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Increasing demand for fine materials in many industries from one hand, and high power consumption level of grinding process from another hand, makes the task of increasing of fine grinding mill productivity actual one. The aim of the work is to develop a system for monitoring and controlling the jet grinding plant productivity based on the results of acoustic monitoring of its working areas. The new approach consists in the constant control of the material granulometric composition and the formation of control actions over the circulating load of the grinding plant on the basis of the acoustic signal characteristic analysis.

The main factors influencing on the material jet grinding efficiency are investigated. The constructed three-level model takes into account the features of the closed grinding cycle, the kinetics of the material granulometric composition in the grinding chamber, and the connection of the process with the acoustic signals characteristics. It is shown that for obtaining high productivity for ready ground product of a given size, it is necessary to control

the acoustic signals of the grinding zone and to regulate the grinding chamber feeding according to them, while maintaining it at the optimum level. These studies can be a basis for the development of an automated control system for a jet grinding plant. The additional installation of a control system in the transportation area of the ready product behind the classifier as the "granulometer" type model allow introducing an additional correction that makes the quality monitoring practically continuous. According to the characteristics of the recorded acoustic signals, the system automatically determines the presence in the two-phase flow of particles larger than the control class and indicates the need for adjusting the classification mode. The elimination of the probability of re-grinding improves product quality and reduces the energy consumption of the process. These researches are basis for improving model and development of jet grinding automatic control system.

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1 0,001 [2]. , -

[3]. , -

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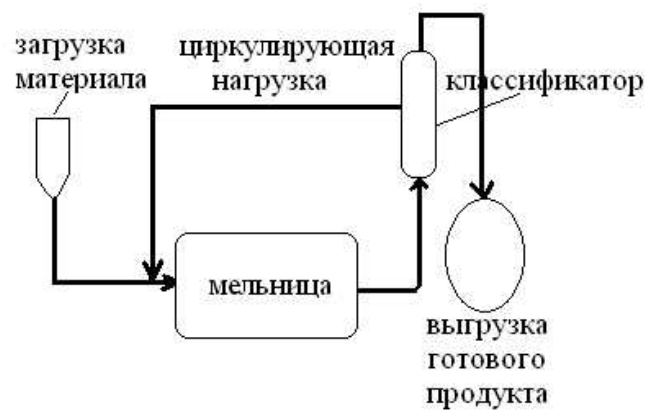
[4]. -

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 [4 - 8]. -
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 [2]. -
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 [10]. -
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. 2.



. 2 –

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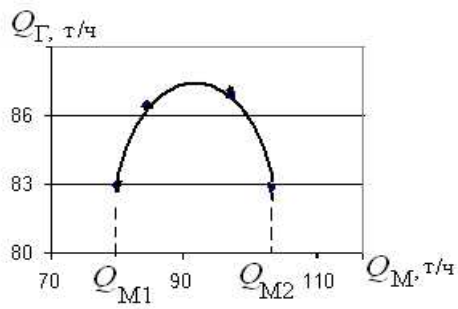
[7]

[2]:

$$Q_T = a_0 + a_1 Q_M - a_2 Q_M^2, \quad (1)$$

$Q_T, / -$
 $Q_M, / -$
 .3

, $a_i -$



.3-

(Q_{M1})

:

Q_T

Q_M

Q_{M2}

Q_T

Q_T

Q_M

$$Q_M = Q_{M2},$$

Q_{M1}

Q_{M2}

Q_T

Q_{M1}

[2, 10]

[2].

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()

$A_i, i = 1, 2, \dots, m, \quad i=1$ A_{\max} m

$N = (n_i), i = 1, \dots, m, \quad n_i$
 A_i
 A_i

Dt
 $t_k = kDt, \quad k = 1, 2, \dots$
 k

N^k N^{k+1}
 $A^k = \{A_{ij}\}$

[11].

$A^{k+1} = GA^k, G = g_{ij}$

$$G = \begin{bmatrix} g_{11} & 0 & \dots & 0 \\ g_{21} & g_{22} & 0 & \dots & 0 \\ \dots & \dots & \dots & \dots & \dots \\ g_{m1} & g_{m2} & g_{m3} & \dots & 1 \end{bmatrix} = \begin{bmatrix} 1 - S_1 \Delta t & 0 & \dots & 0 \\ S_1 b_{21} \Delta t & 1 - S_2 \Delta t & \dots & 0 \\ \dots & \dots & \dots & \dots \\ S_1 b_{m1} \Delta t & S_2 b_{m2} \Delta t & \dots & 1 \end{bmatrix}, \quad (2)$$

S b $S(A)$

$A_i, \Delta n_i^- = n_i S_i \Delta t$

$B = \{b_j\}$

$$Dn_i^+ = \sum_j b_{ij} n_i S_i Dt = Dn_i^- \sum_j b_{ij} \cdot$$

$$P(A) = \frac{1}{t} \sum_{i=1}^m n_i A_i^2. \quad (3)$$

$$S_i = \frac{1 - P_i}{\Delta t}, \quad B_i = \frac{P_i}{S_i \Delta t}. \quad (4)$$

[3],

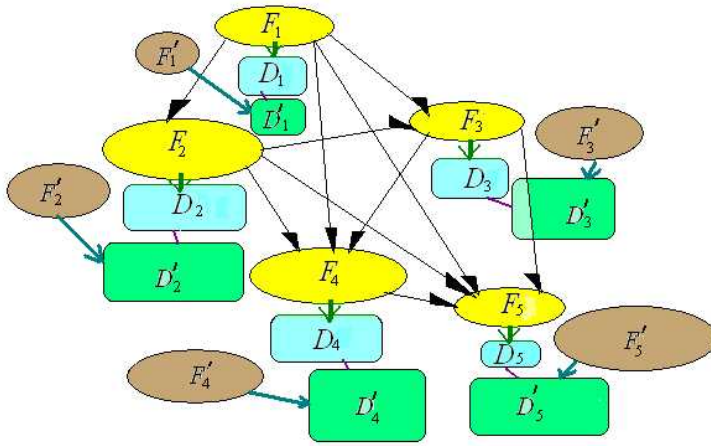
[11]. (. . .1),

[10, 12] (. . .) , « . . . » , . . .

F_5 .

$F_i, i = 1 \div 5,$

(. . . .4).



. 4 -

$$\begin{matrix}
 & F_1, F_2, F_3, F_4 & \\
 F_5 & \left(\begin{matrix} \cdot & \cdot & \cdot & \cdot \\ \cdot & \cdot & \cdot & \cdot \\ \cdot & \cdot & \cdot & \cdot \\ \cdot & \cdot & \cdot & \cdot \end{matrix} \right) & [15]
 \end{matrix}$$

[12].

$$\begin{matrix}
 F_i & t_1 & D_i \\
 t_2 & (F_i^{\ddot{y}}), & \\
 & D_i^{\ddot{y}} (\dots . 4). &
 \end{matrix}$$

$$\frac{d(F_i)}{dt} = - \sum_{j=1}^5 k_{ij} F_j \quad (5)$$

$$k_{5j} = -1, \quad k_{ij},$$

j - , i -

(« »)

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