



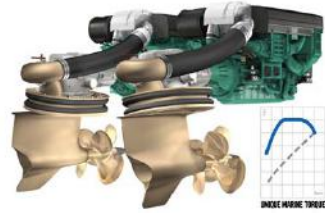
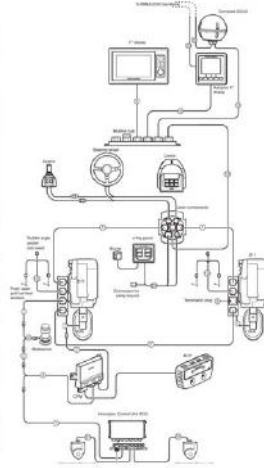
## **High speed pod propulsion – Application and Integration**

Jon Wingren – Volvo Penta Application & Integration Specialist

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# Fully developed system from Propeller to Antenna

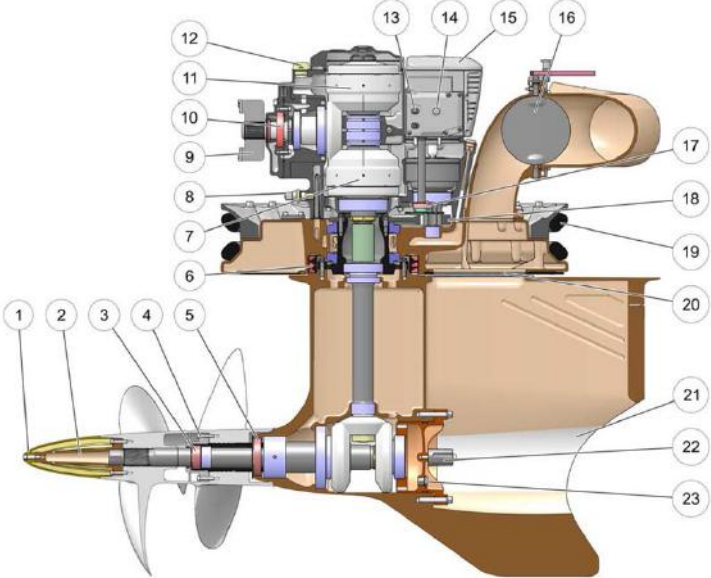
Larger system = more responsibility = closer cooperation



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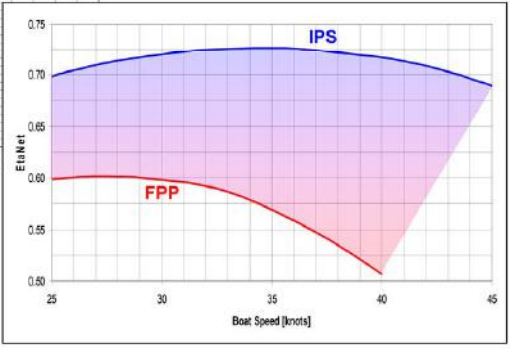
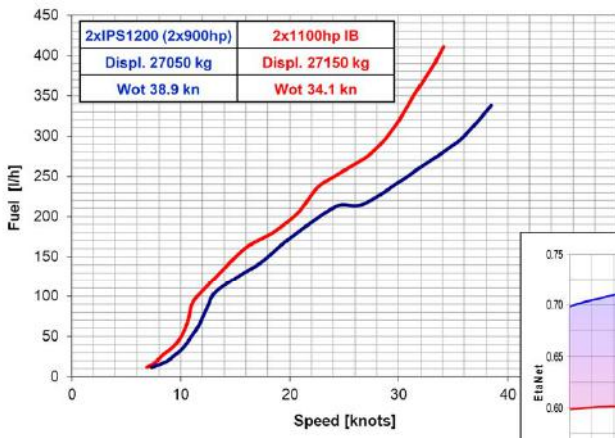
# IPS hardware



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# Efficiency



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## Speed/application window

Maximum speed application window 20 to 40+ knots



Name	IPS900	IPS1050	IPS1050	IPS1200
Power, ratio, rpm	D13-700, 1.99, 2250	D13-800, 1.99, 2300	D13-800, 1.88, 2300	D13-900, 1.88, 2300
Propeller range	QS5-Q7	QS5-Q7	Q1-Q7	Q2-Q7
Boat speed*	20.7-37.2kn	20.3-37.3kn	26.1-41.4kn	27.1-40.2kn

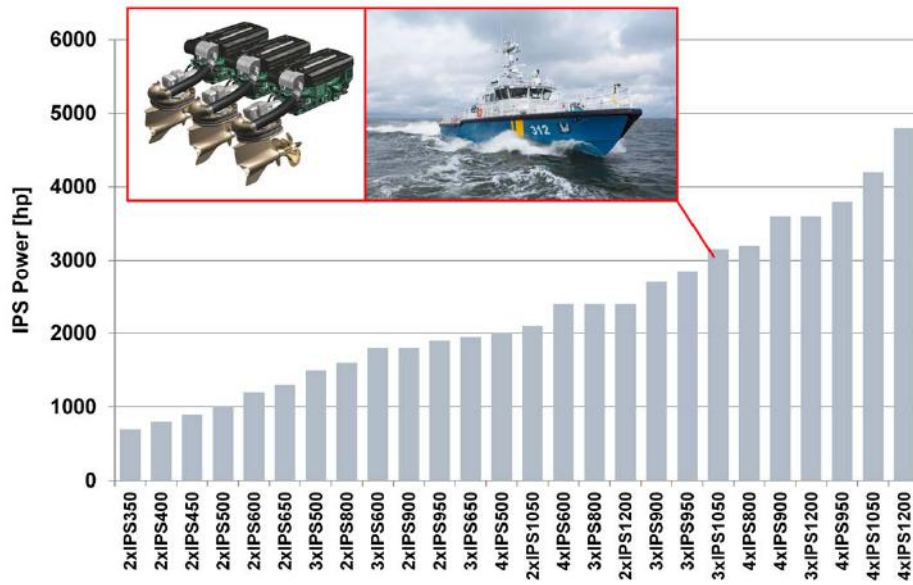
Name	IPS650	IPS800	IPS800	IPS800	IPS900	IPS950
Power, ratio, rpm	D11-510, 1.70, 2250	D11-600, 1.59, 2300	D11-600, 1.70, 2300	D11-625, 1.70, 2400	D11-700, 1.59, 2350	D11-725, 1.70, 2500
Propeller range	PS4-P7	P2-P7	PS4-P7	PS4-P7	(P1) P2-P7	P1-P7
Boat speed*	18.7-37.3kn	28.7-41.8kn	17.8-37.1kn	19.9-39.7kn	28.2-41.5	27.7-41.1

Name	IPS350	IPS400	IPS400MC	IPS450	IPS500	IPS600
Power, ratio, rpm	D4-260, 2.08, 3500	D4-300, 2.08, 3500	D6-310, 1.94, 3500	D6-330, 1.94, 3500	D6-370, 1.94, 3500	D6-435, 1.82, 3500
Propeller range	TS3-T10	TS3-T10	TS3-T10	TS3-T10	TS3-T10	TS3-T10
Boat speed*	17.5-44kn	15.5-42.3kn	19.4-47.8kn	18.6-47.1kn	16.9-45.7kn	18.5-49.2kn

\* Approx. boat speed at engine rated speed

Volvo Penta can NOT deliver outside indicated range.

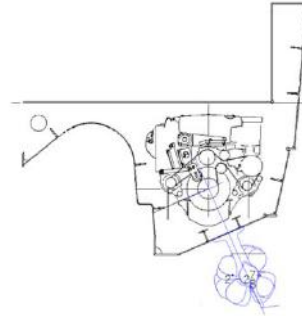
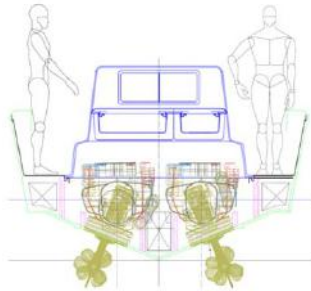
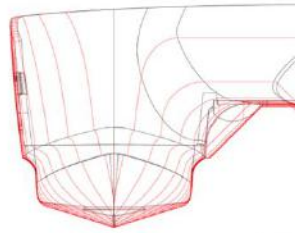
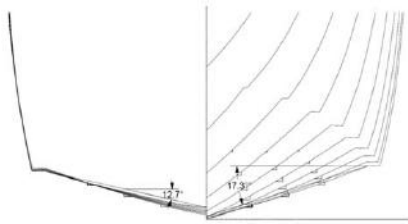
## Product configurations and power range



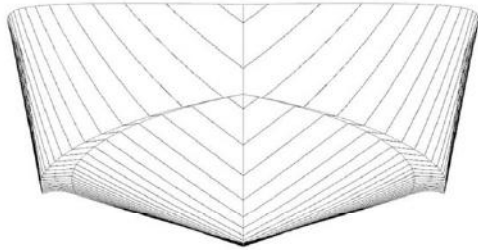
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## Experience of different hull shapes



## Monohull



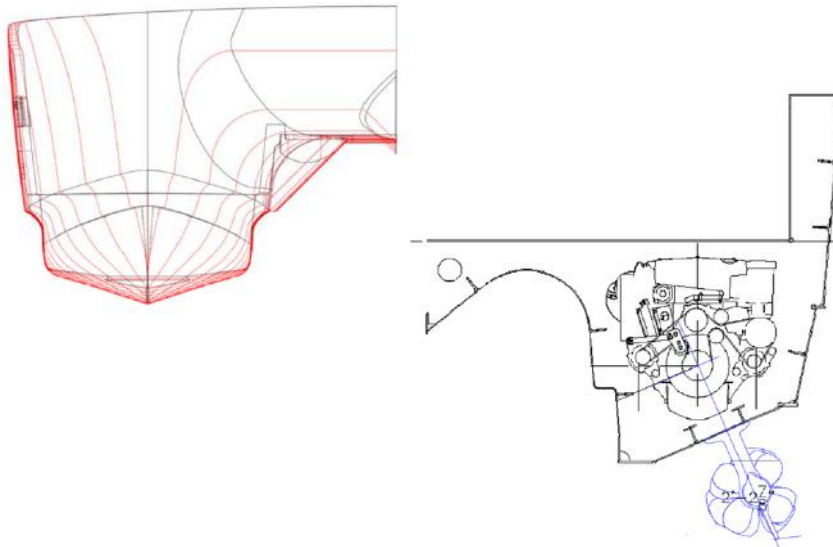
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The IPS system was designed around a monohull shape. Steering configurations, drawings, testing, etc. was made for monohull shapes and there are remnants left in the software due to this. However, the vast number of samples have clearly shown that almost any hull shape is applicable.



## Symmetrical & Asymmetrical catamarans



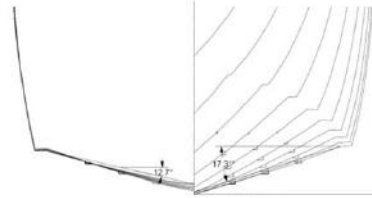
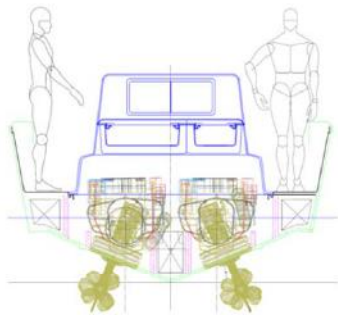
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The symmetrical catamaran is suitable with IPS and will in most cases have the units fitted without deadrise (vertical). This means that some information needs interpretation, example: installation drawing toe-in angle. Steering modes may be limited, several cases with large beam vessels require minimum steering setting.

The asymmetrical catamaran hull is very suitable with IPS but the demi-hulls will in most cases be rather narrow in comparison to symmetrical installations and may be a difficult integration due to service and articulation requirements. Asymmetrical catamarans are normally less efficient than symmetrical, unless very tuned or supported by other assistance, such as foils.

## Deep V and shallow V hulls



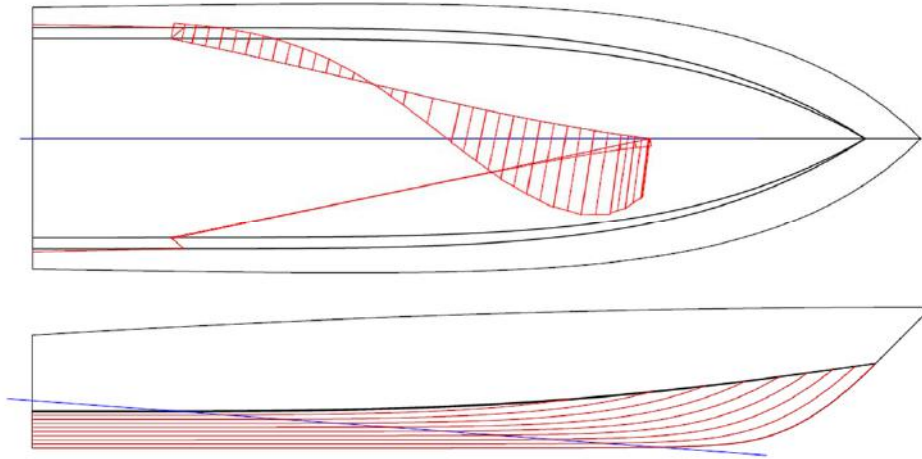
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The deep V is a well functioning hull shape for IPS although the high deadrise, normally above 18-20deg, will allow the IPS to generate substantial rolling moments. A deep V hull must be combined with a low center of gravity and/or aggressive chines to maintain comfortable turning characteristics in combination with IPS.

The low deadrise hull has some good qualities in combination with IPS due to its properties of reduced induced rolling moment and high initial stability. However, since boats with low deadrise run at low trim angles at high speed they may suffer from dynamic instabilities tendencies and articulating pods exaggerates heel and in many cases increases top speed. It may in some cases be difficult to balance these hulls, both transversally but also longitudinally.

## Monohedron hulls

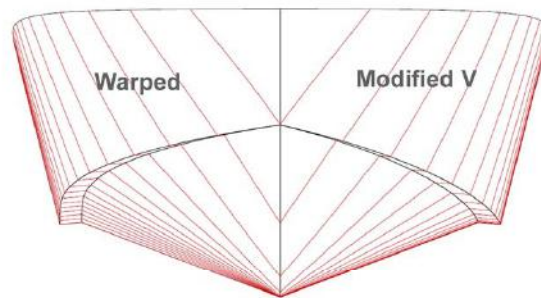


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The monohedron (aka constant deadrise = parallel buttock lines) hull shape has for a long time been considered the most efficient shape for planing boats (without transversal steps). It has been seen in VP testing that it is also the best performer in combination with IPS. The negative aspect is that it requires a rather high deadrise to produce a comfortable ride which means that the rolling moment of IPS is introduced. A well balanced monohedron shape with low vertical center of gravity and slightly above normal chines will produce a very nice IPS application.

## Warped and Modified V hulls

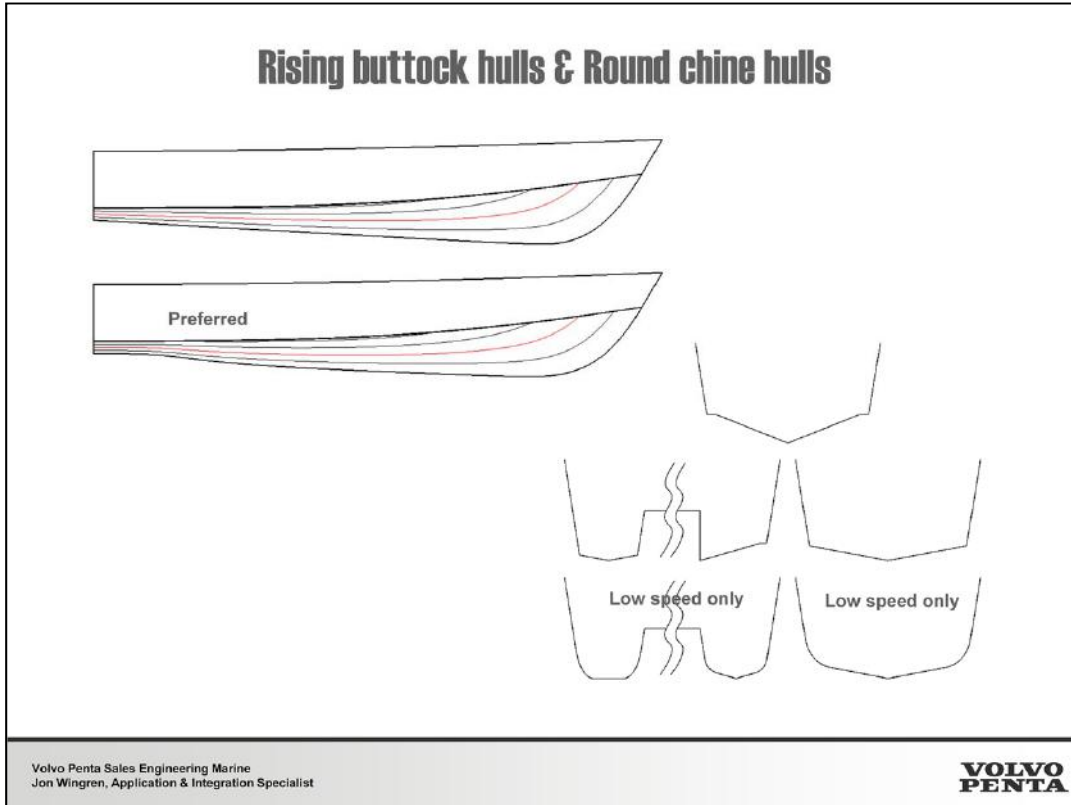


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The warped hull was the first planing hull type. It is good for low planing speeds and is suitable for carrying weight far aft. The negative aspects are that the behavior is somewhat unpredictable especially when turning with typically reduced trim angles and longitudinal trim change over speed is usually exaggerated due to the balance of the boat.

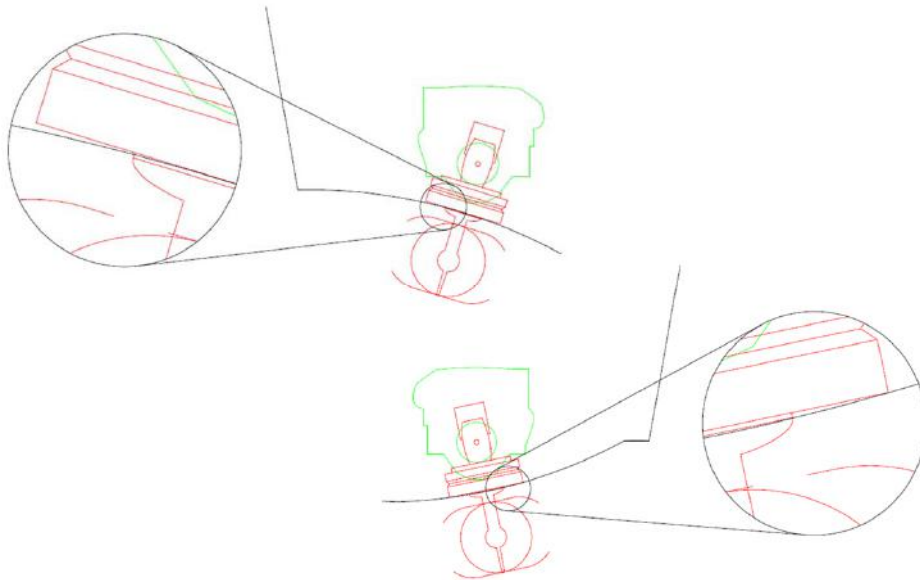
The modified V is a good contender of what might be considered the most popular IPS hull. It combines the sharp entry of the warped hull while the change in deadrise is rather small which is favorable for efficiency. Most versions of this hull shape also have straight sections which makes the integration with IPS simpler.



The traditional rising buttock hull, typically applied in low speed boats (semi-planing high efficiency) has been judged to work well in configuration with IPS given a relatively low speed, around or below  $F_n V = 2.6$ . However the IPS units tested have so far been fitted close to horizontally. This works with benefit to both the thrust angle of IPS but also to give a slight pressure increase to the hulls dynamic balance which in many cases reduces hull drag.

A round chine hull is normally not suited to high speed applications. As for IPS, it is to be avoided unless the speed is kept at a minimum and vertical center of gravity is low in comparison to effective width (natural with catamaran). Risk of air interfering with the propellers and steering may be affected. Poor efficiency, sudden rpm increase or steering oscillations may be the result.

## Concave and Convex section shape



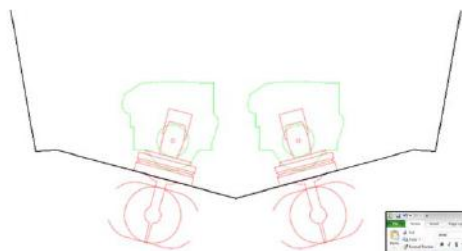
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A concave section shape will improve transverse dynamic stability for low to medium speed applications and also improve small sea state comfort but may also reduce efficiency. The section must not be concave in the area immediately next to or in the interface of the IPS. If this is the case it is likely the unit will mechanically interfere with the hull and the steering forces may be exaggerated.

A convex hull has good planing efficiency but is very poor at generating transverse dynamic stability and in some cases also course stability. It normally requires very large reverse angle chine flats to compensate for the lack of stability, even more so in combination with pod propulsion. The convex shape will also make it difficult to integrate the IPS unit. It is very likely that the result will be negative, similar to the concave shape.

## Straight section shape



The screenshot shows a spreadsheet with the following data:

Instruction: Decide hull type by choosing worksheet, set 'Input values', copy column J and paste in B26n0.					
	Input values				Parameters to build
1	IPS design	1	1	1	IPS design
2	IPS design	1	1	1	IPS design
3	IPS design	1	1	1	IPS design
4	IPS design	1	1	1	IPS design
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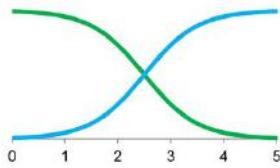
A straight section shape will by far be the simplest to integrate IPS with. It is easy to predict and check and will in most unspecific cases be most efficient. VP recommends this section shape to be the geometric starting point.

# IPS integration process and involvement from Volvo Penta, 1

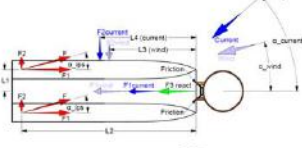
## BOAT DESIGN STAGE

- Input: 3D hull + accurate load data, VP can arrange for scale weighing of current model if needed
- Processing: speed, trim, performance liabilities, geometric aspects, GA considerations
- Result: IPS prospect review report (to OEM/MU)
- . . . secondary reviews based modified data.

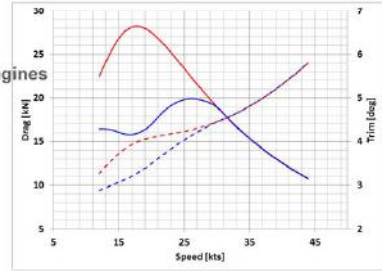
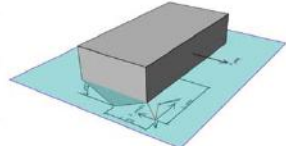
$$RF2.0 = k_1(1 - 1/e^{5-2F_{NV}}) + (k_2 + k_3 + k_4) 1/e^{5-2F_{NV}}$$



- Points of technical review
- Main hull geometry
  - Load cases
  - Location of IPS units/engines
  - Structural solution
  - Specific hull geometry
  - Speed prediction
  - Trim prediction
  - Fuel prediction
  - Joystick analysis
  - Bottom loading
  - Stability index
  - Roll factor 2.0



2 Engines	
R <sub>tot</sub>	143
A <sub>tot</sub>	87 m <sup>2</sup>
V <sub>tot</sub>	10 m/s
V <sub>act</sub>	8.57 m/s
L <sub>tot</sub>	0.86 m
C <sub>D</sub>	1.35
P <sub>tot</sub>	13.2 MW
F <sub>tot</sub>	4622 N
F <sub>act</sub>	2158 N
G <sub>tot</sub>	45.2
Weight	21700 N



OEM = Boat builder, MU = Volvo Penta Market Unit, SEM = Volvo Penta Sales Engineering Marine

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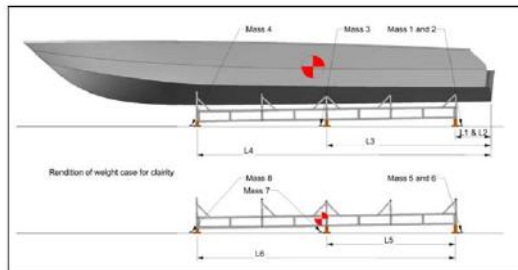
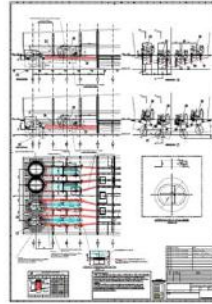
## IPS integration process and involvement from Volvo Penta, 2

### BOAT BUILDING STAGE

- Structural process advice, installation advice, adaptation and interpretation of rules and guidelines.

### BOAT ADAPTATION STAGE

- Follow up scale weighing (up to 110 metric tons)



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## IPS integration process and involvement from Volvo Penta, 3

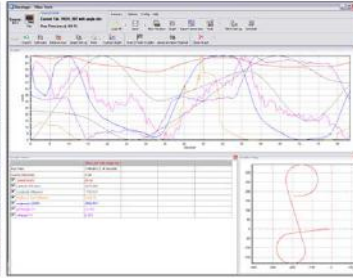
### BOAT VERIFICATION AND/OR ADAPTATION STAGE

- Follow-up: sea-trial with behavior test (rpm, speed, trim, heel, acceleration, consumption) + report, propeller choice!
- Hull and load adaptation/modifications based on test data.
- Re-verification.

$$\alpha = \arctan\left(\frac{v^2}{g \cdot r}\right)$$



v = velocity [m/s]  
g = gravitational constant  
r = radius of turn



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