



# SLOVENSKI STANDARD

**SIST EN 15302:2008**

**01-junij-2008**

---

**þYYnb]ý\_YbUdfUj Y!`A YhcXUrnUi [ cHj `UbYi gffYnbY\_cb] bcghj**

Railway applications - Method for determining the equivalent conicity

Bahnanwendungen - Methode zur Bestimmung der äquivalenten Konizität

Applications ferroviaires - Méthode de détermination de la conicité équivalente

**I<sup>TEH</sup>H STANDARD PREVIEW**  
**(standards.iteh.ai)**  
Ta slovenski standard je istoveten z: EN 15302:2008

[SIST EN 15302:2008](#)

---

<https://standards.iteh.ai/catalog/standards/sist/f12e879c-a613-4937-8f15-d5b5c7c8d55c/sist-en-15302-2008>

**ICS:**

45.060.01 Železniška vozila na splošno Railway rolling stock in general

**SIST EN 15302:2008**

**en**

## iTeh STANDARD PREVIEW (standards.iteh.ai)

SIST EN 15302-2008

<https://standards.iteh.ai/catalog/standards/sist/f12e879c-a613-4937-8f15-d5b5c7c8d55c/sist-en-15302-2008>

EUROPEAN STANDARD  
NORME EUROPÉENNE  
EUROPÄISCHE NORM

EN 15302

March 2008

ICS 17.040.20; 45.060.01

English Version

Railway applications - Method for determining the equivalent conicity

Applications ferroviaires - Méthode de détermination de la conicité équivalente

Bahnanwendungen - Verfahren zur Bestimmung der äquivalenten Konizität

This European Standard was approved by CEN on 7 February 2008.

CEN members are bound to comply with the CEN/CENELEC Internal Regulations which stipulate the conditions for giving this European Standard the status of a national standard without any alteration. Up-to-date lists and bibliographical references concerning such national standards may be obtained on application to the CEN Management Centre or to any CEN member.

This European Standard exists in three official versions (English, French, German). A version in any other language made by translation under the responsibility of a CEN member into its own language and notified to the CEN Management Centre has the same status as the official versions.

iTeh STANDARD PREVIEW

CEN members are the national standards bodies of Austria, Belgium, Bulgaria, Cyprus, Czech Republic, Denmark, Estonia, Finland, France, Germany, Greece, Hungary, Iceland, Ireland, Italy, Latvia, Lithuania, Luxembourg, Malta, Netherlands, Norway, Poland, Portugal, Romania, Slovakia, Slovenia, Spain, Sweden, Switzerland and United Kingdom.

SIST EN 15302:2008

<https://standards.iteh.ai/catalog/standards/sist/f12e879c-a613-4937-8f15-d5b5c7c8d55c/sist-en-15302-2008>



EUROPEAN COMMITTEE FOR STANDARDIZATION  
COMITÉ EUROPÉEN DE NORMALISATION  
EUROPÄISCHES KOMITEE FÜR NORMUNG

Management Centre: rue de Stassart, 36 B-1050 Brussels

## Contents

	Page
<b>Foreword.....</b>	<b>9</b>
<b>Introduction .....</b>	<b>10</b>
<b>1 Scope .....</b>	<b>13</b>
<b>2 Normative references .....</b>	<b>13</b>
<b>3 Symbols .....</b>	<b>14</b>
<b>4 Principle of determining the equivalent conicity.....</b>	<b>15</b>
<b>4.1 Integration of the equation of the wheelset movement of a conical profile .....</b>	<b>15</b>
<b>4.2 Determining the wavelength of a conical profile.....</b>	<b>16</b>
<b>4.3 Definition of equivalent conicity for nonlinear profiles .....</b>	<b>17</b>
<b>5 Description of the reference procedure .....</b>	<b>17</b>
<b>5.1 General principles.....</b>	<b>17</b>
<b>5.2 Determining the wheel and rail profiles .....</b>	<b>18</b>
<b>5.2.1 Principles of measurement.....</b>	<b>18</b>
<b>5.2.2 Accuracy of the measuring system .....</b>	<b>18</b>
<b>5.3 Determining the rolling radius difference function <math>\Delta r</math> .....</b>	<b>18</b>
<b>5.4 Determining the equivalent conicity.....</b>	<b>19</b>
<b>6 Benchmark calculation .....</b>	<b>19</b>
<b>6.1 Overview .....</b>	<b>19</b>
<b>6.2 Validation of evaluation method .....</b>	<b>19</b>
<b>Annex A (informative) Example of presentation of <math>\Delta r</math> function and conicity.....</b>	<b>21</b>
<a href="https://standards.itechdata.org/standard/issv/1228994-as-en-15302-2008">https://standards.itechdata.org/standard/issv/1228994-as-en-15302-2008</a>	<b>SIST EN 15302:2008</b>
<b>Annex B (informative) Example of method for determining the equivalent conicity by integration of the nonlinear differential equation .....</b>	<b>22</b>
<b>B.1 Principle.....</b>	<b>22</b>
<b>B.2 Steps of the procedure.....</b>	<b>25</b>
<b>B.3 Special cases .....</b>	<b>26</b>
<b>Annex C (informative) Example of method for determining the equivalent conicity by linear regression of the <math>\Delta r</math> function .....</b>	<b>28</b>
<b>C.1 Principles .....</b>	<b>28</b>
<b>C.2 Steps of the procedure .....</b>	<b>28</b>
<b>C.3 Particularities .....</b>	<b>28</b>
<b>Annex D (normative) Reference profiles.....</b>	<b>29</b>
<b>D.1 Wheel A.....</b>	<b>29</b>
<b>D.1.1 Drawing.....</b>	<b>29</b>
<b>D.1.2 Analytic definition.....</b>	<b>29</b>
<b>D.1.3 Cartesian coordinates .....</b>	<b>30</b>
<b>D.2 Wheel B .....</b>	<b>31</b>
<b>D.2.1 Drawing.....</b>	<b>31</b>
<b>D.2.2 Analytic definition.....</b>	<b>31</b>
<b>D.2.3 Cartesian coordinates .....</b>	<b>32</b>
<b>D.3 Wheel H .....</b>	<b>33</b>
<b>D.3.1 Drawing.....</b>	<b>33</b>
<b>D.3.2 Analytic definition.....</b>	<b>33</b>
<b>D.3.3 Cartesian coordinates .....</b>	<b>34</b>
<b>D.4 Wheel I .....</b>	<b>35</b>
<b>D.4.1 Drawing.....</b>	<b>35</b>
<b>D.4.2 Analytic definition.....</b>	<b>35</b>

D.4.3	Cartesian coordinates .....	36
D.5	Rail A.....	37
D.5.1	Drawing.....	37
D.5.2	Analytic definition .....	37
D.5.3	Cartesian coordinates.....	38
<b>Annex E</b> (normative) Calculation results with reference profiles .....	39	
E.1	Wheel A / Rail A .....	40
E.1.1	Diagram of $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points .....	40
E.1.2	Representation of the curves of kinematic rolling movement of the wheelset on track .....	41
E.1.3	Numerical values for $\Delta r$ function .....	42
E.1.4	Numerical values for $\tan \gamma_e$ function .....	43
E.2	Wheel B / Rail A .....	44
E.2.1	Diagram $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points .....	44
E.2.2	Representation of the curves of kinematic rolling movement of the wheelset on track .....	45
E.2.3	Numerical values for $\Delta r$ function .....	46
E.2.4	Numerical values for $\tan \gamma_e$ function .....	47
E.3	Wheel H / Rail A .....	48
E.3.1	Diagram of $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points .....	48
E.3.2	Representation of the curves of kinematic rolling movement of the wheelset on track .....	49
E.3.3	Numerical values for $\Delta r$ function .....	50
E.3.4	Numerical values for $\tan \gamma_e$ function .....	51
E.4	Wheel I / Rail A.....	52
E.4.1	Diagram of $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points .....	52
E.4.2	Representation of the curves of kinematic rolling movement of the wheelset on track .....	53
E.4.3	Numerical values for $\Delta r$ function .....	54
E.4.4	Numerical values for $\tan \gamma_e$ function .....	55
E.5	Modified Wheel A (-2 mm on left wheel diameter) / Rail A .....	56
E.5.1	Diagram of $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points .....	56
E.5.2	Representation of the curves of kinematic rolling movement of the wheelset on track .....	57
E.5.3	Numerical values for $\Delta r$ function .....	58
E.5.4	Numerical values for $\tan \gamma_e$ function .....	59
E.6	Modified Wheel B (-2 mm on left wheel diameter) / Rail A .....	60
E.6.1	Diagram of $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points .....	60
E.6.2	Representation of the curves of kinematic rolling movement of the wheelset on track .....	61
E.6.3	Numerical values for $\Delta r$ function .....	62
E.6.4	Numerical values for $\tan \gamma_e$ function .....	63
E.7	Modified Wheel H (-2 mm on left wheel diameter) / Rail A .....	64
E.7.1	Diagram of $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points .....	64
E.7.2	Representation of the curves of kinematic rolling movement of the wheelset on track .....	65
E.7.3	Numerical values for $\Delta r$ function .....	66
E.7.4	Numerical values for $\tan \gamma_e$ function .....	67
E.8	Modified Wheel I (-2 mm on left wheel diameter) / Rail A.....	67
E.8.1	Diagram of $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points .....	67
E.8.2	Representation of the curves of kinematic rolling movement of the wheelset on track .....	69
E.8.3	Numerical values for $\Delta r$ function .....	70
E.8.4	Numerical values for $\tan \gamma_e$ function .....	71
E.9	(Right Wheel A – Left Wheel B) / Rail A.....	72
E.9.1	Diagram of $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points .....	72
E.9.2	Representation of the curves of kinematic rolling movement of the wheelset on track .....	73
E.9.3	Numerical values for $\Delta r$ function .....	74
E.9.4	Numerical values for $\tan \gamma_e$ function .....	75
<b>Annex F</b> (normative) Tolerances on equivalent conicity .....	76	
F.1	Wheel A / Rail A .....	77

F.1.1	Diagram.....	77
F.1.2	Numerical values .....	78
F.2	Wheel B / Rail A.....	80
F.2.1	Diagram.....	80
F.2.2	Numerical values .....	81
F.3	Wheel H / Rail A.....	83
F.3.1	Diagram.....	83
F.3.2	Numerical values .....	84
F.4	Wheel I / Rail A .....	86
F.4.1	Diagram.....	86
F.4.2	Numerical values .....	87
F.5	Modified Wheel A (-2 mm on left wheel diameter) / Rail A .....	89
F.5.1	Diagram.....	89
F.5.2	Numerical values .....	90
F.6	Modified Wheel B (-2 mm on left wheel diameter) / Rail A .....	92
F.6.1	Diagram.....	92
F.6.2	Numerical values .....	93
F.7	Modified Wheel H (-2 mm on left wheel diameter) / Rail A .....	95
F.7.1	Diagram.....	95
F.7.2	Numerical values .....	96
F.8	Modified Wheel I (-2 mm on left wheel diameter) / Rail A .....	98
F.8.1	Diagram.....	98
F.8.2	Numerical values .....	99
F.9	(Right Wheel A – Left Wheel B) / Rail A .....	101
F.9.1	Diagram.....	101
F.9.2	Numerical values .....	102

**iTeH STANDARD PREVIEW**  
**(standards.iteh.ai)**

Annex G (informative) Examples of calculation results with introduced errors.....	104
G.1 Wheel A / Rail A – Random error in mm .....	104
G.2 Wheel A / Rail A — Random error in mm .....	105
G.3 Wheel A / Rail A — Random error in mm .....	106
G.4 Wheel A / Rail A — Grid error in mm .....	107
G.5 Wheel A / Rail A — Grid error in mm .....	108
G.6 Wheel A / Rail A — Grid error in mm .....	109
G.7 Wheel H / Rail A — Random error in mm .....	110
Annex H (informative) Guideline for application of errors .....	111
H.1 Grid error .....	111
H.2 Random error .....	113
Annex I (informative) Guidelines for application .....	115
Annex ZA (informative) Relationship between this European Standard and the Essential Requirements of EU Directive Council Directive 96/48/EC as amended by 2004/50/EC .....	117
Bibliography .....	119

## Figures

Figure 1 — Benchmark process, Step 1 .....	11
Figure 2 — Benchmark process, Step 2 .....	11
Figure 3 — Benchmark process, Step 3 .....	12
Figure 4 — Dimensions on the wheelset.....	15
Figure 5 — $y = f(x)$ function .....	16
Figure A.1 — $\Delta r = f(y)$ function and $\tan \gamma_e = f(y)$ .....	21
Figure B.1 — Representation of $dx, dy$ .....	22

<b>Figure B.2 — Representation of <math>ds</math>, <math>d\Psi</math>.....</b>	<b>22</b>
<b>Figure B.3 — Representation of <math>r_1</math>, <math>r_2</math>, <math>e</math>.....</b>	<b>23</b>
<b>Figure B.4 — <math>\Delta r = f(y)</math> characteristic with negative slope .....</b>	<b>26</b>
<b>Figure B.5 — Calculation of <math>\int \Delta r dy</math> integral .....</b>	<b>26</b>
<b>Figure B.6 — Determination of <math>y_{em}</math>, calculation of <math>\int \Delta r dy</math> and determination of <math>\hat{y}</math> .....</b>	<b>27</b>
<b>Figure B.7 — Determination of <math>y_{emin} = f(\hat{y})</math> and <math>y_{emax} = f(\hat{y})</math> functions .....</b>	<b>27</b>
<b>Figure B.8 — Determination of C constant .....</b>	<b>27</b>
<b>Figure D.1 — Wheel A .....</b>	<b>29</b>
<b>Figure D.2 —Wheel B .....</b>	<b>31</b>
<b>Figure D.3 — Wheel H .....</b>	<b>33</b>
<b>Figure D.4 — Wheel I .....</b>	<b>35</b>
<b>Figure D.5 — Rail A .....</b>	<b>37</b>
<b>Figure E.1a — Diagram of <math>\Delta r</math>, <math>\tan\gamma_a</math>, <math>\tan\gamma_e</math> functions and representation of contact points — Wheel A / Rail A .....</b>	<b>40</b>
<b>Figure E.1b — Representation of the curves of kinematic rolling movement of the wheelset on track — Wheel A / Rail A .....</b>	<b>41</b>
<b>Figure E.2a — Diagram <math>\Delta r</math>, <math>\tan\gamma_a</math>, <math>\tan\gamma_e</math> functions and representation of contact points — Wheel B / Rail A .....</b>	<b>44</b>
<b>Figure E.2b — Representation of the curves of kinematic rolling movement of the wheelset on track — Wheel B / Rail A .....</b>	<b>45</b>
<b>Figure E.3a — Diagram of <math>\Delta r</math>, <math>\tan\gamma_a</math>, <math>\tan\gamma_e</math> functions and representation of contact points — <a href="https://standards.itech.ai/catalog/standards/sist/f12e879c-a613-4937-8d5c/88d55c/sist-en-15302-2008">SIST EN 15302:2008</a>— Wheel H / Rail A .....</b>	<b>48</b>
<b>Figure E.3b — Representation of the curves of kinematic rolling movement of the wheelset on track — Wheel H / Rail A .....</b>	<b>49</b>
<b>Figure E.4a — Diagram of <math>\Delta r</math>, <math>\tan\gamma_a</math>, <math>\tan\gamma_e</math> functions and representation of contact points — Wheel I / Rail A .....</b>	<b>52</b>
<b>Figure E.4b — Representation of the curves of kinematic rolling movement of the wheelset on track — Wheel I / Rail A .....</b>	<b>53</b>
<b>Figure E.5a — Diagram of <math>\Delta r</math>, <math>\tan\gamma_a</math>, <math>\tan\gamma_e</math> functions and representation of contact points — Modified Wheel A / Rail A .....</b>	<b>56</b>
<b>Figure E.5b — Representation of the curves of kinematic rolling movement of the wheelset on track — Modified Wheel A / Rail A .....</b>	<b>57</b>
<b>Figure E.6a — Diagram of <math>\Delta r</math>, <math>\tan\gamma_a</math>, <math>\tan\gamma_e</math> functions and representation of contact points — Modified Wheel B / Rail A .....</b>	<b>60</b>
<b>Figure E.6b — Representation of the curves of kinematic rolling movement of the wheelset on track — Modified Wheel B / Rail A .....</b>	<b>61</b>
<b>Figure E.7a — Diagram of <math>\Delta r</math>, <math>\tan\gamma_a</math>, <math>\tan\gamma_e</math> functions and representation of contact points — Modified Wheel H / Rail A .....</b>	<b>64</b>
<b>Figure E.7b — Representation of the curves of kinematic rolling movement of the wheelset on track — Modified Wheel H / Rail A .....</b>	<b>65</b>

Figure E.8a — Diagram of $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points — Modified Wheel I / Rail A .....	68
Figure E.8b — Representation of the curves of kinematic rolling movement of the wheelset on track — Modified Wheel I / Rail A .....	69
Figure E.9a — Diagram of $\Delta r$ , $\tan \gamma_a$ , $\tan \gamma_e$ functions and representation of contact points — (Right Wheel A – Left Wheel B) / Rail A .....	72
Figure E.9b — Representation of the curves of kinematic rolling movement of the wheelset on track — (Right Wheel A – Left Wheel B) / Rail A .....	73
Figure F.1 — Diagram Wheel A / Rail A .....	77
Figure F.2 — Diagram Wheel B / Rail A .....	80
Figure F.3 — Diagram Wheel H / Rail A .....	83
Figure F.4 — Diagram Wheel I / Rail A .....	86
Figure F.5 — Diagram modified Wheel A / Rail A .....	89
Figure F.6 — Diagram modified Wheel B / Rail A .....	92
Figure F.7 — Diagram modified Wheel H / Rail A .....	95
Figure F.8 — Diagram modified Wheel I / Rail A .....	98
Figure F.9 — Diagram (Right Wheel A — Left Wheel B) / Rail A .....	101
Figure G.1 — Wheel A / Rail A — Random error in mm .....	104
Figure G.2 — Wheel A / Rail A — Random error in mm .....	105
Figure G.3 — Wheel A / Rail A — Random error in mm .....	106
Figure G.4 — Wheel A / Rail A — Grid error in mm .....	107
Figure G.5 — Wheel A / Rail A — Grid error in mm .....	108
Figure G.6 — Wheel A / Rail A — Grid error in mm .....	109
Figure G.7 — Wheel H / Rail A — Random error in mm .....	110
Figure H.1 — Transformation of the point $P(x, y)$ to grid with grid widths $\Delta y, \Delta z$ .....	111
Figure H.2 — Grid transformation with grid widths of 0,5 mm .....	112
Figure H.3 — Variation of the grid origin .....	112
Figure H.4 — 50 variants of grid origins .....	113
Figure H.5 — Random error of measuring points .....	114

## Tables

Table D.1 — Wheel profile: R-UIC 519-A — Right wheel .....	30
Table D.2 — Wheel profile: R-UIC 519-B — Right wheel .....	32
Table D.3 — Wheel profile: R-UIC 519-H — Right wheel .....	34
Table D.4 — Wheel profile: R-UIC 519-I — Right wheel .....	36
Table D.5 — Rail profile: S-UIC 519-A — Right rail .....	38
Table E.1a — Contact geometry wheel / rail: $\Delta r = f(y)$ — Wheel profile: R-UIC 519-A — Rail Profile: S-UIC 519-A .....	42
Table E.1b — Contact geometry wheel / rail: Conicity — Wheel profile: R-UIC 519-A — Rail profile: S-UIC 519-A .....	43

Table E.2a — Contact geometry wheel / rail: $\Delta r = f(y)$ — Wheel profile: R-UIC 519-B — Rail profile: S-UIC 519-A .....	46
Table E.2b — Contact geometry wheel / rail: Conicity — Wheel profile: R-UIC 519-B — Rail profile: S-UIC 519-A.....	47
Table E.3a — Contact geometry wheel / rail: $\Delta r = f(y)$ — Wheel profile: R-UIC 519-H — Rail profile: S-UIC 519-A .....	50
Table E.3b — Contact geometry wheel / rail: Conicity — Wheel profile: R-UIC 519-H — Rail profile: S-UIC 519-A.....	51
Table E.4a — Contact geometry wheel / rail: $\Delta r = f(y)$ — Wheel profile: R-UIC 519-I — Rail profile: S-UIC 519-A .....	54
Table E.4b — Contact geometry wheel / rail: Conicity — Wheel profile: R-UIC 519-I — Rail profile: S-UIC 519-A.....	55
Table E.5a — Contact geometry wheel / rail: $\Delta r = f(y)$ — Diameter difference of 2 mm — Wheel profile: R-UIC 519-A — Rail profile: S-UIC 519-A .....	58
Table E.5b — Contact geometry wheel / rail: Conicity — Diameter difference of 2 mm — Wheel profile: R-UIC 519-A — Rail profile: S-UIC 519-A .....	59
Table E.6a — Contact geometry wheel / rail: $\Delta r = f(y)$ — Diameter difference of 2 mm — Wheel profile: R-UIC 519-B — Rail profile: S-UIC 519-A .....	62
Table E.6b — Contact geometry wheel / rail: Conicity — Diameter difference of 2 mm — Wheel profile: R-UIC 519-B — Rail profile: S-UIC 519-A .....	63
Table E.7a — Contact geometry wheel / rail: $\Delta r = f(y)$ — Diameter difference of 2 mm — Wheel profile: R-UIC 519-H — Rail profile: S-UIC 519-A .....	66
Table E.7b — Contact geometry wheel / rail: Conicity — Diameter difference of 2 mm — Wheel profile: R-UIC 519-H — Rail profile: S-UIC 519-A .....	67
Table E.8a — Contact geometry wheel / rail: $\Delta r = f(y)$ — Diameter difference of 2 mm — Wheel profile: R-UIC 519-I — Rail profile: S-UIC 519-A .....	70
Table E.8b — Contact geometry wheel / rail: Conicity — Diameter difference of 2 mm — Wheel profile: R-UIC 519-I — Rail profile: S-UIC 519-A.....	71
Table E.9a — Contact geometry wheel / rail: $\Delta r = f(y)$ — Wheel profile: right wheel R-UIC519-A / left wheel R-UIC 519-B — Rail profile: S-UIC 519-A .....	74
Table E.9b — Contact geometry wheel / rail: Conicity — Wheel profile: right wheel R-UIC 519-A / left wheel R-UIC 519-B — Rail profile: S-UIC 519-A .....	75
Table F.1 — Benchmark calculations: Tolerances — Wheel profile: R-UIC 519-A — Rail profile: S-UIC 519-A.....	78
Table F.2 — Benchmark calculations: Tolerances — Wheel profile: R-UIC 519-B — Rail profile: S-UIC 519-A.....	81
Table F.3 — Benchmark calculations: Tolerances — Wheel profile: R-UIC 519-H — Rail profile: S-UIC 519-A.....	84
Table F.4 — Benchmark calculations: Tolerances — Wheel profile: R-UIC 519-I — Wheel profile: S-UIC 519-A .....	87
Table F.5 — Benchmark calculations: Tolerances — Wheel profile: R-UIC 519-A — Diameter difference of 2 mm — Rail profile: S-UIC 519-A .....	90
Table F.6 — Benchmark calculations: Tolerances — Wheel profile: R-UIC 519-B — Diameter difference of 2 mm — Rail profile: S-UIC 519-A .....	93
Table F.7 — Benchmark calculations: Tolerances — Wheel profile: R-UIC 519-H — Diameter difference of 2 mm — Rail profile: S-UIC 519-A .....	96

Table F.8 — Benchmark calculations: Tolerances — Wheel profile: R-UIC 519-I — Diameter difference of 2 mm — Rail profile: S-UIC 519-A.....	99
Table F.9 — Benchmark calculations: Tolerances — Wheel profile: right wheel R-UIC 519-A / left wheel R-UIC 519-B — Rail profile: S-UIC 519-A.....	102
Table I.1 — Combinations of profiles and their applications .....	116
Table ZA.1 — Correspondence between this European Standard and Directives: Council Directive 96/48/EC of 23 July 1996 on the interoperability of the trans-European high-speed rail system Directive 2004/50/EC of the European parliament and of the Council of 29 April 2004 amending Council Directive 96/48/EC .....	118

## iTeh STANDARD PREVIEW (standards.iteh.ai)

SIST EN 15302:2008  
<https://standards.iteh.ai/catalog/standards/sist/f12e879c-a613-4937-8f15-d5b5c7c8d55c/sist-en-15302-2008>

## Foreword

This document (EN 15302:2008) has been prepared by Technical Committee CEN/TC 256 "Railway applications", the secretariat of which is held by DIN.

This European Standard shall be given the status of a national standard, either by publication of an identical text or by endorsement, at the latest by September 2008, and conflicting national standards shall be withdrawn at the latest by September 2008.

This document has been prepared under a mandate given to CEN by the European Commission and the European Free Trade Association, and supports essential requirements of EU Directive 96/48 of 23 July 1996 as amended by 2004/50/EC.

For relationship with EU Directive, see informative Annex ZA, which is an integral part of this document.

Attention is drawn to the possibility that some of the elements of this document may be the subject of patent rights. CEN [and/or CENELEC] shall not be held responsible for identifying any or all such patent rights.

According to the CEN/CENELEC Internal Regulations, the national standards organizations of the following countries are bound to implement this European Standard: Austria, Belgium, Bulgaria, Cyprus, Czech Republic, Denmark, Estonia, Finland, France, Germany, Greece, Hungary, Iceland, Ireland, Italy, Latvia, Lithuania, Luxembourg, Malta, Netherlands, Norway, Poland, Portugal, Romania, Slovakia, Slovenia, Spain, Sweden, Switzerland and United Kingdom.

THE STANDARD PREVIEW  
(standards.iteh.ai)

[SIST EN 15302:2008](#)

<https://standards.iteh.ai/catalog/standards/sist/f12e879c-a613-4937-8f15-d5b5c7c8d55c/sist-en-15302-2008>

## Introduction

This European Standard is based on the UIC Code 519 OR submitted to CEN by the International Union of Railways (UIC) and which has been revised by CEN/TC 256/WG 10 "Vehicle/Track Interaction".

The contact geometry is fundamental to explain the dynamic running behaviour of a railway vehicle. Among the parameters by which the dynamic behaviour of a rail vehicle is characterised, the conicity plays an essential role since it allows the satisfactory appreciation of the wheel-rail contact on tangent track and on very large-radius curves (when operated with low cant deficiencies). A wheelset with conical profiles describes a waveform while running on a track. Klingel's theory states that the wavelength depends on the cone angle of the wheel profile and the distance between contact patches.

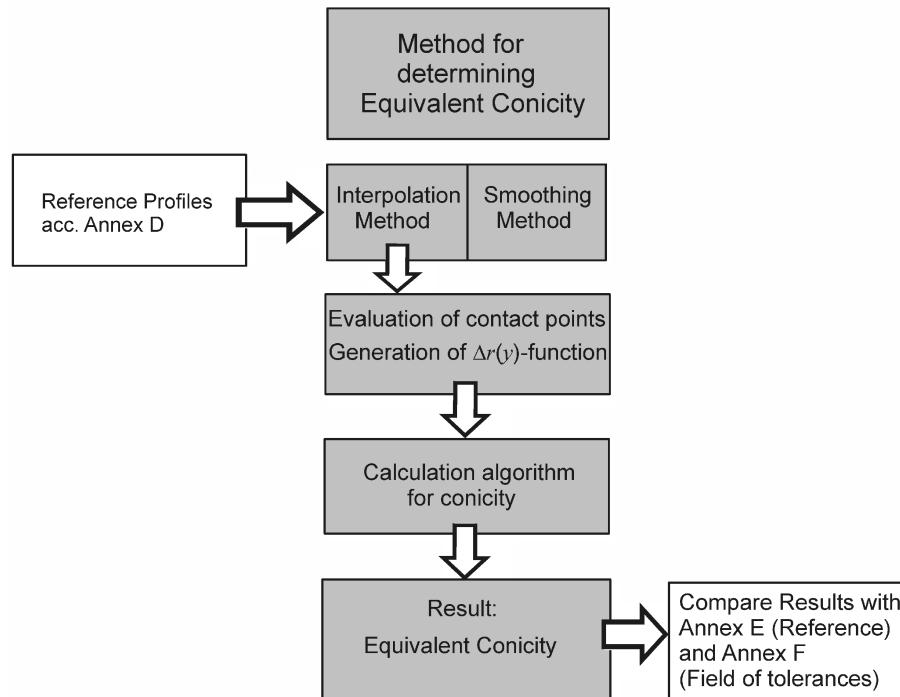
For practical wheel profiles with changing cone angles along the profile it is possible to evaluate the wavelength of the wheelsets movement by integration of the function of rolling radius difference depending on the lateral movement of the wheelset on the track. Equivalent conicity is evaluated by comparison of this wavelength with the one evaluated according to Klingel's theory.

It is necessary to have a clear procedure for the evaluation of equivalent conicity, which is used in European and national standards and documents (legal and technical).

The results need to be consistent. However it is possible to use different evaluation procedures to those given in this European Standard, provided that the procedure used leads to the determination of an equivalent conicity in accordance with the calculation results using reference profiles specified in Annex E.

To confirm whether an alternative evaluation procedure can achieve the results specified in this European Standard, three aspects of the process need to be evaluated in a benchmark process given in this European Standard and outlined below in Steps 1, 2 and 3:  
<http://www.kraibach.de/catalog/standards/sist/f12e879c-a613-4937-8f15-d5b5c7c8d55c/sist-en-15302-2008>

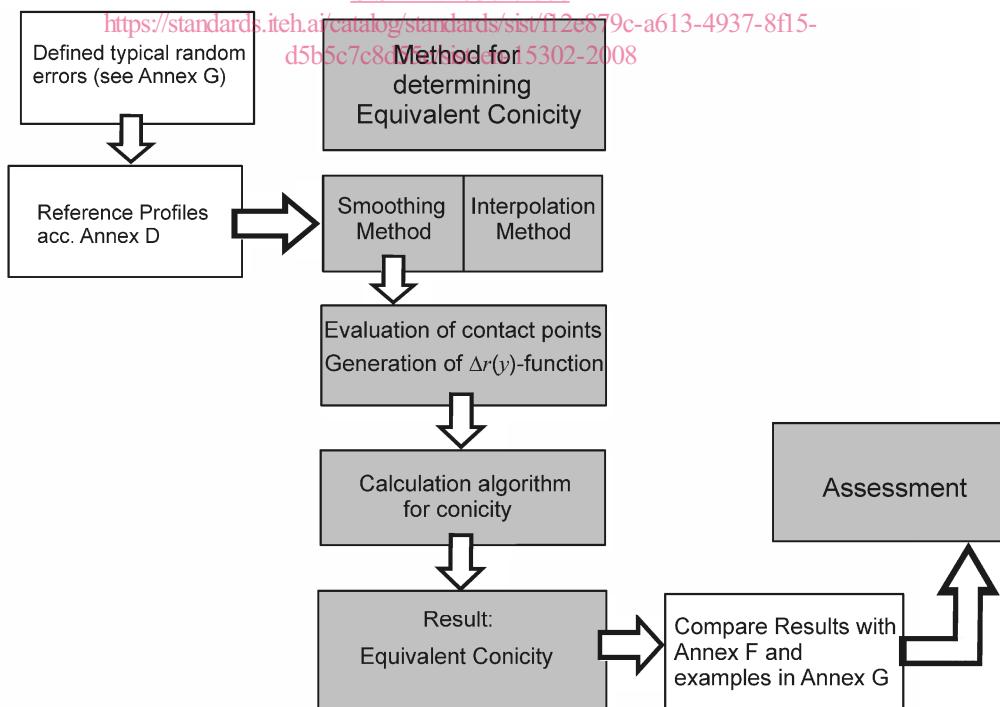
In Step 1, tables of reference profiles in Annex D are applied to the interpolation and calculation algorithm which allows the location of the contact points in order to calculate the rolling radius difference as a function of the lateral position of the wheelset. Starting from this function the equivalent conicity is calculated as a function of the amplitude of the oscillation. A comparison of the achieved results with the reference results in Annex E and a defined field of allowed tolerances in Annex F determine the acceptance or rejection of the assessed evaluation procedure (see Figure 1).



**iTeh STANDARD PREVIEW**

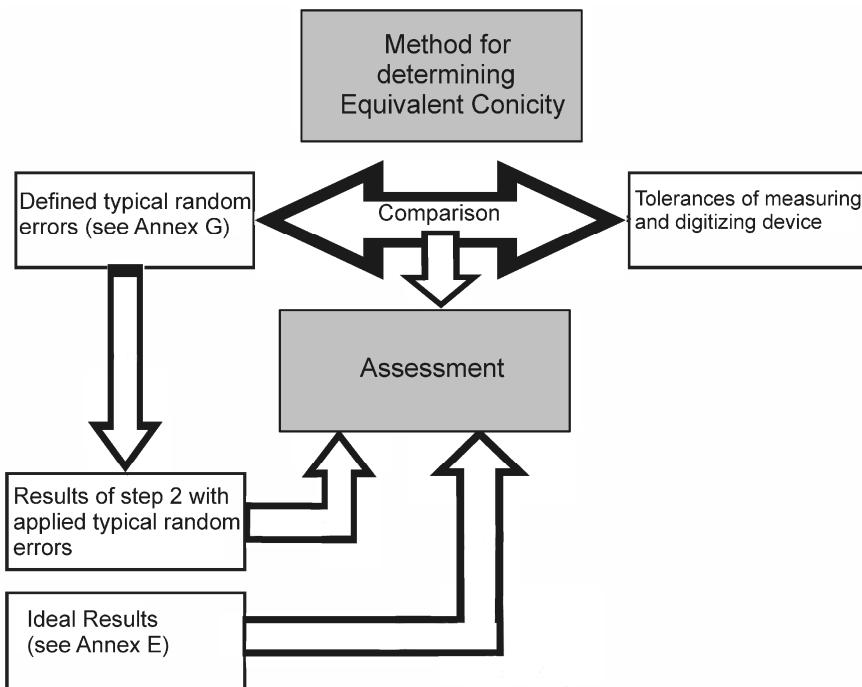
In Step 2, random errors given in Annex G are added to the reference profiles in Annex D and are applied to the smoothing and interpolation algorithm. A comparison of the achieved results with the reference results including the field of tolerances in Annex F allows the assessment of the evaluation procedure (see Figure 2).

SIST EN 15302:2008



**Figure 2 — Benchmark process, Step 2**

In Step 3, the tolerances of the measuring system used are compared with the random errors applied in Step 2 in order to assess their influence on the results.



## iTeh STANDARD PREVIEW

**Figure 3 – Benchmark process, Step 3**

SIST EN 15302:2008

<https://standards.iteh.ai/catalog/standards/sist/f12e879c-a613-4937-8f15-d5b5c7c8d55c/sist-en-15302-2008>

## 1 Scope

This European Standard establishes an evaluation procedure for determining equivalent conicity. A benchmark calculation is specified to achieve comparable results on a consistent basis for the equivalent conicity, which may be calculated by different methods not given in this European Standard. This European Standard also proposes possible calculation methods. Informative examples of the use of the Klingel formula (see Annex B) and linear regression of the  $\Delta r$ -function (see Annex C) are included in this European Standard.

This European Standard includes reference profiles, profile combinations, tolerances and reference results with tolerance limits, which allow the user to assess the acceptability of a measuring and calculation system including random- and grid- errors of the measuring system. It sets down the principles of calculation that need to be followed but does not impose any particular numerical calculation method.

This European Standard does not define limits for the equivalent conicity and gives no tolerances for the rail profile and the wheel profile to achieve acceptable results for the conicity.

For purposes outside the scope of this European Standard (e.g. simulation of vehicle behaviour) it can be useful or necessary to use more sophisticated theories. These methods are not within the scope of this European Standard.

For the application of this European Standard some general recommendations are given in Annex I.

## 2 Normative references

### IEH STANDARD PREVIEW (standards.iteh.ai)

The following referenced document is indispensable for the application of this document. For dated references, only the edition cited applies. For undated references, the latest edition of the referenced document (including any amendments) applies.

[SIST EN 15302:2008](#)

N/A

<https://standards.iteh.ai/catalog/standards/sist/f12e879c-a613-4937-8f15-d5b5c7c8d55c/sist-en-15302-2008>