

FIG. 1

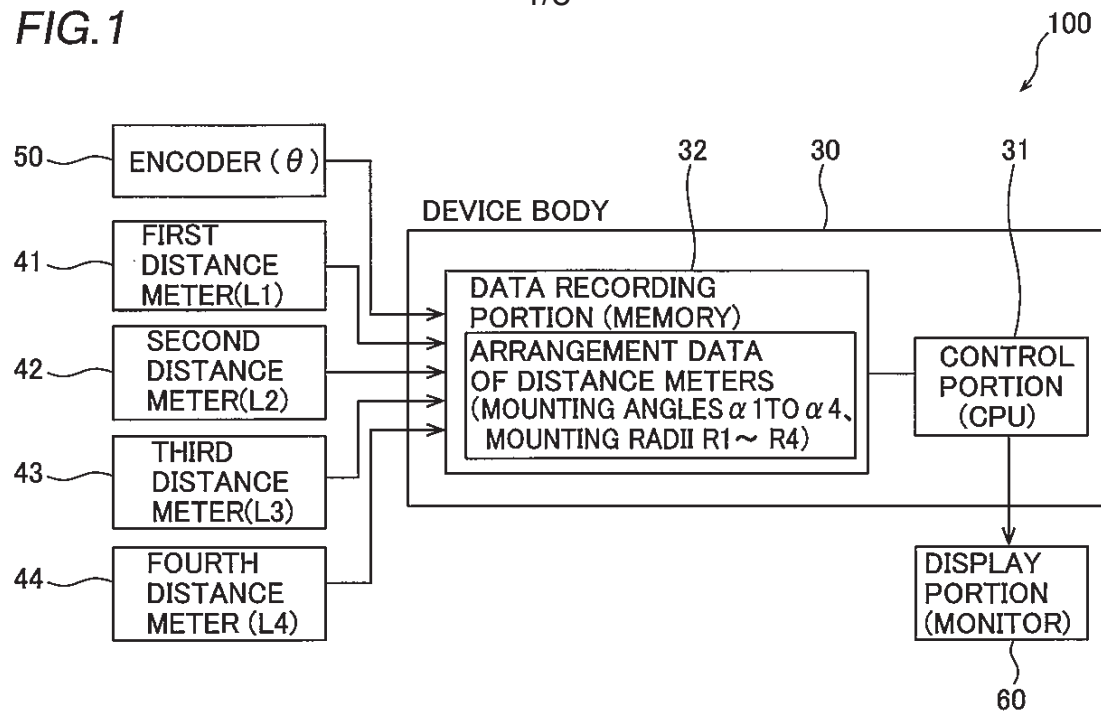


FIG. 2

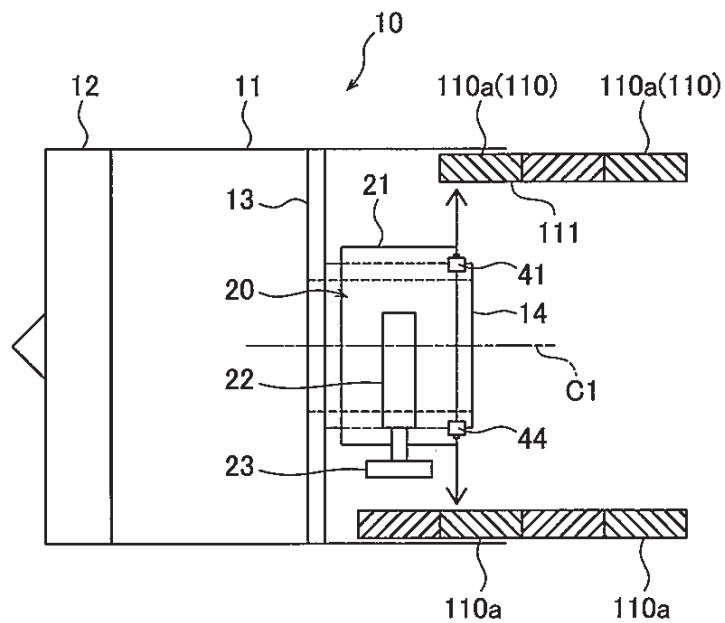


FIG. 3

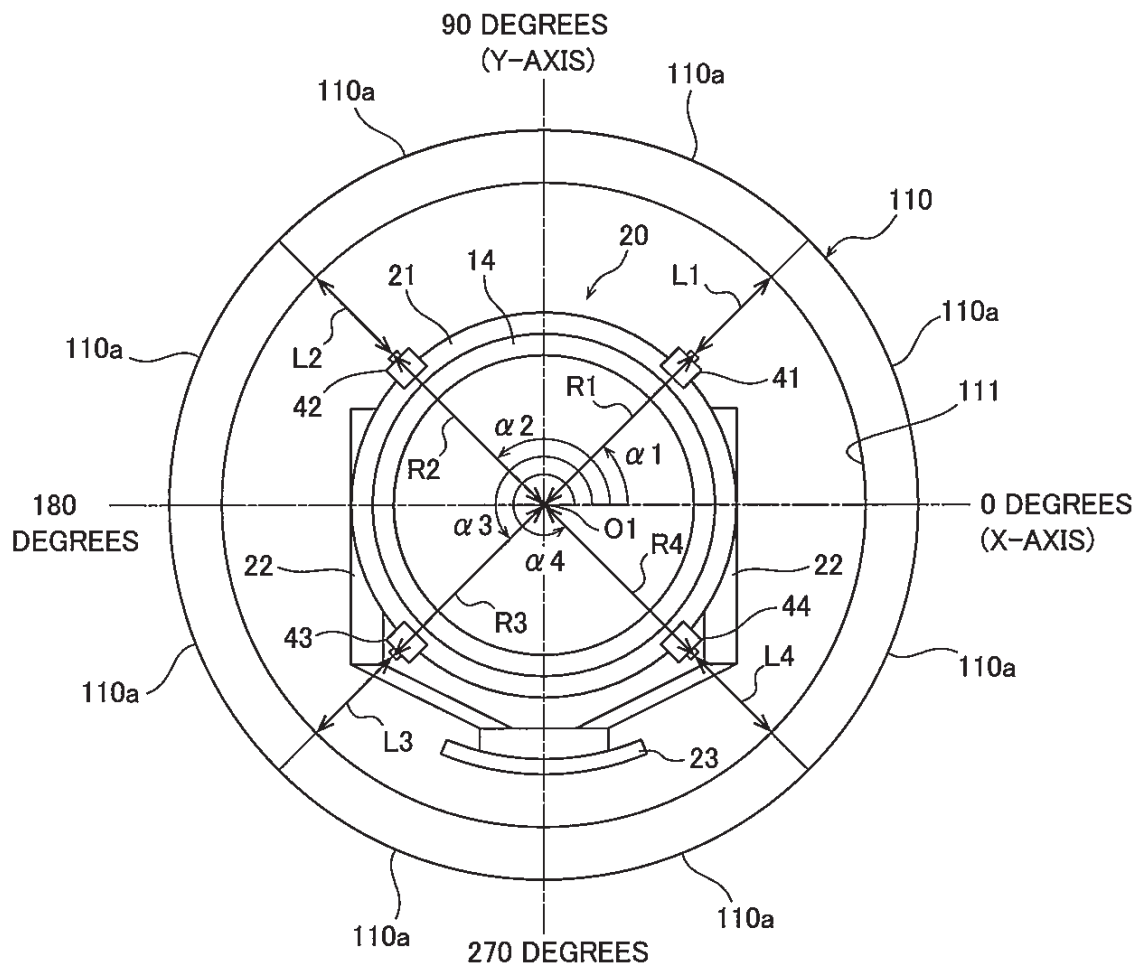


FIG.4

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ROUNDNESS ACQUISITION PROCESSING FLOW

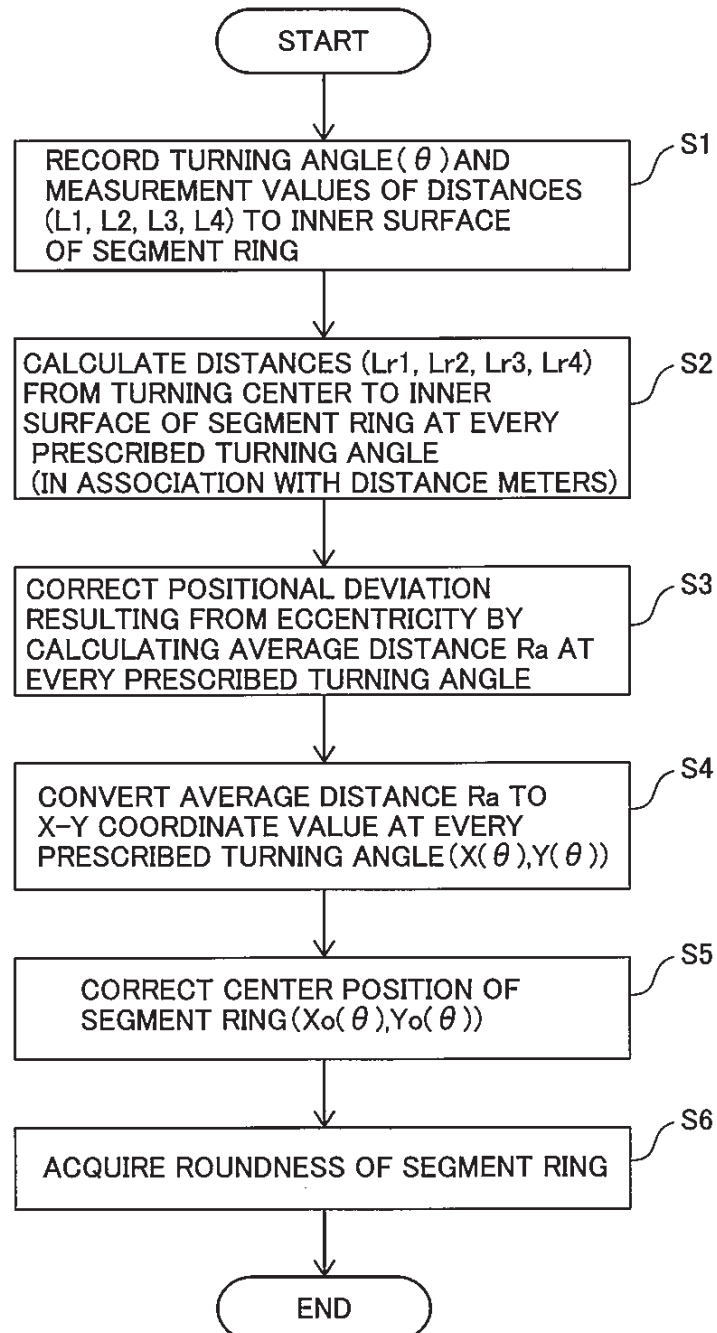


FIG. 5

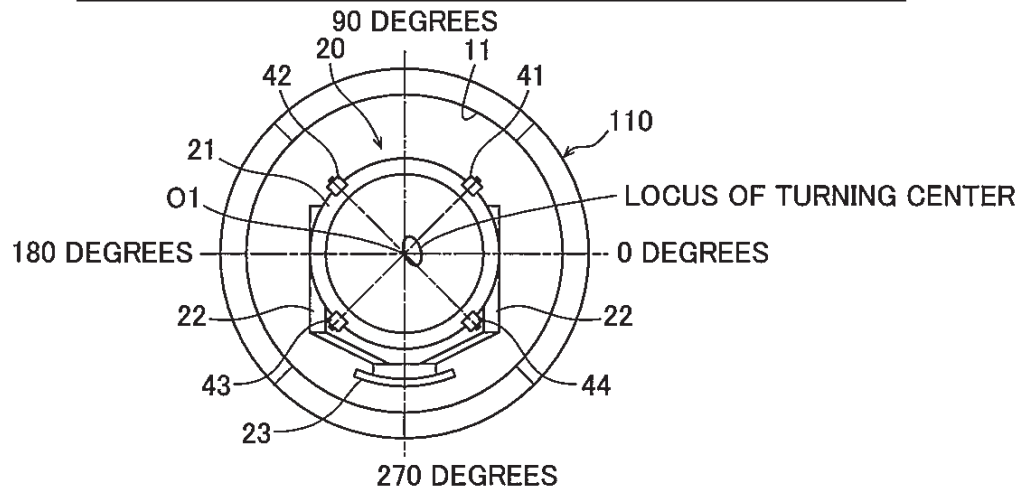
STATE OF BASIC POSITION (TURNING ANGLE OF 0 DEGREES)

FIG. 6

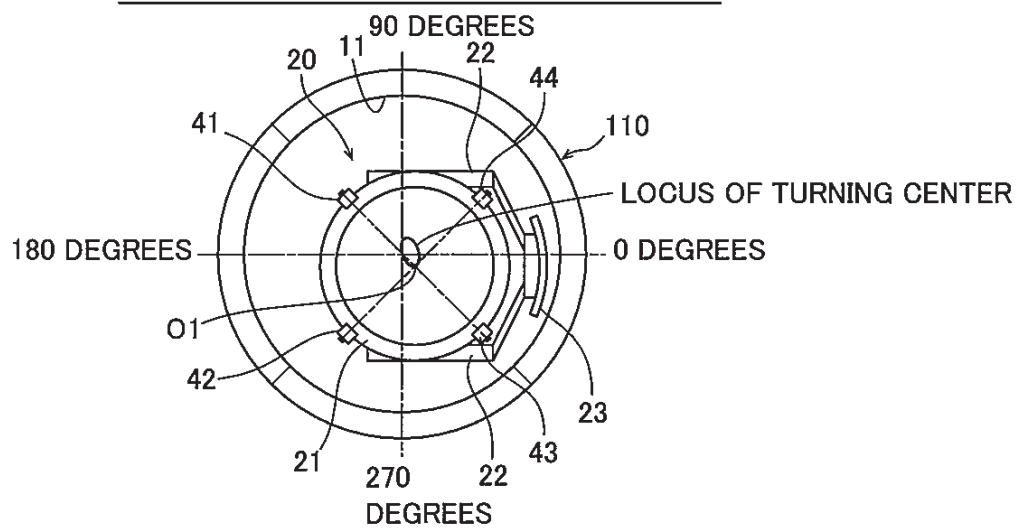
STATE OF TURNING ANGLE OF 90 DEGREES

FIG. 7

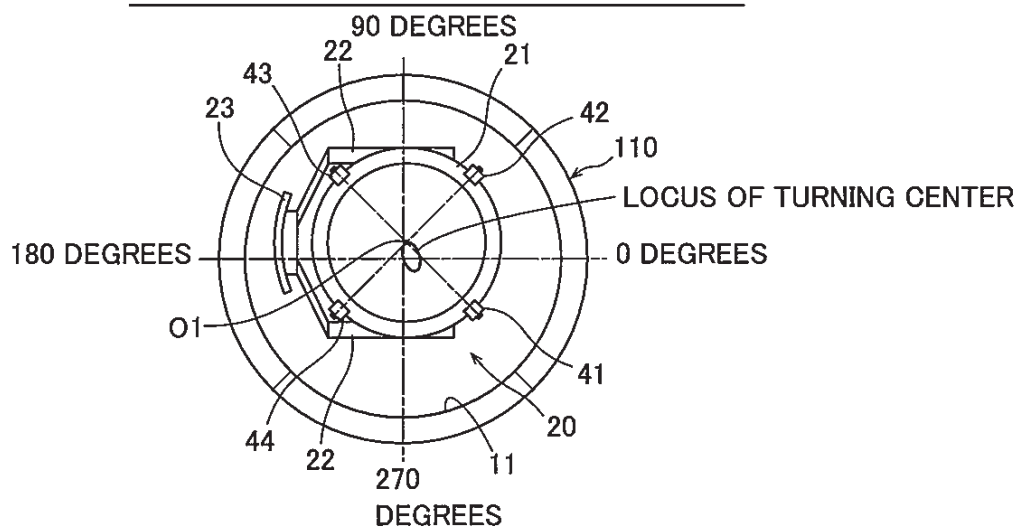
STATE OF TURNING ANGLE OF 270 DEGREES

FIG.8

DISTANCES FROM TURNING CENTER TO INNER SURFACE
OF SEGMENT RING AND AVERAGE DISTANCES

TURNING ANGLE(θ)	FIRST DISTANCE METER	SECOND DISTANCE METER	THIRD DISTANCE METER	FOURTH DISTANCE METER	AVERAGE DISTANCES
0 DEGREES	↓ ↓	↓ ↓	↓ ↓	↓ ↓	Ra(0)
1 DEGREE					Ra(1)
2 DEGREES					Ra(2)
⋮					⋮
45 DEGREES	Lr1(45)	↓ ↓	↓ ↓	↓ ↓	Ra(45)
⋮	↓				⋮
135 DEGREES		Lr2(135)			Ra(135)
⋮		↓			⋮
225 DEGREES			Lr3(225)		Ra(225)
⋮			↓		⋮
315 DEGREES				Lr4(315)	Ra(315)
⋮				↓	⋮
359 DEGREES	↓	↓	↓	↓	Ra(359)

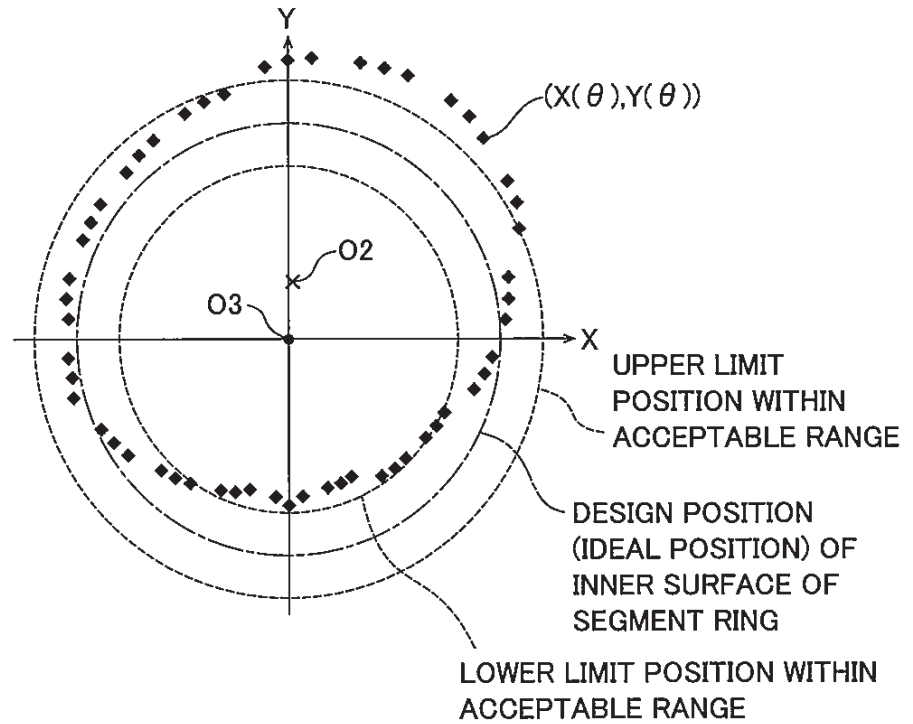
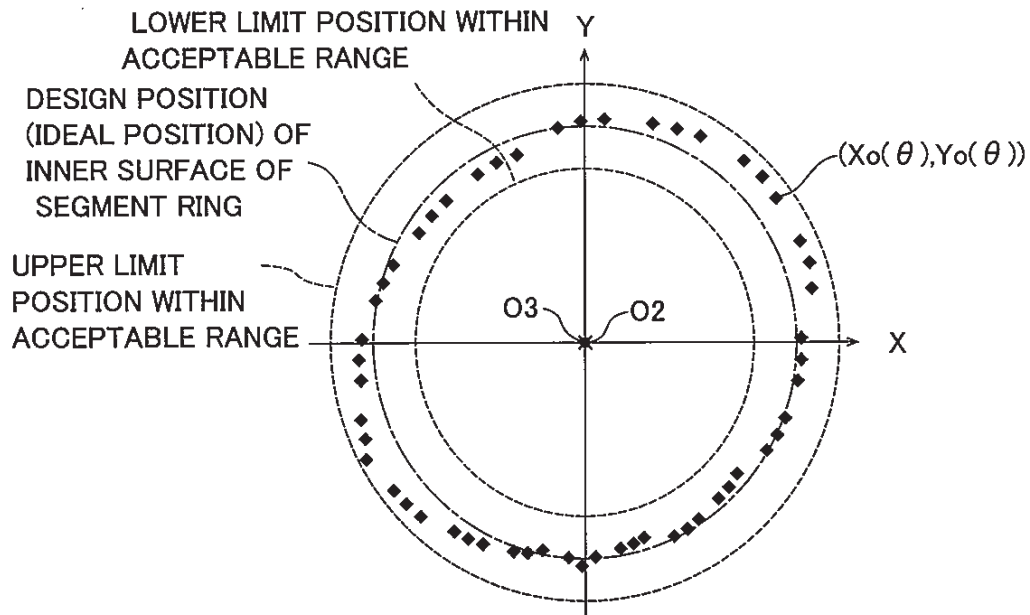
FIG.9STATE BEFORE OFFSET (CORRECTION) OF CENTER POSITION**FIG.10**STATE AFTER OFFSET (CORRECTION) OF CENTER POSITION

FIG. 11

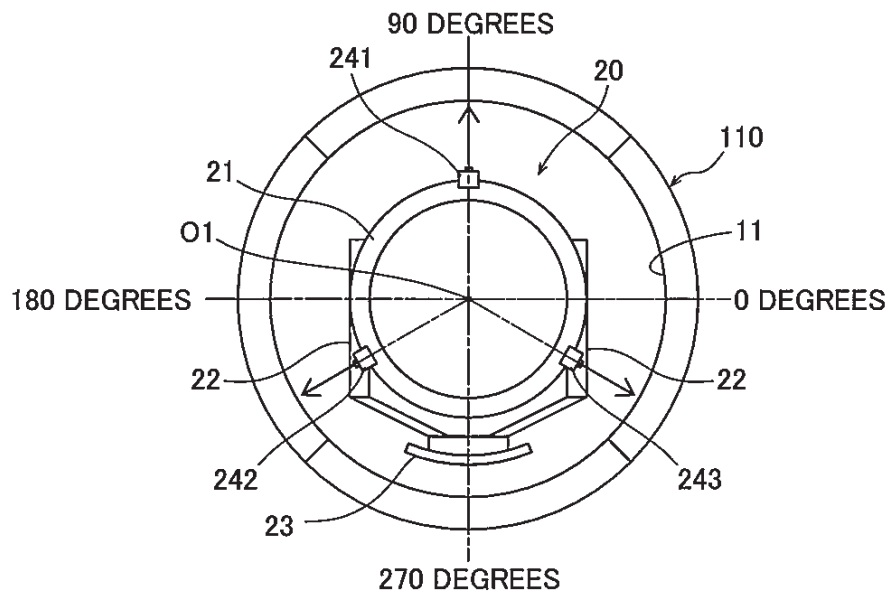
FIRST MODIFICATION (THREE DISTANCE METERS)

FIG. 12

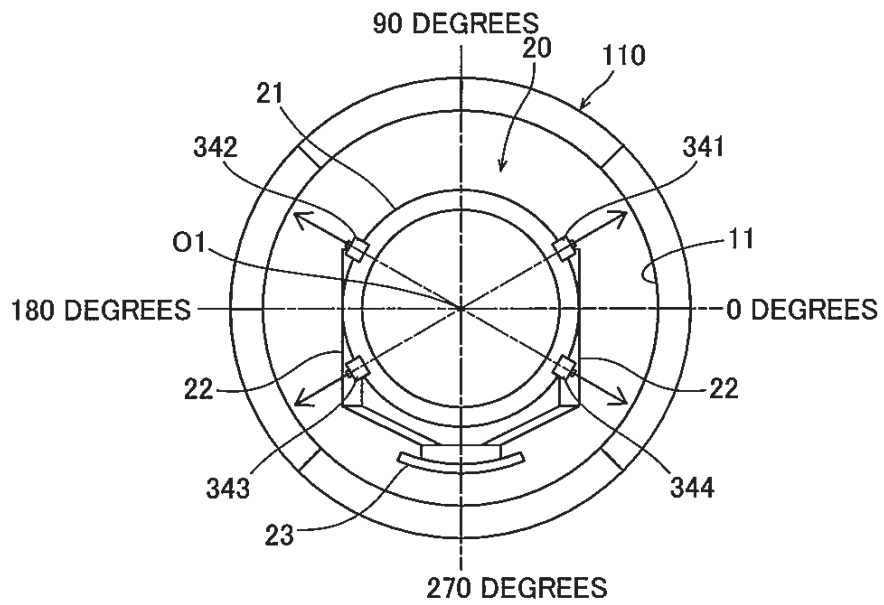
SECOND MODIFICATION (DISTANCE METERS ARE LINE-SYMMETRICALLY ARRANGED)

FIG. 13

THIRD MODIFICATION (BODY PORTION OF
ERECTOR DEVICE IS SUPPORTED FROM OUTSIDE)

