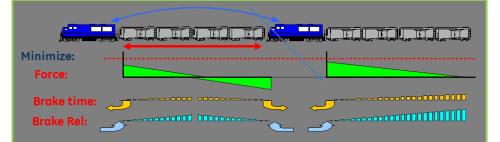
# Running Longer Trains more Productively and Less Destructively



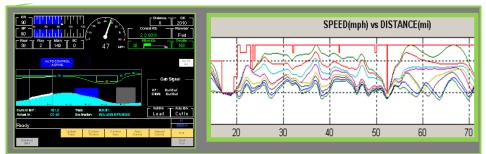




# **The Braun and the Brains...** Two Complimentary Technologies for Long Trains:



### **LOCOTROL Distributed Power (DP) 1985**



### Trip Optimizer (TO) Train Control System 2005







# **More Productively: Distributed Power Capacity**



99,732 tons, 682 ore cars 2x168x2x168x2x168x1x178x1 BP segments: 5,800'



~10,000 tons, 179 wells 5x170x1 typ. BP segment 10,000'



~42,000 tons, 342 ore cars EDDx114XDDEx114xDDDDx114xDD BP segments 3,740'



~16,000 tons, 306 wells 3x102x2x102x2x102x2 BP segment 6,000'



~45,000 tons, 336 ore cars 2x112x2x112x2x112 BP segments 3,608'



15,000 tons, 130 cars 1x74x1x74x1BP segments 6000'

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### **More Productively: Distributed Power Throughput**<sup>4</sup>



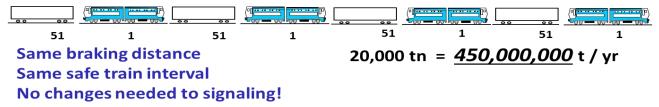


### More Productively: Distributed Power Throughputs

#### **Original Operation:**



#### Current with DP: 4x Capacity, 90 trains daily





Total Program ROI: just over 2 years <u>LOCOTROL ROI</u>: ~ 3-4 months







# More Productively: Distributed Power Stopping Dist.



Principal Engineer (Train Design





Wabtec

# More Productively: Distributed Power Fuel Savings

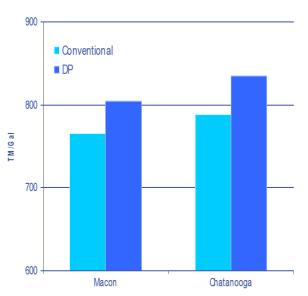
### 322 Out of Macon:

- DP Avg: 342 GTK/Litre (805 GTM/Gal)
- Conventional Avg: 326 GTK/Litre (766 GTM/Gal)
- **5.2% Difference**

### **361 Out of Chattanooga:**

 DP Avg: 355 GTK/Litre (835 GTM/Gal)
 Conventional Avg: 335 GTK/Litre (788 GTM/Gal)

### 6.0% Difference



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#### Fuel Efficiency



### **More Productively:**

# **Distributed Power Fuel Savings**

### • 6% Fuel Savings

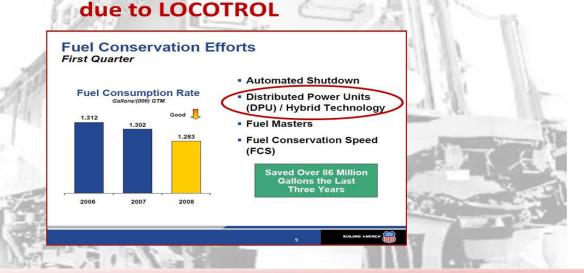
• 10% Improvement in overall tonnage

5% Fuel Savings across the fleet

• 11% Improvement in fewer train starts

### **Union Pacific:**

**CPRR**:

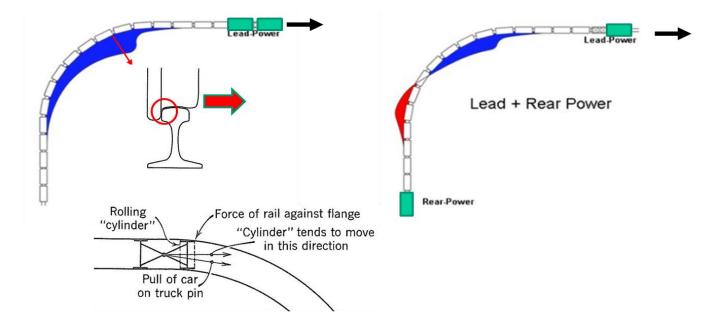








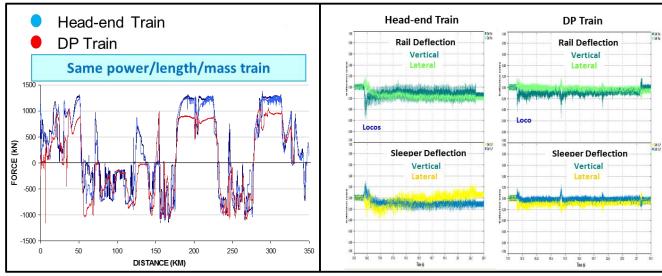
#### **Distributed Power Fuel Savings More Productively:**



5% fuel savings over 5 years **Union Pacific RR:** 6% fuel savings over 4 years **Canadian Pacific RR: WRI** 20019 Wabtec

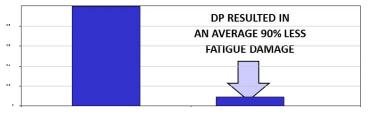
### **Less Destructively:**

# **Distributed Power**





#### 5 Year Revenue Service Data



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# Less Destructively: Distributed Power Control of Lateral Force



Before

The rail installed in Oct. 2004 and replaced in May 2005.

• The extreme rail wear was seen after only 7 months.



After

After installation in May of 2005, which is 7 months, the curve rail wear was between 1/32 to 2/32.

- This is a major improvement.
- Rail Life extended from one year to five years.

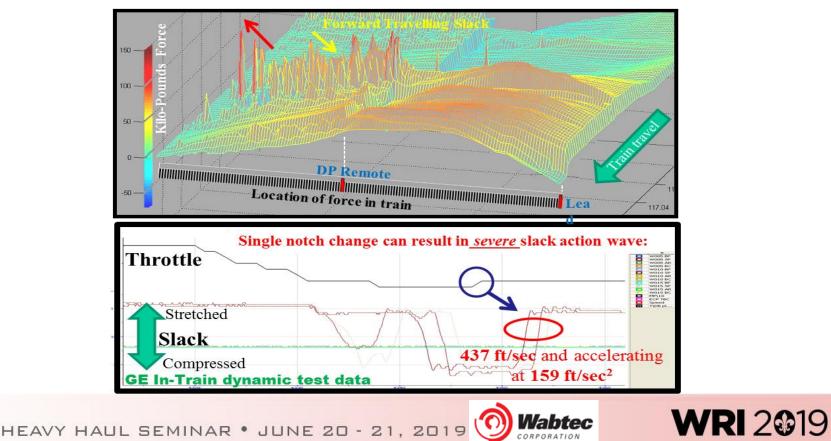
# DP RESULTED IN AN AVERAGE 80% LESS Rail Wear!

- Less friction wear = less Fuel
- Longer Wheel Life
- Less Track grinding/replacement
  Downtime
- Less Sleeper/Wheel Maintenance



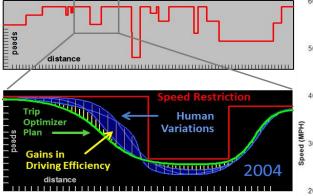


# Less Destructively: Distributed Power Slack Action Control

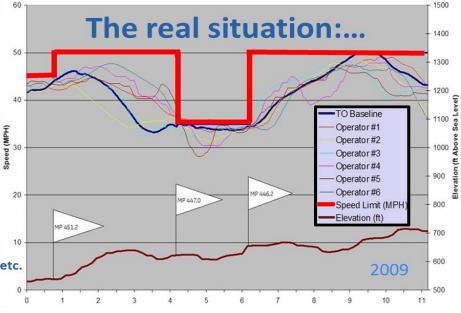


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## **More Productively: Trip Optimizer**



Human Variations Due to: Variations in train mass, Rolling resistance, Locomotive capability/de-rating, Wind, Train length, Mass distribution, Driver experience, etc.



### **Trip Optimizer**

- Plans the most efficient (Optimum) way to Drive for whatever is being Optimized (fuel, time, handling...)
- Automatically Drives to the plan

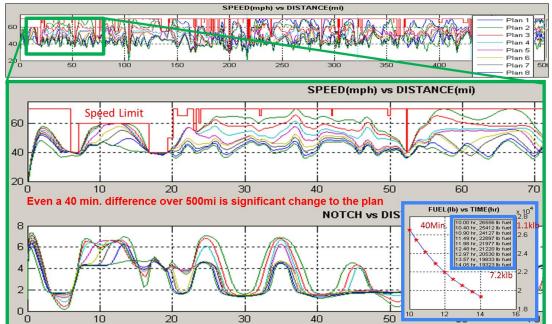




# **More Productively: Trip Optimizer**

### **TO Optimization/Plan – Complex Physics Based**

• <u>Full parametric optimization:</u> For a given set of parameters and constraints (speed restrictions, train mass, HP, train resistance, in-train force, time, etc.), there is <u>only one</u> optimum solution. Upon on *new or learned* data TO can rapidly Calculate the change



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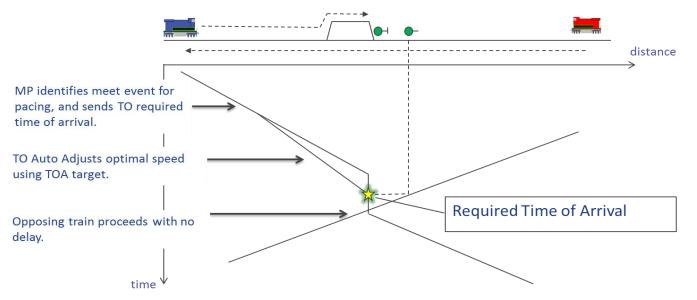
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RPORATION

### **More Productively: Trip Optimizer**

### **Energy Efficient Train Meet**





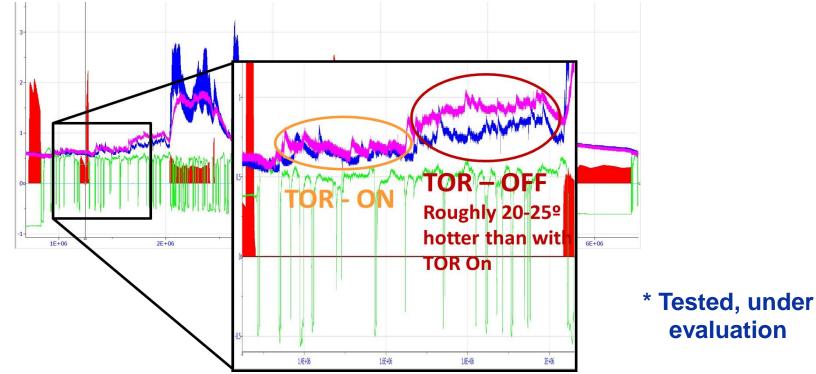
Delayed train saves fuel by pacing approach to meet



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## Less Destructively: Trip Optimizer Friction Modifier Control\*



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# Less Destructively: Trip Optimizer/DP Computer Controlled Slack Action Control

### Relative speed control

#### Concept

Regulate difference between crucial car speeds along the trip

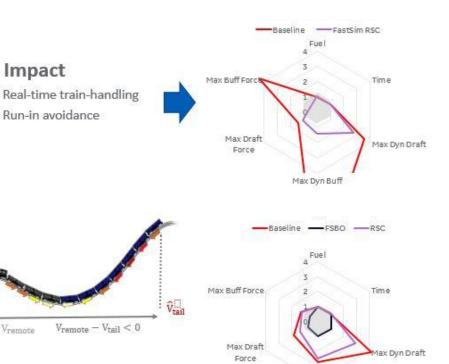
Multiple interacting speed control loops

Train traveling

 $V_{lead} - V_{remote} < 0$ 

- · relative speeds between consists
- planned speed deviation
- remote loco to tail speed

Planned speed





Vlead





