordingly, the equations of state of discrete objects with delays do not differ from the equation of such objects whose signals are not delayed and are generally similar in form [3-5]. The state of the first at an arbitrary time is described by some function defined at intervals $[t_0 - \tau_l, t_0]$, $[t_0 - \theta_r, t_0]$ with the last amount of parameters (this is not the case with the second). This condition greatly complicates the issues of managing such objects.

In this article, stationary, linear dynamic models of delayed objects, the simplest of the series of delayed dynamic models, are considered. It is self-evident that this is a very approximate representation of real processes. However, when the dynamics of many

processes are considered in the areas of slight deviations from the equilibrium regimes, linear dynamic systems describe the research object sufficiently. This serves as sufficient proof of the necessity and meaningfulness of their study.

The equation of state for objects whose coefficients are constant, linear, differential, difference equations, whose parameters do not change, that is, in simple terms, the equations of state for delay, continuous, stationary, linear objects have the following form.

$$\begin{aligned}\dot{x}(t) &= \sum_{i=0}^l A_i x(t - \tau_i) + \sum_{i=0}^r B_i u(t - \theta_i), \quad (7) \\ x(t) &= \varphi_x(t), \quad t_0 - \tau_l \leq t \leq t_0, \quad (8) \\ u(t) &= \varphi_u(t), \quad t_0 - \theta_r \leq t \leq t_0,\end{aligned}$$

where $\varphi_x(t)$, $\varphi_u(t)$ - is the initial function.

To be clear, this means output coordinates $y(t)$ and control effects $u(t)$ we assume that the learning vectors have the same dimension and are equal to n , that is, inputs objects with outputs were “ n ” viewed. The dimension of the state vector $x(t)$ is equal to $m \geq n$.

A , B , C , D are invariant matrices of corresponding size. Block diagrams corresponding to these equations are given in Fig. 1

It should be noted here that if $y(t)$ and $u(t)$ are real physical quantities and their choice strictly depends on the essence of the problem to be solved, then the intermediate parameters $x(t)$ the state of the object There is some freedom in choosing the vector.

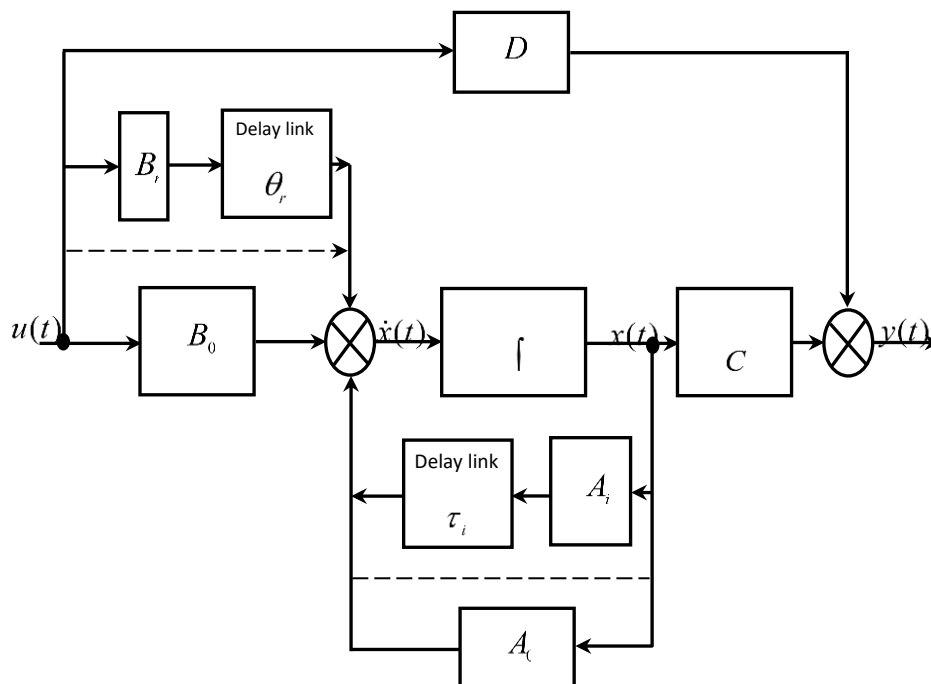


Figure 1. Block diagram of objects whose parameters are invariant and whose differences are differential, represented by straight-line equations.

Indeed, we consider some unbroken transformation [6]

$$x_1(t) = \Gamma x(t), \quad |\Gamma| \neq 0. \quad (9)$$

the equations of state (7) and (8) with respect to $x_1(t)$ will have the following form:

$$y(t) = C_1 x_1(t) + Du(t), \quad (10)$$

$$\dot{x}(t) = \sum_{i=0}^l A_{li} x_1(t - \tau_i) + \sum_{i=0}^r B_{li} u(t - \theta_i), \quad (11)$$

$$\text{It's here} \quad \left. \begin{aligned} A_{li} &= \Gamma A_i \Gamma^{-1}, \\ B_{li} &= \Gamma B_i, \quad C_1 = C \Gamma^{-1} \end{aligned} \right\}.$$

The coefficients are expressed by constant, linear differential equations, for objects with constant parameters, that is, for delayed, discrete, stationary and linear objects, the state equations have the following form

$$y(kT) = Cx(kT) + Du(kT), \quad (13)$$

$$x[(k+1)T] = \sum_{i=0}^l A_i x[(k - \tau_i)T] + \sum_{i=0}^r B_i u[(k - \theta_i)T], \quad (14)$$

$$x(kT) = \varphi_x(kT), \quad k_0 - \tau_l \leq k \leq k_0,$$

$$u(kT) = \varphi_u(kT), \quad k_0 - \theta_r \leq k \leq k_0,$$

where $\varphi_x(kT)$, $\varphi_u(kT)$ – initial functions.

A general block diagram of the system similar to the one in Figure 1 (Figure 2)

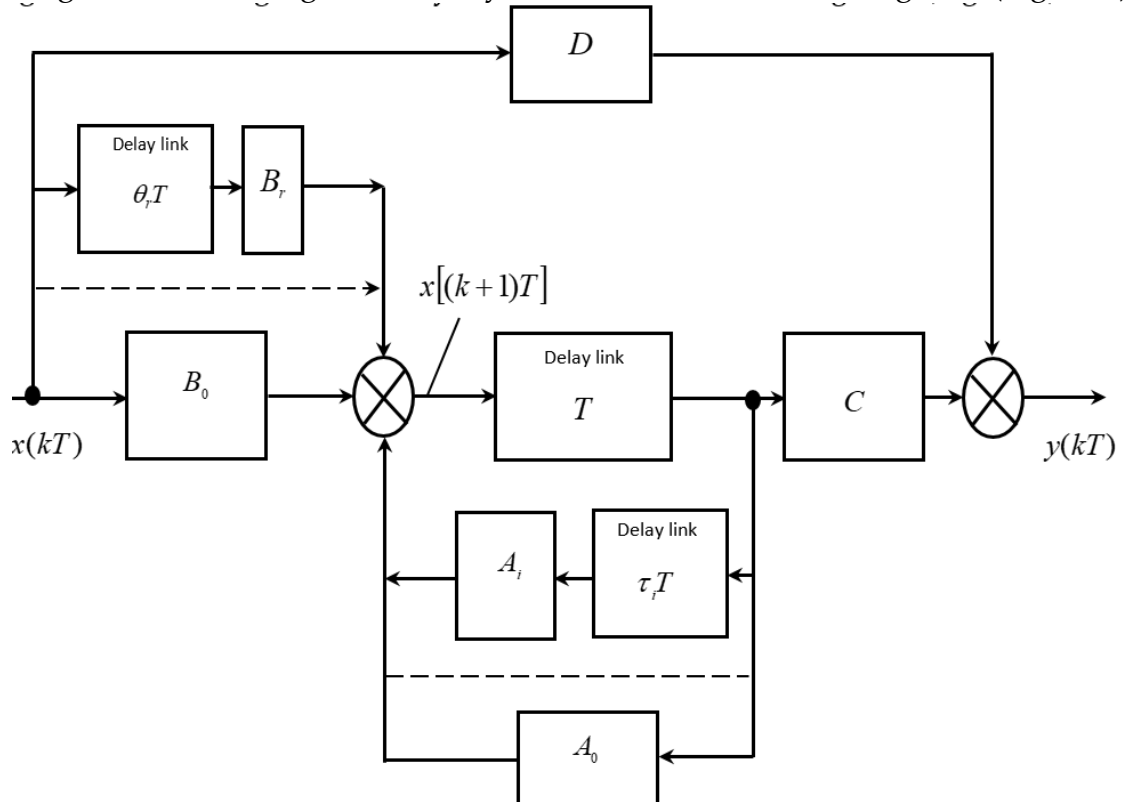


Figure 2. Block diagram of objects whose parameters are constant and whose differences are represented by straight-line equations

$$\left. \begin{aligned} y(t) &= Cx(t) + Du(t), \\ \dot{x}(t) &= \sum_{i=0}^i A_i x(t-\tau) + \sum_{i=0}^r B_i u(t-\theta_i) + B_f f(t), \end{aligned} \right\} \quad (19)$$

where B_f is an invariant matrix of appropriate size.

$$\left. \begin{aligned} A_i &= \begin{bmatrix} 0 & 0 & 0 & \dots & 0 & -L_q^i (L_0^0)^{-1} \\ E\delta_{i0} & 0 & 0 & \dots & 0 & -L_{q-1}^i (L_0^0)^{-1} \\ 0 & E\delta_{i0} & 0 & \dots & 0 & -L_{q-2}^i (L_0^0)^{-1} \\ \dots & \dots & \dots & \dots & \dots & \dots \\ 0 & 0 & 0 & \dots & E\delta_{i0} & -L_1^i (L_0^0)^{-1} \end{bmatrix}, \\ B_i &= \begin{bmatrix} G_q^i \\ G_{q-1}^i \\ \dots \\ G_1^i \end{bmatrix}, B_f = \begin{bmatrix} R_q \\ R_{q-1} \\ \dots \\ R_1 \end{bmatrix}, \\ C &= \begin{bmatrix} 0 & 0 & \dots & (L_0^0)^{-1} \end{bmatrix}, \end{aligned} \right\}$$

δ_{i0} - The epitome of a chronicler

The objects whose delay is only in the control signals constitute an important class ((8), (14) in equations $A_i = 0, \quad i \neq 0$). These are called objects with control delay. This the common "subclass" of objects with pure latency belongs to the class ((8) ($A_i = 0, \quad i \neq 0, \quad B_0 = 0$) in equations (14)). Examples of such objects are models of many production systems, in particular, flow production models [9-11], models of stock management problems [12-13], models of human behavior and many technical objects [14]. Only the objects whose coordinates have a delay form a separate class ((8), in equations (14) $B_i = 0, \quad i \neq 0$). These are called delayed coordinate objects. This class describes recycling processes, such as processes in chemical reactors of grinding aggregates.

Conclusion. Due to the fact that the mathematical models of linear dynamic objects with delay are expressed in different forms, there are also different approaches to finding a solution to the problems of synthesizing optimal closed-loop control systems. For these reasons, this article focuses on expressions of type (1), (2) related to objects of the said class.

Particular attention is paid to the approximation of the dynamic properties of continuous objects with a delay by special linear differential equations.

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CONTENTS

PRIMARY PROCESSING OF COTTON, TEXTILE AND LIGHT INDUSTRY

Korabayev Sh.	3
From street traffic to space: innovations in autonomous vehicles	
Egamov N.	10
Investigation of vertical forced vibration in the longitudinal - vertical plane of a binder that softens the crush between cotton rows	
Khamraeva S., Kadirova D., Davlatov B.	15
Determination of alternative technological factors for the production of functional fabric with a complex structure	
Khamraeva S., Kadirova D., Daminov A.	21
Designing fabrics for a given stretchability	
Kuliyev T., Rozmetov R., Tuychiev T., Sharipov Kh.	28
The effect of the angle of heat agent supply to the drying - cleaning equipment on cotton quality and cleaning efficiency of the equipment	
Abdujabbarov M., Alieva D., Karimov R.	35
Determination of the influence of the length of the tested yarn samples on their mechanical characteristics	
Jurayeva M., Nabidjonova N.	41
Research on physical and mechanical properties of fabric selected for special clothing of preschool children	
Yangiboev R., Allakulov B., Gulmirzayeva S.	45
Studying the alternative technological factors of the loom in the production of textiles based on basalt yarn	
Ganikhanov Kh., Mavlyanov A., Abdusamatov A., Mirzaumidov A.	55
Analysis of the maintechnologicalparameters of the condenser	
Mavlyanov A., Mirzaumidov A.	60
The scientific basis of the lightened shaft	
Elmanov A., Mirzaumidov A.	69
Modeling of laser processingof thin-walled steel gears	
Nurillaeva Kh., Mirzaumidov A.	77
Cotton cleaner with multifaceted grates	
Ganikhanov Kh., Mavlyanov A., Abdusamatov A., Mirzaumidov A.	83
The equation of motion of cotton fiber in the condenser	
Khuramova Kh., Xoshimxojaev M.	89
Progressive method of cotton regeneration	

Abdulkarimova M., Lutfullaev R., Usmanova N., Mahsudov Sh.	94
Evaluation of aestheticity of women's dress models based on deep learning models	

GROWING, STORAGE, PROCESSING AND AGRICULTURAL PRODUCTS AND FOOD TECHNOLOGIES

Zufarov O., Isroilova Sh., Yulchiev A., Serkayev K.	101
Theoretical aspects of obtaining oxidation-stable vegetable oils	
Toshboyeva S., Dadamirzaev M.	110
Filling sauces for canned fish and their layer kinetics	
Atamirzaeva S., Saribaeva D., Kayumova A.	115
Prospects for the use of rose hips in food technology	
Turgunpolatova Sh.	121
Study of the quality of fruit pastela products	
Sultanov S.	126
Analysis of experiments on the process of deodorization of vegetable oil using floating nozzles	
Adashev B.	132
Physical-chemical analysis of oil taken from seeds of safflower	
Ismailov M.	137
Influence of surface layer thickness on hydraulic resistance of the device	
Khurmamatov A., Boyturayev S., Shomansurov F.	142
Detailed analysis of the physicochemical characteristics of distillate fractions	
Madaminova Z., Khamdamov A., Xudayberdiyev A.	154
Preparing peach seed for oil extraction and improving oil extraction through pressing	
Aripova K.	162
Methods of concentration of fruit juices and their analysis	
Djuraev Kh., Urinov Sh.	168
Theoretical and experimental study of the crack formation device in the shell of apricot kernels	

CHEMICAL TECHNOLOGIES

Urinboeva M., Abdikamalova A., Ergashev O., Eshmetov I., Ismadiyarov A.	175
Study of the composition and main characteristics of petroleum oils and their emulsions	
Tursunqulov J., Kutlimurotova N.	182
Application of 1-(2-hydroxy-1-naphthoazo)-2-naphthol-4-sulfo acid in amperometric determination of scandium ion	
Kucharov A.	191

Development of coal enrichment and gas extraction technology for the use of construction materials industrial enterprises	
Abdulkhaev T., Mukhammadjonov M., Mirzarakhimova F.	
Isotherm of benzene adsorption and differential heat of adsorption on AgZSM-5 zeolite	198
Vladimir L., Eshbaeva U., M.Ergashev	
Innovative environmental packaging for separating storage of two components, allowing to extend the lifetime without preservatives	204
Kodirov O., Ergashev O.	
Energetics of adsorption of water molecules to aerosol	212
Yusupov K., Erkabaev F., Ergashev D., Rakhimov U., Numonov M.	
Synthesis of melamine-formaldehyde resins modified with n-butanol	219
Ergashev O., Abdikamalova A., Bakhronov Kh., Askarova D., Xudoyberdiyev N., Mekhmonkhonov M., Xolikov K.	
Thermodynamics of Congo red dye adsorption processes on mineral and carbon adsorbents	228
Ergashev O., Maxmudov I.	
Water vapor adsorption isotherm in zeolites regenerated by microwave thermoxidation method	235
Jumaeva D., Zaripbaev K., Maxmudov F.	
The elements and oxide content of the chemical composition of the feldspar	242
MECHANICS AND ENGINEERING	
Khudoyberdiev U., Izzatillaev J.	
Analysis of research on small wind energy devices	249
Atajonova S.	
Mathematical model of system analysis of technological processes in the form of key principles for effective decision-making	258
Kuchkarbayev R.	
Mathematical modeling of heat transfer through single-layer and multi-layer cylindrical walls in buildings and structures	264
Atambaev D.	
Difference in the length of individual yarn composition of twisted mixed yarn and comparative analysis of single-thread elongation deformations	269
Abdullayev S.	
Modeling the functionalities of an automated system for managing movement in the air	276
Turakulov A.	
Describing computational domains in applications for solving three-dimensional problems of technological processes	285
Mamaxonov A.	

Mathematical model of machine aggregate of tillage equipment process	293
Khudayberdiyev A.	
Technical and economic aspects of processing pyrolysis distillate into motor fuel	304
Abdurahmonov J.	
Research results on the selection of the mesh surface of a lint-cleaning device	311
Vohidov M.	
Development of a program for determining eccentricity by analyzing the magnetic field in the air gap of an asynchronous motor	319
Utaev S., Turaev A.	
Analysis of methods and prospects for application of optical methods for control of working surfaces of cylinder liners of internal combustion engines	327
Boltabayev B.	
Determination of seed damage in the pneumatic transport system by conducting experiments	335
Azizov Sh., Usmanov O.	
Simulation of equation of motion of the new construction gin machine	339
Sharibaev N., Homidov K.	
Theoretical analysis of the coefficient of friction induced by the pressure force of a vertical rope acting from above and below	347
Aliyev B., Shamshidinov M.	
Improvement of the linter machine and development of its working scheme	356
Mukhametshina E.	
Analysis of cotton flow behavior in different pneumatic pipes	362
Yangiboev R., Allakulov B.	
Obtaining and analyzing correlational mathematical models of the sizing process	369
Mirzakarimov M.	
Efficient separation of fibers from saw teeth in the newly designed gin machine	379
Azambayev M.	
Measures to improve the quality of fluff	387
Abdullayev R.	
Scientific innovative development of cotton gining	392
Kholmiraev F.	
Air flow control factors in pneumatic transport device	397
Sharibaev N., Makhmudov A.	
Separation of cotton from airflow in pneumatic transport systems of the cotton industry	404
Sharibaev N., Mirzabaev B.	

Effect of steam temperature on yarn moisture regulation in textile industry	410
Sultanov S., Salomova M., Mamatkulov O.	
Increasing the useful surface of the mesh surface	415
Muhammedova M.	
Kinematics of the foot in a healthy person's foot and ankle injury	421
ADVANCED PEDAGOGICAL TECHNOLOGIES IN EDUCATION	
Abdullayev H.	429
Algorithm for creating structured diagrams of automatic control systems	
Kodirov D., Ikromjonova N.	437
On delayed technological objects and their characteristics	
Uzokov F.	444
Graphing circles, parabolas, and hyperbolas using second-order linear equations in excel	
ECONOMICAL SCIENCES	
Zulfikarova D.	449
Issues of developing women's entrepreneurship	
Ergashev U., Djurabaev O.	455
Methods for assessing the effectiveness of waste recycling business activities in the environmental sector	