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STUDY OF THE DYNAMICS OF THE DRIVE MECHANISM OF MOVING NEEDLES

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Abstract: This article examines design issues and calculations that take into account the dynamic nature of loads acting on machines. As is well known, all bodies with mass and elasticity are capable of oscillatory motion. Unwanted vibrations in a mechanism can reduce the strength of the connection between parts, disrupt the machine's technological process, or ultimately lead to failure of the mechanism or machine. The goal of vibration analysis is to determine the parameters of an oscillatory system that will ensure optimal operating conditions.

Keywords: dynamics, vibrations, displacement, kinematic disturbance, needle bed, knitting and stitching machine, drive, mechanism, loop formation, frequency.

Introduction. Modern industry is characterized by high-speed process equipment used to produce both consumer and industrial goods. Therefore, calculations that take into account the dynamic nature of the loads acting on machines play an increasingly important role in the design of new equipment [1]. In particular, calculations of machines, mechanisms, and individual components for vibrations caused by process and inertial loads arising during machine operation are of great importance.

The overall performance of a knitting-stitching machine is determined by the perfection of the loop-forming system and the drive mechanisms of the working elements. The loop formation process on knitting-stitching machines is carried out simultaneously, in which all the machine needles move simultaneously, as in the production of knitwear on warp knitting machines [2, 3]. One of the features of the technological process carried out on knitting-stitching machines is the need to pierce the fibrous web with moving needles, and the technological load arising from piercing the fibrous web makes a significant contribution to the workload on the moving needle drive.[4].An important characteristic of the newly designed drive of the sliding needles is the natural frequency of the beams, knowledge of which allows one to avoid possible resonances of the structure at operating speed. The sliders and rods of the sliding needles of the VP-II, VP-180M, and Maliwatt knitting and stitching machines have a rectilinear reciprocating motion [5]. A significant drawback of these mechanisms is the presence of a kinematic pair of sliders and guides. This pair requires continuous lubrication during operation. To eliminate this drawback, a new mechanism for driving the sliding needles and contains an elastic link, while the driven link of the mechanism is a connecting rod that performs a flat movement.[6].

Supported system. In these mechanisms, the kinematic disturbance is applied not to the mass itself, but to the support or base of the system. In this case, both the absolute and relative motion of the mass and base are of interest.

Let us first consider the absolute motion $x_2(t)$ of mass m (Fig. 1).

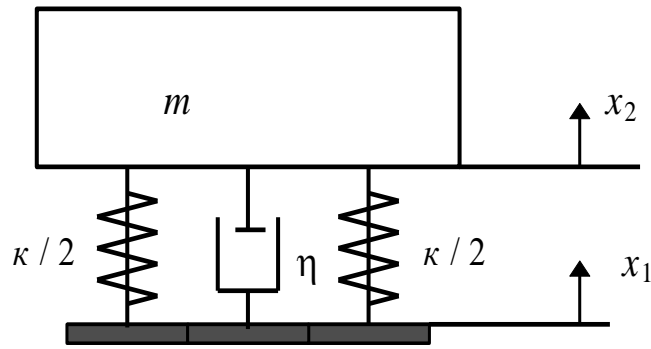


Fig. 1. System on substructure supports

If the base of the system moves according to a given law $x_1(t)$. According to Newton's second law, we will have

$$m\ddot{x}_2 = \sum X_i = -k(x_2 - x_1) - \eta(\dot{x}_2 - \dot{x}_1)$$

or

$$m\ddot{x}_2 + \eta\dot{x}_2 + kx_2 = \eta\dot{x}_1 + kx_1 \quad (1.)$$

Let $x_1(t) = a \sin \omega t$. Then (using the abbreviation for shorthand notation $\frac{\omega}{p} = c$),

$$m\ddot{x}_2 + \eta\dot{x}_2 + kx_2 = \eta a \omega \cos \omega t + k a \sin \omega t = a \sqrt{1 + (2\zeta c)^2} \sin(\omega t + \gamma),$$

Where $\gamma = \arctg(2\zeta c)$.

If for a given frequency ω coefficient of $\sin(\omega t + \gamma)$ is a constant value, then, denoting it by $F\vartheta$, we can write

$$m\ddot{x}_2 + \eta\dot{x}_2 + kx_2 = F\vartheta \sin(\omega t + \gamma). \quad (2)$$

We know a particular solution to this equation:

$$x_{2 \text{ hours}} = \frac{F\vartheta}{k} \chi \sin(\omega t + \gamma - \varphi),$$

$$\text{Where } \chi = \frac{1}{\sqrt{(1 - c^2)^2 + (2\zeta c)^2}}; \quad \varphi = \arctg \frac{2\zeta c}{1 - c^2}.$$

Substituting the expression for $F\vartheta$ into the equation, we get

$$x_{2 \text{ hours}} = a \sqrt{1 + (2\zeta c)^2} \chi \sin(\omega t + \gamma - \varphi). \quad (3)$$

From formula (3) it is clear that as ω/p the amplitude value x_{2h} will change in the same way as the dynamic gain factor χ , i.e. $x_{2h} \rightarrow 0$ at $\omega/p \rightarrow \infty$.

If we accept that $\omega \rightarrow \infty$ (the machine is installed without intermediate elements on a movable base), then $p \rightarrow \infty$, $\omega/p \rightarrow 0$ and $x_{2h} \max \rightarrow a$, i.e. the mass will move together with the base.

In many cases, this situation is undesirable. For example, suppose a precision metal-cutting machine is located on the second floor of a production facility (a rare, but possible, occurrence).

Due to vibrations in the ceiling, the machine may not be able to provide the required accuracy of processing the part.

Then it is installed on springs, the rigidity of which is selected so that x_{2h} does not exceed the specified value.

Let's look at an example. It is necessary to select the rigidity of the elastic suspension of the machine so that when $\zeta = 0.1$ the maximum amplitude x_{2hmax} of the machine oscillations was equal to (or less than) $0.1a$, i.e.

$$x_{2h \max} = 0.1a = \frac{a\sqrt{1+0,04c^2}}{\sqrt{(1-c^2)^2 + 0,04c^2}}.$$

Having solved this equality, we obtain $c^2 = (\omega/p)^2 = 13.37$.

Since $p^2 = k / m$, the suspension stiffness is determined by the formula

$$T_0 \leq \frac{m\omega^2}{13,37}.$$

Of great interest is the relative displacement of the mass and the base.

The relative displacement is defined as the difference between the absolute displacement x_2 of the mass and the given or known movement x_1 of the base, i.e.

$$x = x_2 - x_1.$$

From here

$$x_2 = x + x_1.$$

Substituting x_2 into equation (1.35), we obtain

$$m\ddot{x} + \eta\dot{x} + kx = -m\ddot{x}_1 = m\omega^2 a \sin \omega t. \quad (4)$$

The particular solution will be written as follows:

$$x_h = \frac{m\omega^2 a}{\kappa} \chi \sin(\omega t - \varphi) = c^2 \chi a \sin(\omega t - \varphi); \quad \varphi = \text{arctg} \frac{2\zeta c}{1-c^2}. \quad (5)$$

Factor $c^2 \chi$ is an indicator of the deviation of the amplitude of relative motion from the given kinematic amplitude a .

Let us plot a graph of the change in this multiplier (Fig. 2).

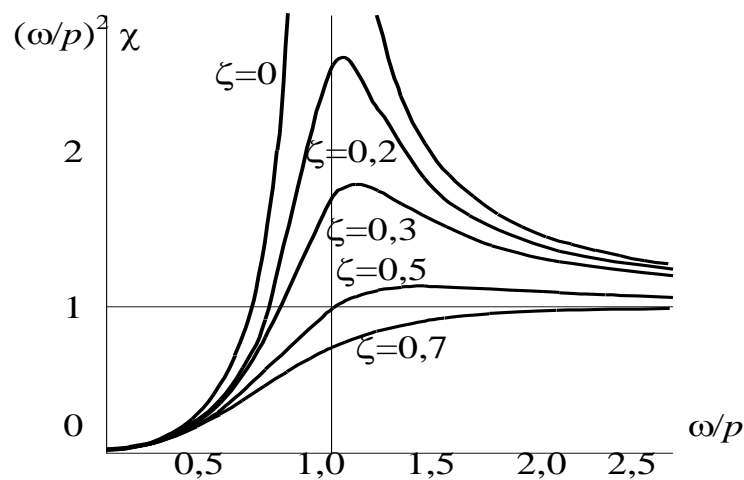


Fig. 2. Graph of changes

As can be seen from the graph, in the high frequency region the value $c^2\chi$ approaches 1. In fact, when $\omega/p \rightarrow \infty$ magnitude $c^2\chi \rightarrow 1$

$$\lim_{c \rightarrow \infty} \frac{c^2}{\sqrt{(1-c^2)^2 + (2\zeta c)^2}} = \lim_{c \rightarrow \infty} \frac{1}{\sqrt{(1/c^2 - 1)^2 + (2\zeta/c)^2}} = 1. \quad (6)$$

It should be noted that the phase angle of the relative displacement x in this case does not coincide with the phase of the base movement by almost 180°.

Indeed, when $\omega/p \rightarrow \infty$ (see equation (5))

$$\text{tg}\varphi = \frac{\sin 180^\circ}{\cos 180^\circ} = -0.$$

Let us use the above and consider how to obtain the equations of motion of the system with unbalanced rotational and reciprocating movements.

In knitting and stitching machines, the needle bar develops the greatest inertial force compared to other mechanisms.

The diagram of the machine is shown in Fig. 3. The reciprocating mass m_n consists of the mass of the needle bed, the mass of the rods and part of the mass of the connecting rods.

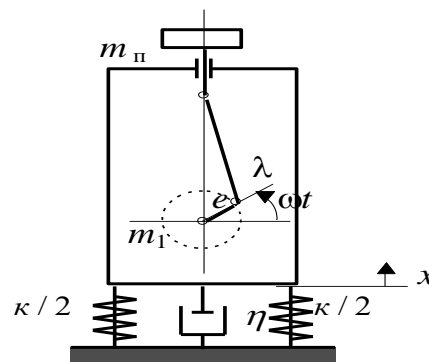


Fig. 3. Model of the mechanism

The inertial force of the reciprocating motion of the mass m_n is approximately equal to

$$P_{\text{And}} = m_n p \omega^2 e (\sin \omega t + e/l \sin 2\omega t).$$

If e/l is small, which is practically the case in warp knitting (knitting-stitching) machines, then the second term can be neglected and then

$$F_{\text{eh}} = m_n p \omega^2 e; F(t) = F \sin \omega t.$$

Conclusion. Thus, harmonic excitation occurs in a wide range of textile and light industry machines. The resulting relationships can be used to analyze the dynamics of these machines.

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CONTENTS

TECHNICAL SCIENCES: COTTON, TEXTILE AND LIGHT INDUSTRY

Dustkobilov U.	
Circular economy practices in the textile industry: Current status, indicators, and development opportunities	3
Kuldashov G., Oripov J.	
Forecasting the temperature gradient of cotton revolt	10
Kuldashov G., Oripov J.	
Optoelectronic three-wave moisture meter of raw cotton	16
Umarov A.	
Research on the optimization of the saw gin's roll box	26
Tursunov A., Sharibaev N.	
Techniques and devices for mitigating environmental pollution in cotton processing industries	36
Ganikhanov Kh., Mavlyanov A., Abdusamatov A., Mirzaumidov A.	
Effect of the forces on the separation of fiber flow from the saw in an improved lower fiber removal device	43
Nurulloyeva Kh., Abdusamatov A., Mirzaumidov A.	
Experimental determination of the load on the multifaceted columns on the elastic supports of the cotton ginner	49
Muradov A.	
Study of the dynamics of the drive mechanism of moving needles	54
Ismatullayev N., Shamsiyeva M.	
Development of technology for producing leather from african catfish skins	59
Rahmatova S.	
Theoretical study of the quality indicators of newly structured knitted fabrics based on a mathematical model	65
Parpieva N., Kayumov J., Parpiyev D., Lastochkin P.	
Theory of torsional vibrations of grooved cylinders	71
Komilov Sh., Mamadaliyev N., Jurayeva G.	
Quality indicators of cotton fiber analyzed	83

TECHNICAL SCIENCES: AGRICULTURE AND FOOD TECHNOLOGIES

Sobirova M., Mohamed R., Farmonov J., Samadiy M.	
Impact of calcium chloride on the cheese yield during swiss cheese manufacturing process	91

Kurayazov Z., Ravshanov S., Kanoatov X.	
Analysis of the influence of the whitening process during preparation for flouring on the quality of bakery flour made from a mixture of wheat and rye grains	96
Xusanxodjayeva F., Meliboyev M., Ergashev O.	
Development of technology for complex processing of garlic onions	105
Meliboyev M.	
Development of complex processing technology for the secondary mass of watermelons and zucchini	112
Nishonov U., Mominov U.	
Evaluation of organoleptic properties of soft drinks prepared from plant materials	118
Khurmamatov A., Yusupova N., Sarsenbayev N., Mallabayev O.	
Results of determination of bitumen movement modes at different temperatures	124
Yusupova N., Sarsenbayev N., Mallabayev O.	
Results of improving the construction of the plate heat exchange	130

CHEMICAL SCIENCES

Jumayeva D., Zaripbaev K., Oxunjonov Z., Nomonova Z.	
Compositional analysis of raw materials in sorbent production	135
Abdumalikov A., Ummatov O., Mamajonov B., Esonkulova N., Ochilov G.	
Thermal treatment of various samples of low-molecular-weight polyethylene – a by-product of polyethylene production	145
Mamajonova M., Salixanova D., Abduraxmonov E., Ismailova M.	
Energetics of water molecule adsorption on modified bentonite surfaces	153
Abdurahimov A., Abdullayeva F., Usmonova Z.	
Infrared spectroscopic analysis of the purification of sunflower oil from waxy substances using perlite and vermiculite	160
Eshbaeva U., Gökhan Z., Bahri B.	
Theoretical foundations for ensuring the mechanical strength of papers containing collagen hydrolysates	167
Eshbaeva U.	
Research on the printing and technical properties of kraft paper incorporating "cotton cellulose-industrial waste-paculate"	172
Makhkamova D.	
Research on the separation of zinc from metallurgy waste with a mixture of ammonia and ammonium salts	181
Yuldasheva M., Makhkamova D., Turayev Z	
	188

Study of interaction of components in the H_3BO_3 – KNO_3 – H_2O system	
Juraev M., Siddikov D., Askarova O.	
Aboveground components of salvia sarawschanica	194
Davlatova O.	
Zeolite-based bimetallic composite catalysts for pyrolysis and gasification: chemical technologies for deep biofuel upgrading and conversion intensification	202
Davlatova O.	
Use of BaNaY faujasite zeolite-based bimetallic composite catalysts for deep biofuel purification and selective xylene separation	208
Shamuratova M., Giyasidinov A., Eshmetov I., Nurjanova G.	
On the study of physicochemical properties of soils in the regions of the republic	214
Hoshimov F., Lutpillayeva M.	
Optimized chemical synthesis of stable silver nanoparticles using various reducing and stabilizing agents	220
Sarimsakova N.	
Investigation of the adsorption properties of the sorbent obtained in the process of modification of clinoptilothite in the purification of natural gas from sulfur compounds	227
Kokharov M., Bakhronov Kh., Sultonov A., Jumaeva D., Jumaboeva Z., Gaybullayeva D., Abdumutalova G.	
Adsorption isotherm of hydrogen sulfide on an activated adsorbent derived from hybrid paulownia tomentosa wood	234
Ikramov M., Zakirov B.	
Optimization of the aqueous solubility of monoammonium phosphate, potassium nitrate, and magnesium nitrate via thermodynamic analysis and selective crystallization	243
Nazhimova N., Seitnazarova O.	
Study of the chemical and mineralogical composition of thermal power plant wastes	249

TECHNICAL SCIENCES: MECHANICS AND MECHANICAL ENGINEERING

Berdiev U., Hasanov F., Avazov B., Ostanayev., Viktor M.	
Study of the nature and prospects of practical application of the magnetocaloric effect in energy-efficient cooling systems	256

Sodikov T.	
Research of mechanical part of solar photovoltaic power station	263
Otamirzayev D.	
Calculation of absorption coefficient of organic dye N719 for dye-sensitive solar cell (DSSC)	270
Abdovakhidov M.	
Study on determining the bending and torsional stiffness of packaged working bodies	276
Abdovakhidov M.	
The study torsion fluctuations packet worker organ with provision for influences of the correlation longitudinal acerbity their element	280
Shodmonov J.	
Energy-integrated smart textiles: international trends and prospects for uzbekistan's research ecosystem	285
Djurayev Sh.	
Integrated genetic-differential evolution approach for simultaneous pressure-drop reduction and efficiency enhancement in multi-cyclone dust collectors	292
Mamaxanova Z.	
Technological principles for creating a suit that ensures high reliability and safety in aquatic environments	297
Pirnazarov U.	
Theoretic observation of the cotton movement in the operating camera of the new separator	306
Pirnazarov U.	
Investigation of the interaction between the moving separator screen surface and the cotton mass	315
Yusupov D., Abduraximov D., Muxammadjonov M.	
Determination of energy loss in the magnetic core of oil power transformers under long-term operation conditions	319

ADVANCED PEDAGOGICAL TECHNOLOGIES IN EDUCATION

Abdullayev X.	
Transition function of second-order element	326

ECONOMICAL SCIENCES

Isroilov R.	
Criteria, indicators and laws of small business development	331

Isroilov R.

Concept of assessment of the economic development potential of small business and its evaluation **340**

Bustonov M.

Econometric analysis of the activities of multi-sectoral farms **348**

Bustonov M.

Global digitalization: paths and problems **356**

Kadirova Kh.

Prospects for development and improvement of the mechanism of functioning of the stock market **366**
