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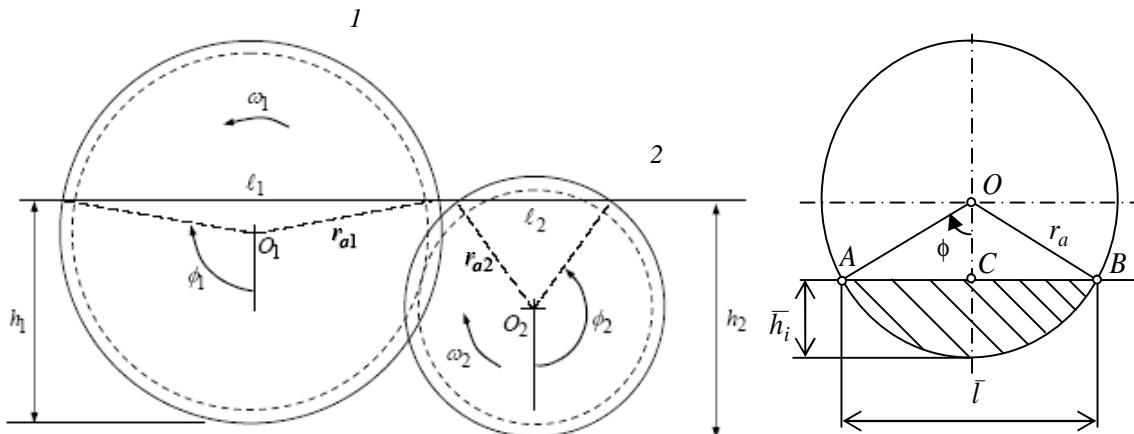
50–80%,

[3], [4], [5], [6]

Changenet [7], [8]. [9]

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$$\begin{aligned}
 i - & , \\
 & , \\
 & : \\
 M_{\Gamma} = & M_k + M_T + M_P, \quad (1) \\
 M_k - & , \\
 & , ; \\
 M_T - & ; \\
 M_P - & .
 \end{aligned}$$



. 1.

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$$\bar{h}_i = h_i / r_{ai} \leq 0 \quad (\text{--- . 1})$$

$$(\bar{h}_i \geq 2, \bar{h}_i \leq 0,$$

$$\bar{h}_i = 2,$$

$$\bar{h}_i \leq 2 \quad \phi_i \leq \pi$$

$$(\text{--- . 1})$$

$$A = [\arccos(1 - \bar{h}_i) - \sqrt{\bar{h}_i \cdot (2 - \bar{h}_i)} \cdot (1 - \bar{h}_i)] \cdot r_{ai}^2, \quad (2)$$

$$\phi_i = \arccos(1 - \bar{h}_i) - \quad (\text{--- . 1});$$

r_{ai} - , .

$$(\quad . \quad 1) \\ l = 2 \cdot r_{ai} \cdot \sqrt{\bar{h}_i \cdot (2 - \bar{h}_i)} . \quad (3)$$

$$n_z = \frac{2 \cdot \phi_i \cdot r_i}{\pi \cdot m} = \frac{2 \cdot \phi_i \cdot r_i \cdot z_i}{\pi \cdot 2 \cdot r_i} = \frac{\arccos(1 - \bar{h}_i) \cdot z_i}{\pi} , \quad (4)$$

$$r_i = \dots ; \\ z_i = \dots ; \\ F_k , \quad ,$$

$$F_k = m^b \cdot a_k , \quad (5)$$

$$m^b = \left(m_{\max}^b + m_{\min}^b \right) / 2 ; \\ m_{\max}^b = \dots ; \\ m_{\min}^b = 0 ; \\ \vdots ; \\ a_k = \dots , \quad , \quad / ^2 .$$

$$V_\tau = \omega_i \cdot r_i \cdot \sin \alpha \cdot \cos \beta ,$$

$$a_k = 2 \cdot \omega_i \cdot V_\tau = 2 \cdot \omega_i^2 \cdot r_i \cdot \sin \alpha \cdot \cos \beta , \quad (6)$$

$$\omega_i = \dots , \quad / ; \quad \alpha = \dots ; \\ \beta = \dots , \quad .$$

$$m_{\max}^b = Q_3 \cdot \Delta t , \quad (7)$$

$$Q_3 = \dots , \quad , \quad / ; \\ \Delta t = \dots , \quad .$$

$$(\quad . \quad 1): \\ \Delta t = \frac{\cup}{\omega_i} = \frac{2 \cdot \phi_i \cdot r_i}{\omega_i} = \frac{2 \cdot r_i \cdot \arccos(1 - \bar{h}_i)}{\omega_i} . \quad (8)$$

$$Q_3 = k_s \cdot A \cdot \rho_m \cdot V_3 , \quad (9) \\ \rho_m = \dots , \quad / ^3 ; \\ A_a = S_{bn} \cdot \sum_{i=1}^2 y_i = \dots , \quad ^2 ;$$

$$\begin{aligned}
y_i &= \frac{4 \cdot B_i \cdot \bar{\delta}_i}{(A_i^2 - B_i^2)} ; \\
\bar{\delta}_i &= \delta_i / r_i ; \\
\delta_i &- ; \\
S_{bn} &- [10], \quad ^2; \\
k_s &- ; \\
A_i &= r_{ai} / r_i ; \\
B_i &= r_{fi} / r_i ; \\
r_f &- ; \\
V_3 &- , \quad / . \\
m^b &= \frac{A \cdot \rho_m \cdot V_3 \cdot r_i \cdot \arccos(1 - \bar{h}_i)}{\omega_i} .
\end{aligned} \tag{10}$$

$$\begin{aligned}
&\vdots \\
\bar{V}_3^2 &= \bar{p}_b - \bar{p}_j - \bar{p}_g + \bar{p}_h + \frac{k_o^2 \bar{V}_\tau^2}{2}, \\
\bar{p}_b &= p_b / (\rho_m \cdot \omega_i^2 \cdot r_i^2) = \Phi_i / \sqrt{\text{Re}} ; \\
\bar{p}_j &= 0,5 \cdot (A_i^2 - B_i^2) ; \\
\bar{p}_g &= (A_i - B_i) / Fr ; \\
p_h &= r_i \cdot \bar{h}_i \cdot g \cdot \rho_m / (\rho_m \cdot \omega_i^2 \cdot r_i^2) = \bar{h}_i / Fr , \\
k_o &- ; \\
\Phi_i &= (\bar{V}_\tau / \Phi_i)^{1,5} \cdot (tg^2 \alpha_a - tg^2 \alpha_f) \cdot \cos \alpha / (A_i \cdot \sqrt{3}); \\
V_\tau &= V_\tau / (\omega_i \cdot r_i) ; \\
\text{Re} &= (\omega_i \cdot r_i^2) / \vartheta_m ; \\
\vartheta_m &- , \quad ; \\
\alpha_a, \alpha_f &- , \quad ; \\
Fr &= (\omega_i^2 \cdot r_i) / g ; \\
\Phi_i &- , \quad .
\end{aligned} \tag{11}$$

$$V_\tau \quad , \quad V_3 .$$

$$\frac{V_3}{\omega_i r_i} = \bar{V}_3 = \sqrt{\left(A_i^2 - B_i^2\right) + \frac{2}{Fr} \cdot (\bar{h}_i - A_i - B_i) + \frac{2 \cdot \Phi_i}{\sqrt{\text{Re}}} + (k_o \cdot \sin \alpha \cdot \cos \beta)^2} . \quad (12)$$

$$M_k = \frac{\rho_m \cdot \omega_i^2 \cdot r_i^5}{\pi} (\pi - 4x \cdot \operatorname{tg} \alpha) \cdot (A_i^2 - B_i^2) \cdot \sum_{i=1}^2 y_i \cdot \bar{V}_3 \cdot \arccos^2(1 - \bar{h}_i) \cdot \sin \alpha \cdot \cos^2 \beta. \quad (14)$$

$$M_k = \rho_m \cdot \omega_i^2 \cdot r_i^5 \cdot (A_i^2 - B_i^2) \cdot \sum_{i=1}^2 y_i \cdot \bar{V}_3 \cdot \arccos^2(1 - h_i) \cdot \sin \alpha \cdot \cos^2 \beta. \quad (15)$$

$$C_k = 2 \cdot \left(A_i^2 - B_i^2 \right) \cdot \sum_{i=1}^2 y_i \cdot \bar{V}_3 \cdot \arccos^2(1 - \bar{h}_i) \cdot \sin \alpha \cdot \cos^2 \beta. \quad (16)$$

(. . 1),

$$M = F \cdot r_{ai} = 4 \cdot \mu_m \cdot b_i \cdot r_{ai}^2 \cdot \omega_i \cdot \phi_i, \\ \text{Re} = \rho_m \cdot r_i^2 \cdot \omega_i / \mu_m \quad \bar{b} = b/r_i, \quad (17)$$

$$M = \frac{4 \cdot \mu_m \cdot A_i^2 \cdot \bar{b}_i \cdot r_{ai}^5 \cdot \omega_i^2 \cdot \phi_i \cdot \rho_m}{\rho_m \cdot \omega_i \cdot r_i^2} = \frac{4 \cdot A_i^2 \cdot \rho_m \cdot \bar{b}_i \cdot r_{ai}^5 \cdot \omega_i^2 \cdot \phi_i}{\text{Re}},$$

$$\bar{b} = b/r_i \quad ;$$

b - , .

$$\phi_i = \arccos(1 - h_i),$$

$$C = \frac{M}{0,5 \cdot \rho_m \cdot r_i^5 \cdot \omega_i^2} = \frac{8 \cdot A_i^3 \cdot \bar{b}_i \cdot \arccos(1 - \bar{h}_i)}{\text{Re}}. \quad (18)$$

$$C = \frac{2 \cdot A_i^2 \cdot [\arccos(1 - \bar{h}_i) - \sqrt{\bar{h}_i \cdot (2 - \bar{h}_i)} \cdot (1 - \bar{h}_i)]}{0,5 \cdot \rho_m \cdot \omega_i^2 \cdot r_i^5} = \frac{2 \cdot A_i^2 \cdot [\arccos(1 - \bar{h}_i) - \sqrt{\bar{h}_i \cdot (2 - \bar{h}_i)} \cdot (1 - \bar{h}_i)]}{\sqrt{6 \cdot i \cdot \sqrt{\bar{h}_i \cdot (2 - \bar{h}_i)} \cdot \text{Re}}}. \quad (19)$$

$$= \frac{M}{0,5 \rho_m \omega_i^2 r_i^5} = \frac{i^2 \cdot 0,0276 \cdot [\arccos(1 - \bar{h}_i) - \sqrt{\bar{h}_i \cdot (2 - \bar{h}_i)} \cdot (1 - \bar{h}_i)]}{\sqrt[7]{2 \cdot i \cdot \sqrt{\bar{h}_i \cdot (2 - \bar{h}_i)} \cdot \text{Re}}}. \quad (20)$$

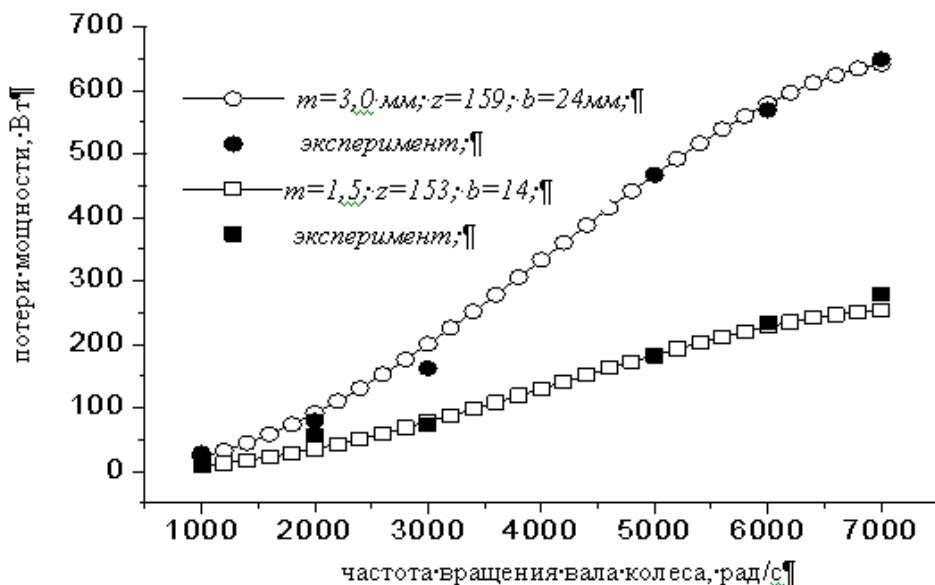
$$M_{\Gamma} = 0,5 \cdot \rho_m \cdot \omega_i^2 \cdot r_i^5 \cdot (C_k + C_T + C_P). \quad (21)$$

$$P_{\Gamma} = 0,5 \cdot \rho_m \cdot \omega_i^3 \cdot r_i^5 \cdot (C_k + C_T + C_P). \quad (22)$$

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(22)

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21.01.2012.

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CHURNING POWER LOSSES
IN HIGH-SPEED GEARED
TRANSMISSIONS

A series of formulas which enable accurate prediction of churning power losses for one pinion characteristic of gear transmission geometry and physical properties of lubrication are presented. On the basis of the offered dependences the method of calculation, enabling with the minimum expenses of calculable efforts in number to estimate the churning power losses, is developed. Specific gravity of different making losses of power is exposed. Obtained results have been experimentally validated over a wide range of speeds and gear geometries.

Keywords: gears, churning power, dimensionless drag torque, pressure, immersion depth, Reynolds number, Froude number, rotational speed, immersed surface area, tooth face width, number of teeth, gear pitch radius.