

## SECTION 11.

### SYSTEM ANALYSIS, MODELING AND OPTIMIZATION

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## A FULL-FACTOR ANALYTICAL MODEL OF DIMENSIONAL DISTORTION IN SINGLE-TOOL MACHINING SETUPS CONSIDERING TRANSLATIONAL AND ANGULAR DISPLACEMENTS

***Abstract.** This paper presents a full-factor analytical model for dimensional distortion in single-tool machining setups, taking into account both translational and angular displacements of the technological system subsystems. It is shown that in machining operations involving workpieces with significantly anisotropic dimensions, angular displacements induced by cutting forces can substantially affect the overall machining accuracy. Unlike previously proposed models, which are limited in scope and often inconsistent with the general principles of the mechanics of elastically deformable systems, the developed model is based on a rigorous matrix formulation of compliance characteristics. The model incorporates both translational and rotational compliance matrices, as well as coordinate transformation matrices associated with the point of force application. A generalized expression for dimensional distortion is derived as a combination of translational and angular components, reflecting the full set of six degrees of freedom. The resulting full-factor model provides a unified and physically consistent framework for analyzing machining errors in single-tool setups. The proposed model can serve as a theoretical basis for improving accuracy prediction, technological process design, and further development of computer-aided manufacturing systems.*

**Introduction.** In practice, there are frequent cases where workpieces with significantly different overall dimensions in different directions are machined in turning operations. In such cases, rotations of the workpiece can make a substantial contribution to machining errors, especially along the directions of dominant overall dimensions [1-25]. The necessity of accounting for angular displacements of the workpiece under cutting forces was already emphasized in the several works. They proposed even simple analytical relationships for calculating such angular displacements [26-68].

However, all these relationships are of a particular nature and include parameters whose determination in practice is associated with significant difficulties [69-114]. For example, the spindle rotation center is a virtual object that cannot be directly measured. Most importantly, these models are not consistent with the general laws of mechanics of elastically deformable systems. Therefore, they cannot be used to construct a unified theory of machining accuracy that accounts for possible angular displacements of technological system subsystems.

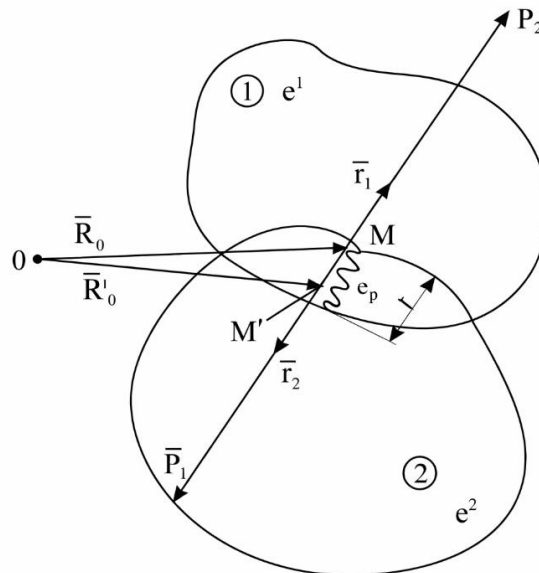
The fixation of a rigid body in space is achieved by imposing constraints on each degree of freedom. Three constraints limit translational motion along the coordinate axes, while three constraints limit rotational motion about these axes. The degree of motion restriction introduced by a constraint is characterized by its stiffness or, inversely, its compliance. In the contact interaction model of a two-body system (Fig. 1), considering only translational (planar) movements, the transformation into a full-factor model is carried out as follows:

For the first body [72-80]:

$$\bar{u}_1 = (\mathbf{e}_1 - \mathbf{a}_{0_1}^1 \xi_1 \mathbf{a}_{0_1}^1) \bar{P}_1 \quad (1)$$

For the second body [72-80]:

$$\bar{u}_2 = (\mathbf{e}_2 - \mathbf{a}_{0_2}^2 \xi_2 \mathbf{a}_{0_2}^2) \bar{P}_2 \quad (2)$$



**Fig. 1. Schematic diagram of force interaction in a two-body system.**  
**Notation:**  $\bar{P}_1$  – force exerted by body 1 on body 2;  $\bar{P}_2$  – force exerted by body 2 on body 1;  $\bar{r}_1$  – elastic displacement of body 1;  $\bar{r}_2$  – elastic displacement of body 2;  $t$  – parameter defining the level of force interaction;  $e^1$  – compliance characteristic of body 1;  $e^2$  – compliance characteristic of body 2.

Here, the following notation is used [72–75]:

- $e_1$  and  $e_2$  matrices of translational compliance of bodies 1 and 2, respectively;
- $\xi_1$  and  $\xi_2$  matrices of rotational compliance of bodies 1 and 2, respectively;
- $a_{O_1}^1$  and  $a_{O_2}^2$  matrices defining coordinate vectors of the force application point for bodies 1 and 2;
- $O_1(x_0^1, y_0^1, z_0^1)$  and  $O_2(x_0^2, y_0^2, z_0^2)$  base points of bodies 1 and 2 (reference points for angular displacements).

For each contacting body, its coordinate vector is defined as:

$$\overline{R}_1 = \overline{O_1A} = \{x^1 - x_0^1; y^1 - y_0^1; z^1 - z_0^1\} \quad (3)$$

$$\overline{R}_2 = \overline{O_2A} = \{x^2 - x_0^2; y^2 - y_0^2; z^2 - z_0^2\} \quad (4)$$

The vector  $\overline{M^1M^2}$  (Fig. 1), representing the displacement of the contact point due to elastic interaction (where  $M$  is the initial contact position,  $M^1$  and  $M^2$  and are the positions of the point on bodies 1 and 2 in the deformed state), is determined as the difference of partial displacement vectors of each body:

$$\overline{M^1M^2} = \overline{w} = \overline{u}_2 - \overline{u}_1 \quad (5)$$

Since the vectors  $\overline{u}_1$  and  $\overline{u}_2$  represent the total displacements of the force application point on each body, the vector  $\overline{w}$  characterizes the displacement of the contact point, i.e., the total dimensional distortion caused by both translational and angular displacements of the deformable bodies. Taking into account expressions (1), (2), and the relationship, equation (5) takes the form:

$$\overline{w} = \left[ (e_1 - a_{O_1}^1 \xi_1 a_{O_1}^1) + (e_2 - a_{O_2}^2 \xi_2 a_{O_2}^2) \right] \overline{P} \quad (6)$$

where  $\overline{P}$  is the cutting force.

For translational displacements, the concept of a unified compliance matrix was previously introduced  $e_{12} = e_1 + e_2$  [3, 4]. However, from equation (6), it follows that for the full consideration of all six degrees of freedom, it is not possible to define a single unified compliance matrix, since the effective angular compliance matrices for given points of each body are products of three matrices. Therefore, only the previously introduced unified compliance matrix for translational displacements can be used. With its application, equation (6) is transformed into:

$$\overline{w} = \left[ e_{12} - (a_{O_1}^1 \xi_1 a_{O_1}^1 + a_{O_2}^2 \xi_2 a_{O_2}^2) \right] \overline{P} \quad (7)$$

Analysis of the full-factor dimensional distortion model (7) shows that, in accordance with the structure of the total displacement of a point in a body, a translational component can be distinguished:

$$\bar{u} = e_{12} \bar{P} \quad (8)$$

and a component due to angular displacements of the contacting bodies around their base points:

$$\bar{\delta} = -\left(a_{O_1}^1 \xi_1 a_{O_1}^1 + a_{O_2}^2 \xi_2 a_{O_2}^2\right) \bar{P} \quad (9)$$

Clearly, the angular component of dimensional distortion is also defined as the difference in angular displacements of the contact point on each contacting body:

$$\bar{\delta} = \bar{\rho}_2 - \bar{\rho}_1 \quad (10)$$

Thus, the full-factor model of dimensional distortion in a single-tool setup can be represented structurally as:

$$\bar{w} = \bar{u} + \bar{\delta} \quad (11)$$

Therefore, model (11) forms the basis for modeling dimensional distortion in single-tool setups, taking into account not only translational displacements of technological subsystems but also their angular displacements about base points.

**Conclusion.** A full-factor model of dimensional distortion in single-tool setups has been developed, accounting for both translational and angular displacements of interacting bodies within the technological system. In contrast to existing approaches, the proposed model is consistent with the fundamental principles of mechanics of elastic systems and does not rely on poorly measurable or virtual parameters.

The analysis has shown that dimensional distortion can be represented as the sum of two components: one caused by translational displacements and the other by angular displacements of the contacting bodies relative to their base points. This decomposition allows for a more accurate description of the physical nature of machining errors.

The developed model forms a unified analytical framework that can be applied to a wide range of machining conditions, particularly in cases where angular effects are significant. It can be used for improving the accuracy of machining process modeling, as well as for the development of advanced methodologies in process planning and computer-aided manufacturing systems.

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