

ANALYSIS AND CONTROL OF VIBRATION IN MACHINE TOOLS

This report is submitted in accordance with requirement of the Universiti Teknikal Malaysia Melaka (UTeM) for Bachelor Degree of Manufacturing Engineering (Robotics and Automation) (Hons.)

by

LIM KIM YEW B051310101 930531-14-5235

FACULTY OF MANUFACTURING ENGINEERING 2017

C Universiti Teknikal Malaysia Melaka

اونيۇم سېتى تېكنىكا ماللە اونيۇم سېتى تېكنىكا ماللە NIVERSITT TERNIKAL MALAYSIA MELAKA	
BORANG PENGESAHAN STAT	US LAPORAN PROJEK SARJANA MUDA
Tajuk: ANALYSIS AND CONTROL	OF VIBRATION IN MACHINE TOOLS
Sesi Pengajian: 2017 Semester 2	
Saya LIM KIM YEW (930531-14-52:	35)
mengaku membenarkan Laporan Proje Perpustakaan Universiti Teknikal Mala kegunaan seperti berikut:	k Sarjana Muda (PSM) ini disimpan di nysia Melaka (UTeM) dengan syarat-syarat
 Laporan PSM adalah hak milik Un Perpustakaan Universiti Teknikal M untuk tujuan pengajian sahaja deng Perpustakaan dibenarkan membuat pertukaran antara institusi pengajia *Sila tandakan (√) 	iversiti Teknikal Malaysia Melaka dan penulis. Malaysia Melaka dibenarkan membuat salinan gan izin penulis. salinan laporan PSM ini sebagai bahan m tinggi.
SULIT (Mengandungi maklu Malaysiasebagaimana TERHAD (Mengandungi maklu	umat yang berdarjah keselamatan atau kepentingan a yang termaktub dalam AKTA RAHSIA RASMI 19 umat TERHAD yang telah ditentukan oleh organisasi
TIDAK TERHAD	Disahkan oleh:
Yew	74
Alamat Tetap: 1306, Jalan 13/32, Tamar Jinjang Baru, 52000 Kuda Lumeur.	Cop Rasmi: ASSUC PROF Dil. ZAMBERI BIN JAMAL Paculty of Manufacturing Engineer Universiti Teknikal Malaysia Mela Hang Tuah Jaya
actual traction and its	and a second

C Universiti Teknikal Malaysia Melaka

DECLARATION

I hereby, declared this report entitled "Analysis and Control of Vibration In Machine Tools" is the result of my own research except as cited in references.

SignatureYewJAuthor's Name: LIM KIM YEWDate: 22nd JUNE 2017



APPROVAL

This report is submitted to the Faculty of Manufacturing Engineering of Universiti Teknikal Malaysia Melaka as a partial fulfilment of the requirement for Degree of Manufacturing Engineering (Robotics and Automation) (Hons). The members of the supervisory committee are as follow:

(Profesor Madya Dr Zamberi bin Jamaludin)

ASSOC. PROF. OR. ZAMBERI BIN JAMALUDIN Faculty of Manufacturing Engineering Universiti Teknikal Malaysia Melaka Hang Tuah Jaya

C Universiti Teknikal Malaysia Melaka

ABSTRAK

Antara tujuan bagi projek ini adalah untuk menganalisis ciri-ciri getaran alat mesin, mereka bentuk pengawal dan model pemerhati dan mengesahkan fungsi sistem kawalan. Ketepatan memainkan peranan penting dalam meningkatkan kualiti sistem kawalan. Walau bagaimanapun, getaran dikenali sebagai daya gangguan berpunca daripada pusingan alat mesin akan mengurangkan ketepatan sistem kawalan. Oleh itu, kesan getaran yang negatif perlulah disingkirkan dengan mereka bentuk satu pengawal bagi mengurangkan kesan buruk tersebut. Dalam kajian ini, pengawal "cascade P/PI" dan model pemerhati telah dipilih sebagai pengawal untuk mengawal getaran. Sistem penilaian telah dilakukan untuk mencari fungsi pemindahan. Kemudian, pengawal "cascade P/PI" dan model pemerhati telah direka bentuk dengan menggunakan perisian MATLAB Simulink dan kaedah "loop shaping" sambil mengambil kira faktors "gain margin", "phase margin", rajah "Nyquist" serta lebaran. Analisis berangka telah dijalankan dengan menggunakan perisian MATLAB Simulink. Dua parameter seperti kualiti penjejakan dari segi penjejakan ralat maksimum dan keupayaan mengurangkan gangguan dari segi penganalisis ralat min punca kuasa dua telah dikaji. Sistem kawalan tersebut telah dianalisis dengan mempunyai gangguan isyarat dan tanpa gangguan isyarat, maka perbandingan antaranya telah dibuat. Projek ini menggunakan "sinusoidal" isyarat sepenuhnya untuk kajian. XYZ mesin pengilangan digunakan sebagai sistem kedudukan manakala daya pemotongan dan "band limited white noise" digunakan sebagai gangguan isyarat. Seterusnya, pengesahan terhadap fungsi pengawal telah dibuat dengan menjalankan eksperimen XYZ mesin pengilangan. Keputusan yang diperolehi menunjukkan bahawa pengawal "cascade P/PI" berintegrasi dengan model pemerhati telah mengurangkan gangguan yang tinggi pada kadar 21 peratus. Untuk menambahbaikkan sistem pengawal tersebut, "speed feedforward" dicadangkan untuk meningkatkan keteguhan sistem kawalan.

ABSTRACT

The aim of this report is to analyze the characteristic of vibration on machine tools, to design a controller and an observer, and to validate the performance of control system. Precision and accuracy play important role in enhancing the performance and quality of the control system. However, vibration, is known as disturbance force that occur on machine tool can reduce the accuracy of the system. Hence, a compensator is required to design for mitigating the vibration effect to the system. In this project, a cascade P/PI controller and an inverse model based disturbance observer were chosen as compensator to control the vibration effect. Firstly, the behavior of the system was evaluated by finding its transfer function. Then, a cascade P/PI controller and disturbance observer were designed in MATLAB Simulink environment by applying the principle of traditional loop shaping method with taken into consideration on phase margin, gain margin, Nyquist diagram and bandwidth. Numerical analysis was carried out using MATLAB Simulink software. Two parameters were analyzed; disturbance rejection in root mean square tracking error and maximum amplitude of tracking error. The tracking performance of the control system was analyzed with and without input disturbances signals, then a comparison was made between them. A sinusoidal input reference was applied for this project. XYZ stage was used as positioning system whereas band limited white noise and cutting forces were utilized as emitting disturbance signal. To validate the performance of controller, an experimental analysis was conducted on the test setup. Based on the result obtained, a cascade P/PI controller with an add-on module, disturbance observer had reduced the disturbance efficiently by 21%. Further improvement was recommended by adding the speed feedforward to enhance the robustness of control system.

DEDICATION

Only

my beloved father, Lim Foo Lian my appreciated mother, Chong Yuen Yee my adored sister, Lim Mei Kee

for giving me moral support, money, cooperation, encouragement and also understandings Thank You So Much & Love You All Forever



ACKNOWLEDGEMENT

First and foremost, I would like to express my deepest appreciation to my respected supervisor, Profesor Madya Dr. Zamberi bin Jamaludin. His kindness, unwavering perseverance and mentorship supervised me, his teaching, explanations and positive thinking allowed me to grow and learn in such a way that I am now a better researcher. Furthermore, I would like to express my gratefulness to my beloved co-supervisor, Puan Nur Aidawaty binti Rafan for her supervision, advice and recommendations as well as exposing me with meaningful theories throughout the study and analyses.

Last but not least, I would like to give a special thanks to my best friends especially Chiew Tsung Heng, Madihah binti Haji Maharof, and Nur Amira Anang who gave me much encouragement, sincere advices and constructive suggestions in completing this report. I would like to extend my truthful thanks to all of them. Thanks for the great friendship.

Finally, I would like to sincerely thank my family members who gave me the moral motivation and spiritual support as well as expressing my sincerest apologies to all important person for my insensitive behaviours, words, disrespectful and embarrassment.

TABLE OF CONTENTS

Abst	rak	i		
Abst	ract	ii		
Dedi	cation	iii		
Ackn	nowledgement	iv		
Table	e of Contents	v		
List o	of Tables	ix		
List o	of Figures	xi		
List o	of Abbreviations	xiii		
List o	of Symbols	xiv		
СНА	APTER 1: INTRODUCTION			
1.1	Background of Study	1		
1.2	Problem Statement	2		
1.3	3 Objectives			
1.4	4 Scope			
1.5	Project Significance 3			
1.6	5 Contents of Report			
СНА	APTER 2: LITERATURE REVIEW			
2.1	Overview of Machining Process, Quality, and Issues	5		
	2.1.1 Overview of Milling Machine	6		
2.2	Overview of Vibration	7		
	2.2.1 Definition of Vibration	7		
	2.2.2 Negative Effect Caused By Vibration	8		
2.3	Causes of Vibration	8		
	2.3.1 Self-Excitation Mechanism	9		
	2.3.2 Rotating Machinery and Rotor Imbalance	10		

2.4	Classi	fications of Vibration	10
	2.4.1	Linear and Non-linear Vibration	11
	2.4.2	Terminologies of Vibration	11
	2.4.3	Deterministic and Random Vibrations	14
2.5	Vibra	tion Analysis	15
	2.5.1	Application of Mass-Spring-Damper Model	15
	2.5.2	Vibration Analysis Procedures	16
	2.5.3	Data Acquisition By Vibration Detectors	18
2.6	Vibra	tion of Machine Tools Under Rotational Motion	22
	2.6.1	Torsional Vibration	23
	2.6.2	Lateral Vibration	25
2.7	Vibra	tion Control	26
	2.7.1	PID Controller	27
	2.7.2	Cascade P/PI Controller	28
	2.7.3	Inverse Model Based Disturbance Observer	30
	2.7.4	Repetitive Controller	31
2.8	MAT	LAB	32
	2.8.1	MATLAB Simulink	32
	2.8.2	Tool for Interactive Simulation and Model-Based Design	33
2.9	Sumn	nary	34
СНА	PTER	3: METHODOLOGY	
3.1	Introd	luction	35

3.2	Project Implementation	35
3.3	Experimental Setup	38
	3.3.1 Software Simulation Tool	41
3.4	System Identification	41
3.5	Controller Design	45
3.6 Numerical Analysis		47
3.7	Experimental Analysis	48
3.8	Summary	49

CHAPTER 4: RESULTS & DISCUSSIONS

4.1	Controller Design		
	4.1.1	Design of Cascade P/PI Controller	
		4.1.1.1 Design of Velocity Loop and Loop Analysis	51
		4.1.1.2 Design of Position Loop and Loop Analysis	54
4.2	Casca	de P/PI Controller With Disturbance Observer	57
	4.2.1	Design and Analysis of Observer's Low Pass Q-filter	57
	4.2.2	Design and Analysis of Velocity Loop With Disturbance	
		Observer	59
	4.2.3	Design and Analysis of Position Loop With Disturbance	
		Observer	62
4.3	Valida	ation of Controller's Performance	64
	4.3.1	Tracking Performance Without Input Disturbance	65
	4.3.2	Tracking Performance With Input Disturbance	67
		4.3.2.1 Tracking Error Using Band Limited White	
		Noise As Input Disturbance	68
		4.3.2.2 Tracking Error Using Measured Cutting	
		Forces As Input Disturbance	70
4.4	Sumn	nary	79

CHAPTER 5: CONCLUSION AND RECOMMENDATIONS

5.1	Conclusion	80
5.2	Recommendations	81
5.3	Sustainability	83
REF	TERENCES	84

APPENDICES

A Simulink Control Scheme of Cascade P/PI Controller With Disturbance Observer

88

LIST OF TABLES

2.1	Factors of vibration for each mode	22	
2.2	Effect of vibration for each mode	23	
		70	
3.1	Gantt chart	30	
3.2	Model parameters	44	
3.3	Parameters for cascade P/PI controller	46	
3.4	Sample of simulated data collection table	48	
3.5	Sample of experimental data collection table	49	
4.1	Velocity loop controller parameters of x-axis	52	
4.2	Gain margin and phase margin of x-axis velocity open loop	52	
4.3	Gain margin and phase margin of x-axis position open loop	55	
4.4	Transient response characteristics	57	
4.5	Parameters of low pass Q-filter	59	
4.6	Gain margin and phase margin of x-axis velocity open loop	60	
4.7	Gain margin and phase margin of x-axis position open loop	63	
4.8	Bandwidth of velocity loop and position loop	64	
4.9	Simulated tracking error with sinusoidal input reference	65	
4.10	Experimental tracking error with sinusoidal input reference	66	
4.11	Experimental percentage error and friction reduction	67	
4.12	Simulated tracking error of sinusoidal input reference with white noise	68	
4.13	Experimental tracking error of sinusoidal input reference with white noise	69	
4.14	Relationship between cutting forces and spindle speeds	70	
4.15	Simulated tracking error of sinusoidal input reference with cutting forces	70	
4.16	Simulated results of Fast Fourier Transform (FFT)	74	
4.17	Simulated results of percentage error and friction reduction	74	
4.18	Experimental tracking error of sinusoidal input reference with		
	cutting forces	77	
4.19	Experimental results of Fast Fourier Transform (FFT)	78	

C Universiti Teknikal Malaysia Melaka

LIST OF FIGURES

2.1	Sinusoidal wave	12
2.2	Average, RMS and peak of sinusoidal wave	13
2.3(a)	A deterministic (periodic) excitation	14
2.3(b)	A random excitation	14
2.4	Mass-spring-damper model	15
2.5	Displacement probe and signal conditioning system	19
2.6	Schematic diagram of velocity transducer	20
2.7	Schematic diagram of accelerometer	21
2.8	Schematic diagram of laser vibrometer	21
2.9	Types of vibration	22
2.10	Mechanical modeling of torsional vibration	24
2,11	Forward and backward whirling	26
2.12	PID controller	28
2.13	Scheme of cascade control structure	29
2.14	Ideal block diagram of cascade controller structure	29
2.15	Inverse model based disturbance observer	30
2.16	Configuration of basic repetitive control system	31
3.1	Flowchart of conducting overall project of FYP	37
3.2	XYZ stage	39
3.3	Experimental setup of apparatus	39
3.4	Control structure diagram of XYZ stage	40
3.5	Flowchart of conducting system identification process	42
3.6	Open loop system for FRF measurement	42
3.7	Flowchart of conversion procedures	43
3.8	Bode plot for FRF measurement, x-axis	45
3.9	Flowchart of designing a controller	47
4.1	Control Scheme of cascade P/PI controller	51

C Universiti Teknikal Malaysia Melaka

4.2	Bode plot of velocity open loop transfer function	52
4.3	Nyquist plot of x-axis velocity open loop transfer function	53
4.4	Bode diagram of velocity closed loop transfer function	53
4.5	Bode plot of position open loop transfer function	54
4.6	Nyquist diagram of x-axis position open loop transfer function	55
4.7	Bode diagram of position closed loop transfer function	56
4.8	Step response of position closed loop transfer function	56
4.9	Magnitude plot of Bode diagram of Q-filter	59
4.10	Velocity open loop transfer function with IMBDO	60
4.11	Nyquist diagram of velocity open loop with and without IMBDO	61
4.12	Bode diagram of velocity closed loop with and without IMBDO	61
4.13	Position open loop transfer function with IMBDO	62
4.14	Nyquist diagram of position open loop with and without IMBDO	63
4.15	Bode diagram of position closed loop with and without IMBDO	64
4.16	Simulated tracking error with sinusoidal input reference	65
4.17	Experimental tracking error with sinusoidal input reference	66
4.18	Simulated tracking error for sinusoidal input reference with	
	white noise	68
4.19	Experimental tracking error for sinusoidal input reference	
	with white noise	69
4.20	Simulated tracking error for sinusoidal input reference with	
	1500 rpm	71
4.21	Simulated tracking error for sinusoidal input reference with	
	2500 rpm	72
4.22	Simulated tracking error for sinusoidal input reference with	
	3500 rpm	73
4.23	Experimental tracking error for sinusoidal input reference with	
	1500 rpm	75
4.24	Experimental tracking error for sinusoidal input reference with	
	2500 rpm	76
4.25	Experimental tracking error for sinusoidal input reference with	
	3500 rpm	77
5.1	H-infinity	82
	xii	

LIST OF ABBREVIATIONS

ASTM	18	American society for testing and materials	
DAC	(4)	Data acquisition unit	
FRF		Frequency Response Function	
FFT	j.	Fast Fourier Transform	
IMBDO		Inverse Model Based Disturbance Observer	
PID	с е П	Proportional-Integral-Derivative	
PI	- 12 - 12 - 12 - 12 - 12 - 12 - 12 - 12	Proportional-Integral	
Р	ie.	Proportional	
RMS	÷	Root Mean Square	

LIST OF SYMBOLS

mm	1911	Millimetre
vpm	÷	Vibration per minute
N	÷	Newton
Hz	1, 2 ,-	Hertz
0	-	Degree
dB	÷.	Decibel
m	1940 - E	Order of numerator
n	÷.	Order of denominator
w _c	÷.	Cut off frequency
rpm		Revolution per minute

xiv

CHAPTER 1

INTRODUCTION

This research is about the study and analysis of the vibration control of a milling machine where the machine tool is under rotational motion. Milling process normally leads to many types of vibration troubles. The research will demonstrate the understanding of the vibration troubles and how to minimize it.

1.1 Background of Study

Machine tool vibration basically is considered as undesirable phenomena. This undesirable vibration causes a huge problem in the manufacturing industry. Vibration occurs due to the excitation that appear on the material deformation and distortion. Sometimes, the long and slim drill bit is generally required to pre-drill hole as a marking on a work sample, thus totally contribute extra sensitive to the vibration. These vibrations will bring to some adverse effect such as low dimensional accuracy, poor surface finish of the work samples, undesirable noise, and most critically shorten the machine tool life.

Due to its critical effect to the machine tool, the vibration has been studied widely by some previous researchers to find out the preventive measures to mitigate vibration caused by the rotary machine tool. Tobias (1965) studied the unstable state of metal cutting process. The theory considered by Merchant (1944) was that the cutting force is directly proportional

to the depth of cut. According to Nigm *et al.* (1977), dimensional analysis of orthogonal cutting under steady cutting state can be applied in modeling the cutting process. Furthermore, Minis *et al.* (1990) obtained the cutting transfer function by referring to the dynamic cutting force model in which the transfer function can be used to predict vibration in turning process.

1.2 Problem Statement

The typical rotational machine tools used in the milling machine can cause three types of vibration which are axial, lateral, and torsional. Axial vibration occurs along the length of machine tool. Lateral vibration occurs due to unbalance force and instability acting the drill bit. Torsional vibration occurs due to non-linear load applied on the drill bit. The performance of system is controlled by several external factors which include voltage variation and input cutting forces. Thus, a position compensator and an observer are required to design for rejecting the vibration disturbance due to the machining effect. A good design compensator and an observer were very important to ensure good tracking performance.

1.3 Objectives

The objectives of this project are as follow:

- i. To analyze the vibration characteristics in machine tools.
- To design a controller and an observer to mitigate the vibration effect on machine tools.
- iii. To validate the performance of the control system.

1.4 Scopes

The scopes of this project are as follow:

- i. A XYZ feed table milling machine is used as positioning system.
- ii. Vibration is occurred due to the interaction of machine tool and workpiece during cutting process.
- iii. The control system consists of a cascade P/PI controller and an Inverse Model Based
 Disturbance Observer.
- iv. MATLAB and Simulink software are used for control design and performance analysis.
- v. Control performance analysis was based on transient response and frequency response characteristics.

1.5 Project Significance

This project plays a significant role in analyzing the vibration caused to machine tool. Firstly, vibration is identified as a critical problem to manufacturing industry. The root causes of vibration are studied and investigated. Once the causes are discovered, several alternatives and preventive measures are proposed to suppress the vibrations. Then, the most effective measure is selected to apply in this project. Next, the selected measure is then executed and implemented by designing a controller and an observer. Finally, the vibration absorber device is monitored regularly to reduce the vibration disturbance that came from the machining effect.

1.6 Contents of Report

This report is comprised of five chapters. Chapter one has been discussed as section above. Chapter two discussed the literature review of project based on previous researchers. It included the theories of vibration characteristics, causes and types of vibration, and the vibration control methods. The methods involved to collect the data and graphical presentation are covered in Chapter three. This is followed by the result and discussion in Chapter four which includes data presentation and tabulation, results interpretation, and discussion on vibration characteristics and how to control the vibration of machine tools. Finally, the conclusion and recommendations for future improvement are stated in Chapter five.

4

CHAPTER 2

LITERATURE REVIEW

This chapter relates information on vibration study and analysis in machine tools applications under rotational motion condition. The key topics covered in this chapter includes the overview of machining process, quality, and issues, fundamental of vibration, classifications, and terminologies of vibration, causes of vibration, vibration analysis, vibration of machine tools under rotational motion, vibration control, MATLAB Simulink, and summary.

2.1 Overview of Machining Process, Quality, and Issues

In recent decade, those technologies that applied in machining process have improved rapidly and widely. For example, numerical control is incorporated to enhance the computer monitoring system. Every year in the market, the ability of producing a new product has increased because the development of new ideas, concepts, tooling, materials, and manufacturing devices. Different machining processes have different demand. The increasing demand of market year by year, the accuracy, performance and flexibility are improved constantly to highest rate with creative and innovative solutions. Hence, all these enhancements greatly depend on the generation of precious knowledge and experiences. Besides that, the milling fundamental must be understood first, then proceed to conduct machining process. But this is a very difficult task because the complicated of chip formation mechanism. According to recent trend, the computers and sensors are widely used and being focused on the managing, controlling, planning and monitoring of the machining process. The diagnosis aspects like surface finish, dimensional accuracy, productivity, and identification of vibrations can be conducted by the development of sensors and signal processing skills. The manufacturing border has expanded due to the enhancement of science, technology, manufacturing skills and the pressure from high competitive market (Quintana and Ciurana, 2011).

2.1.1 Overview of Milling Machine

Milling is defined as the machining process of applying rotary cutting tool to shape the solid materials by feeding in a direction at an angle with the cutting tool axis. Milling machine includes diverse of operations such as boring, turning, surface finishing and so on. It is very popular applied processes in manufacturing industry today for shaping parts into desired size.

Meanwhile, the movements of cutting tool are normally perpendicular to the axis. As the machine tool enters the workpiece, the edge of cutter cut into and exit from the workpiece, chips are produced with each pass. Therefore, it removes the material with many separate and small cuts by spinning the machine tool in high speed or controlling the workpiece carefully and slowly.

Furthermore, cutter is very important in machining process. There are many types of tools that used in milling machine. The cutting surface of cutting tool is made of rigid and high temperature resistant material. The high speed steel is a manufacturing material for low cost cutting tools whereas the cemented carbide is for high cost cutting tool. Thin film will coat on the cutter to decrease friction and increase the hardness as well (Usher and John, 1896).

Despite of how perfect the operations and functions of milling machine, however, vibration is appeared as a limitation to enhance the productivity, dimensional accuracy, and product quality. This issue has been a controversial and common topic that needs to research and investigate. This project focuses on compensating effects of vibration in machine tools.