## Claims

1. A SHARED ACTUATION SYSTEM, for positioning an actuation tool relative to several valve interfaces on a subsea structure as a manifold, comprises:

a connection device for connection to the subsea structure, the system characterised in that, the connection device being connected to the subsea structure by means of a first rotary joint,

a first structural element connected to said subsea structure and to the connection device by means of the first rotary joint and of a second rotary joint,

a second structural element connected to a first end of the first structural element by means of a third rotary joint, the rotary joints providing at least two degrees of freedom for a distal end of the second structural element where the actuation tool is positioned for interaction with the valve interfaces on the subsea structure,

a sail element connected to an opposite second end of the first structural element, the sail element being designed to compensate the weight, at least one of the first structural element and the second structural element having a hydrodynamic profile formed with a relative thinner cross section at two forward edges opposite each other compared with a trailing part of the structural element in movement directions.

2. THE SHARED ACTUATION SYSTEM according to claim 1, wherein the connection device comprises a single interface comprising a pin or funnel for interaction with complementary elements on the subsea structure.

3. THE SHARED ACTUATION SYSTEM according to claim 1 or 2, wherein said rotary joints are elements sealed to the external environment.

4. THE SHARED ACTUATION SYSTEM according to any one of claims 1 to 3, wherein said rotary joints are offset by lubricating oil that protects the rotary joints in the subsea environment.

5. THE SHARED ACTUATION SYSTEM according to any one of the preceding claims, wherein at least a part of the first element and the second structural elements is made of composite materials.

6. THE SHARED ACTUATION SYSTEM according to claim 5, wherein the submerged weight of the shared actuation system is less than 100 kg.

7. THE SHARED ACTUATION SYSTEM according to any one of claims 1 to 6, wherein the operation of the shared actuation system when deployed in the seabed is carried out by remotely operated vehicles (ROVs).

8. THE SHARED ACTUATION SYSTEM according to claim 7, comprising two electrical connectors for the ROV to be able to connect jumpers to subsea lines,

wherein the first electrical connector is for the power unit and the second electrical connector is for the communication to the top-side unit.

9. THE SHARED ACTUATION SYSTEM according to any one of claims 1 to 8, wherein the sail element comprises a robotic motion unit and a robotic drive unit,

wherein the robotic motion unit and the robotic drive unit responsible for the autonomous movement of the actuation tool.

10. THE SHARED ACTUATION SYSTEM according to claim 7 or 8, comprising one or more handlers to connect with ROV operators.

11. THE SHARED ACTUATION SYSTEM according to any one of claims 1 to 10, characterized in that it comprises floating elements integral with and/or attached to the system.

12. THE SHARED ACTUATION SYSTEM according to one of the claims 1 to

11, characterized in that it comprises a control system arranged to operate the rotary joints to position the actuation tool (2) relative to a desired valve interface for interaction with said valve interface.

13. THE SHARED ACTUATION SYSTEM according to claim 12, characterized in that the control system comprises a communication unit for communication with a remote located operator.

14. A SHARED ACTUATION SYSTEM according to any one of claims 1 to 6, characterized in that the system comprises one or more handlers for said system being lifted and operated in the seabed by a remotely operated vehicle (ROV).

15. THE SHARED ACTUATION SYSTEM according to claim 14, characterized in that said system comprises two electrical connectors for the ROV to be able to connect jumpers to subsea lines, wherein the first connector is for a power unit and the second connector is for communication with a top-side unit.

16. THE SHARED ACTUATION SYSTEM according to any one of claims 1 to 15, characterized in that the sail element holds two units that contain electronic elements as a robotic motion unit and a robotic drive unit responsible for an autonomous movement of the first and second structural element.

17. A SUBSEA SYSTEM, comprising a subsea structure and a shared actuation system according to one of the claims 1 to 16, characterized in that the shared actuation system is connected to the subsea structure in one fixed position, arranged such that the actuation tool at the distal end of the second structural element may be operated to interact with several valve interfaces arranged around said fixed position and at different radial distances from the fixed position.