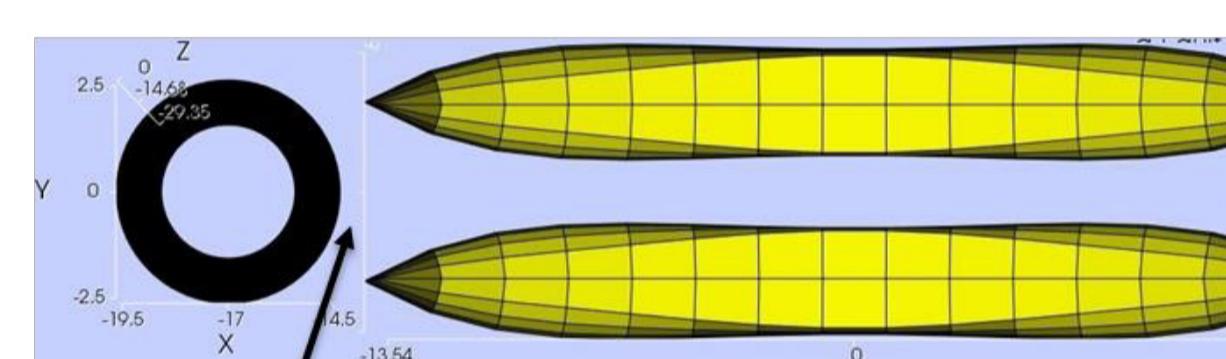
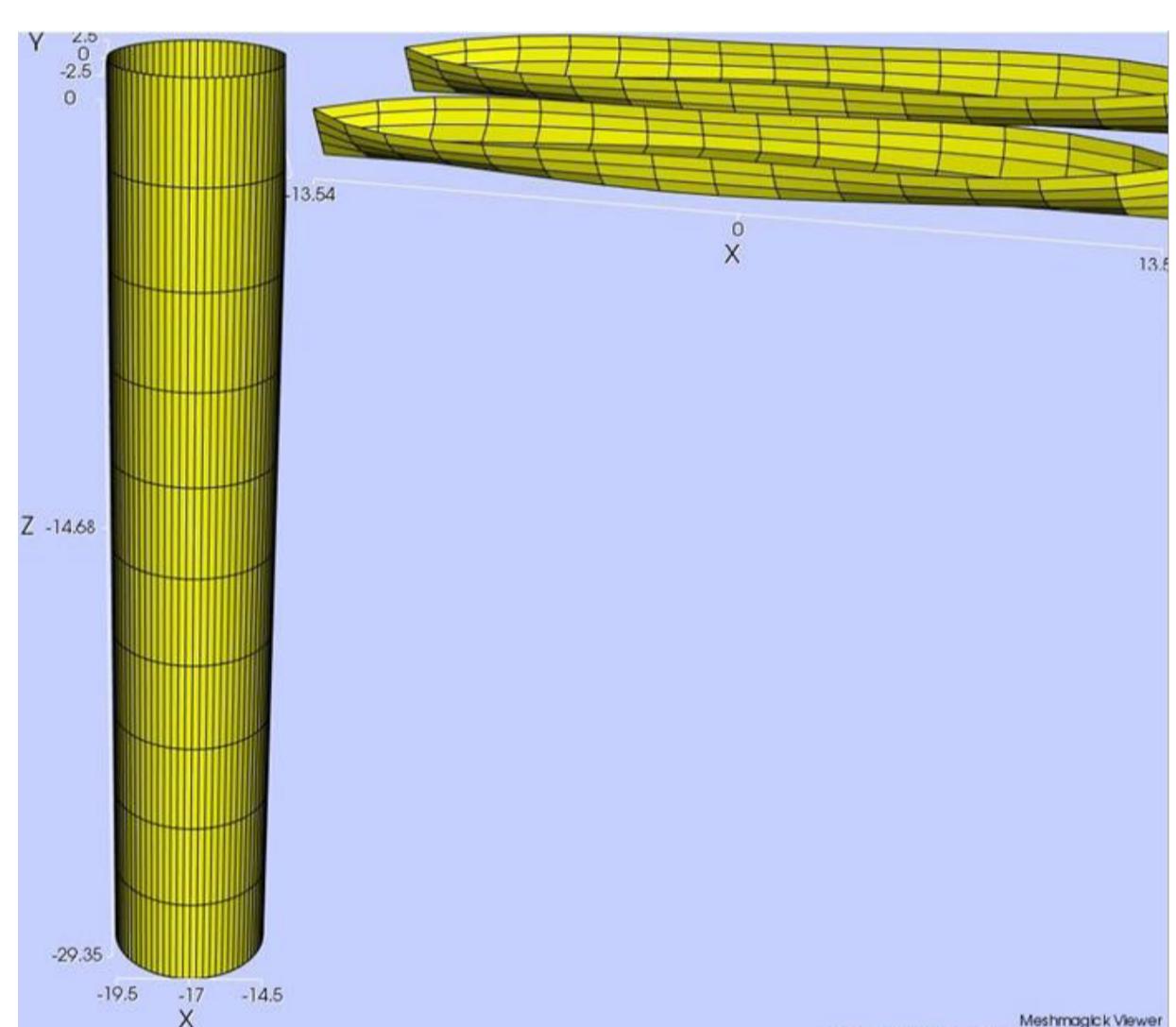




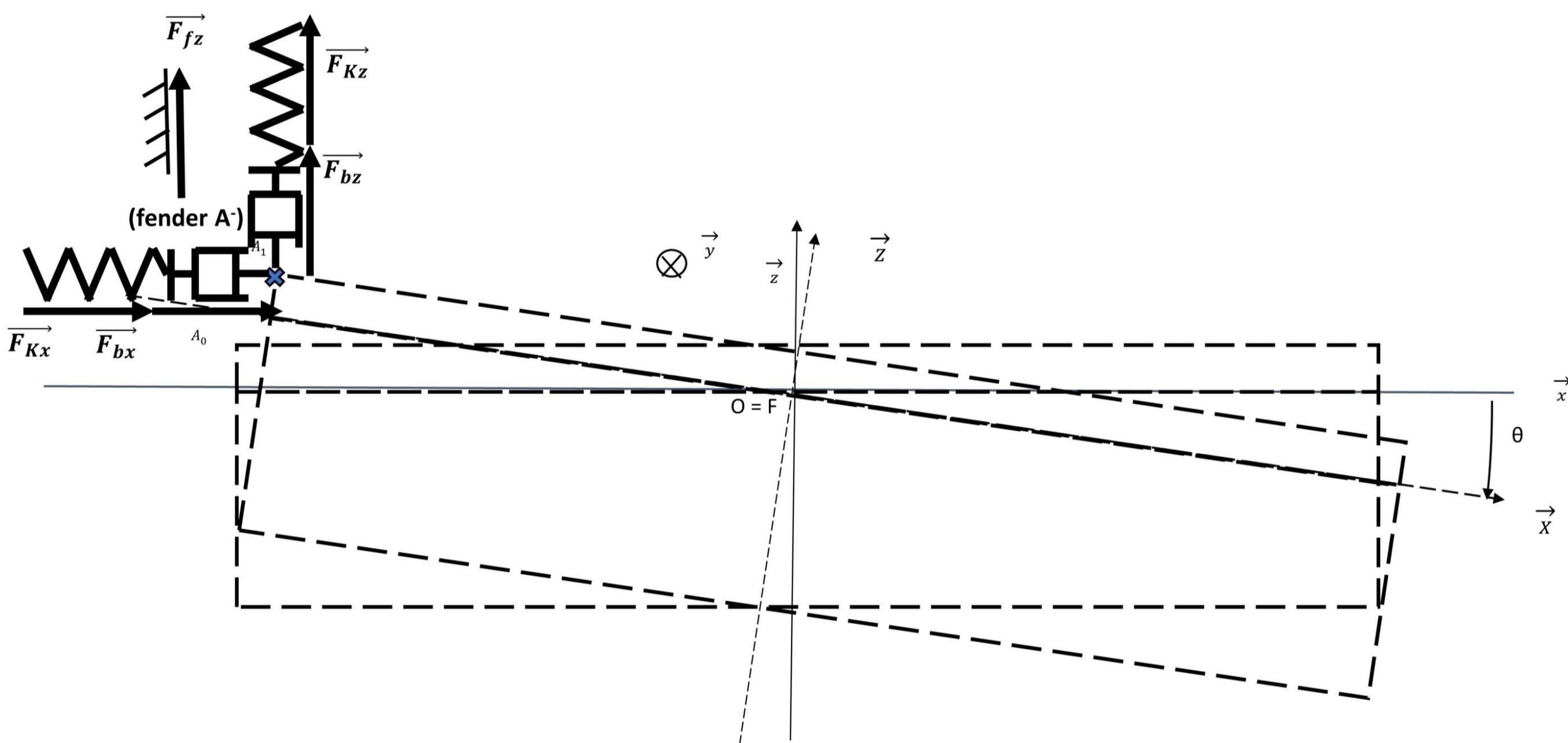
Berthing of CTVs against Offshore Wind Turbines by Kinetic/Static Friction

Berthing catamaran Crew Transfer Vessel (CAT CTV) against monopile

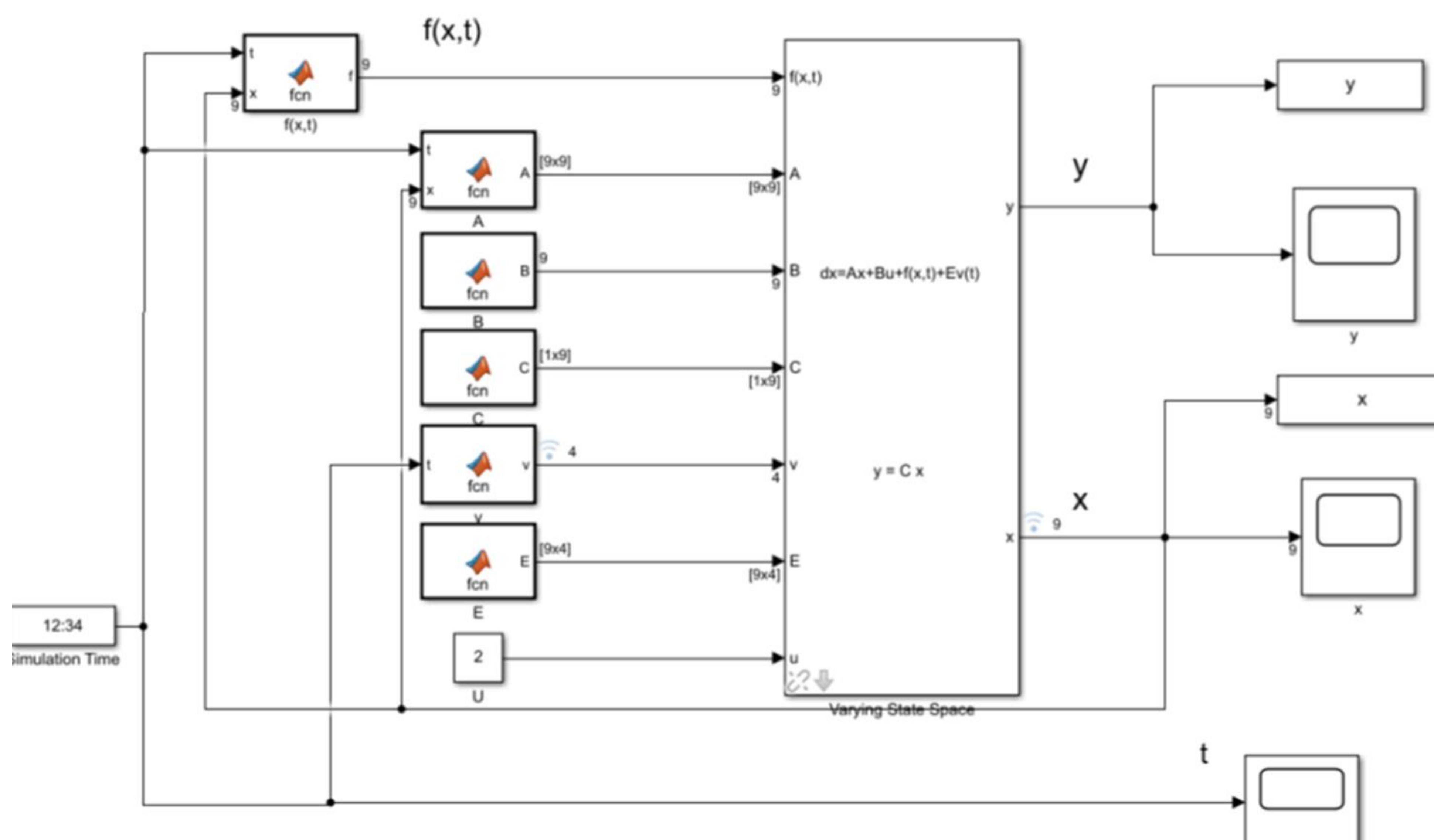


Approximation: CAT with Wigley hulls

CAT/monopile contact: horiz. & vertical springs & dampers, vertic. friction force



MATLAB/SIMULINK model



Results : significant wave height (Hs) and wave length berthing limitations

Wave length / boat length	CAT CTV 27m [2] 2017 benchmark	CAT CTV 27m [3] 2022 linear calc. (pseudo-kinetic friction)	CAT CTV 27m 2024 non linear calc. (either kinetic or static friction)
0		2m Hs	
1,76			2m Hs
1,80	2m Hs		
1,85		1,5m Hs	
14	1,5m Hs		1,5m Hs

Conclusion: Non-linear calc. meets wavelength boarding criteria from ref. [2] (benchmark) and [3] (linear calc.) with respectively -3% and +2% accuracy. Next step : irregular wave analysis.

Références: [1] AUESTAD Oyvind, GRAVDAHL Jan, PEREZ Tristan, SORENSEN Asgeir, & ESPELAND Trygve (2015): "Boarding control system for improved accessibility to off-shore wind turbines: Full-scale testing", Control Engineering Practice, 45, pp. 207-218
[2] Nere G. Skomedal and Trygve Halvorsen Espeland (2017) Cost-effective Surface Effect Ships for Offshore Wind, FAST 2017 conference, Nantes, France. ESNA AS, KRISTIANSAND S, NORWAY, 7.

[3] Laurent BARTHELEMY (2022): "Optimizing Berthing of Crew Transfer Vessels against Floating Wind Turbines – A Comparative Study of Various Floater Geometries", ECOLE NATIONALE SUP. MARITIME, NANTES, FR, SEANERGY 2022 conference, Le Havre, FR.

Equations ruling CTV motion [1]

$$\begin{bmatrix} m + m_a & 0 & I_{GA15} & \ddot{x} \\ 0 & m + m_{a3} & 0 & \ddot{z} \\ I_{GA15} & 0 & 0 & \ddot{\theta} \\ B_{11} & 0 & B_{15} & \dot{x} \\ B_{31} & B_{33} & B_{35} & \dot{z} \\ B_{15} & B_{53} & B_{55} & \dot{\theta} \\ K_{11} & 0 & K_{15} & x \\ K_{31} & K_{33} & K_{35} & z \\ K_{15} & K_{53} & K_{55} & \theta \end{bmatrix} = F$$

Fender fictitious mass motion [1]

$$m_* \cdot \ddot{z}_{MC} = F_{Fz} - F_{Kz} - F_{Bz}$$

SIMULINK State-space model [1]

$$\dot{x} = Ax + f(x) + Ev$$