

A tool for a horizontal connecting device

The present invention relates to a tool for lowering, alternatively later retrieval, of a pipeline end provided with a connecting part designed for “horizontal” mating with and connection to a first connecting part on the sea bed, and is so arranged that the tool can be brought to the surface again for reuse.

The tool is in particular developed with a view to deploy on the seabed a connecting device of the type described in Norwegian Patent Application NO 2009 3107 having the same applicant and inventor as in the present application. Reference is hereby given to that patent application.

In this context “horizontal connecting device” has that meaning that the connecting parts are mated in a substantially horizontal direction.

On subsea structures, for example manifold and valve structures, which are deployed on the seabed, piping is often arranged thereon having one or more pipes that terminate in open pipe subs, or porches, forming a connecting point. Each connecting point includes a stationary connecting part. In this context “Stationary” means relative to the subsea structure. The connecting point is later used for connection to an external pipe.

There exist two principles for the connecting devices, either vertical or horizontal. For a horizontal connecting device the connecting point projects horizontally out from the structure. In the North Sea this solution almost has market control. Other places, like the Gulf of Mexico for example, the vertical solution is the most common one.

One example of a vertical connecting device is shown in NO 2009 2880.

It is to be mentioned that in principle there are three (or actually two) different forms for external connections to a structure:

- Direct connection between two structures. Here, a rigid pipe having a mobile connecting part at each end normally will be used. This will usually be termed a

jumper. The jumper will be manufactured based on measuring the relative position of the two connecting points.

- Connection between the end of a pipeline (rigid pipe) and a structure. It is almost impossible (at least very difficult) to connect a rigid pipe line directly to a structure preinstalled on the seabed. Thus, an intermediate piece of pipe, frequently termed a "spool", is provided between the pipe line and the structure. In order to be able to connect the spool to the pipeline, the pipeline will be welded directly to a small structure including a connecting point. A spool is in principle like the jumper described above.

10 -Direct connection of a flexible pipeline or umbilical to a structure. In some cases it is chosen to use so called flexible pipes instead of rigid steel pipes. Such pipes can be compared with a big garden hose. Then it is not necessary with a spool or jumper between the end of the pipe and the structure. The pipe is so flexible that one may have a mobile connector part right on the end of the pipe, and connect this one
15 directly to the stationary connector part on the structure. Then it is neither necessary to make precise measurements of the position on the connecting point on the structure.

It is to the latter principle this application is related.

20 The tool has several main components and is such designed in one embodiment that each main component is in the form of a replaceable module. The tool can be used to deploy both a first and a second end of a flexible pipeline, yet after having made some modifications on the tool. The problems to be addressed can be somewhat different when the first end is to be laid from a surface vessel and down to the seabed compared
25 with deployment of the second end.

According to the present invention, a tool of the introductory said kind is provided, which tool is distinguished in that the tool comprises a central lifting frame, a guiding part forming an extension of the lifting frame, and a lifting yoke, which tool includes
30 gripping mechanisms which, in one situation, are actuatable to partly circumscribe and retain the pipeline end, and, in a second situation, the gripping mechanisms are releasable to release the pipeline end from the lifting frame

In one embodiment the gripping mechanisms are releasable from the pipeline end by operation (by ROV) of actuating means that preferably are accessible from above.

5 Preferably, each gripping mechanism includes a pawl that is pivotable arranged to the lifting frame where the pawl can be influenced by said actuating means which in turn acts against an inclined surface of the pawl in order to cause said pivoting motion.

In a suitable embodiment the tool is assembled of modules including a central lifting frame module, one control module releasable from the lifting frame module that forms
10 an extension of the lifting frame module, and a lifting yoke module releasable from the lifting frame module, which lifting frame module includes said gripping mechanisms.

The control module can be releasable from the lifting frame module by means of quick release means, such as a hook, lock pin or cotter pin.

15 The lifting yoke module may in turn be releasable from the lifting frame module by means of quick release means, such as a lock pin, snap hook or cotter pin.

It is to be noted that the tool is in particular designed to operate a connecting device that
20 includes:

a first connecting part supporting or retaining a first end of a first pipeline, which first connecting part and first pipeline are designed to be landed and deployed on the seabed in beforehand, and where the first connecting part includes a control structure located a distance apart from the pipe end,

25 a second submersible connecting part supporting, or retaining a second end of a second pipeline, which second connecting part and second pipeline are designed to be lowered from the surface together with the tool towards the first connecting part, and where the second connecting part includes the control module located a distance apart from the pipe end, and

30 a connector arranged between the connecting parts for final connection between the pipe ends.

Suitably, the control module cooperates with the guiding structure during a lowering motion of the second connecting part and pivots the second connecting part into coarse alignment of the second pipe end in a direction towards the first pipe end such that the first and second pipelines are brought to align with each other on the sea bed, and the first connecting part includes an adjacent ramp structure having abutment surfaces and guiding means designed for engagement with cooperating surfaces and means on the second connecting part when the second connecting part is displaced towards the first connecting part to fine alignment of the pipe ends.

The adjacent ramp structure is normally physically separated from the first connecting part such that the second connecting part can be parked on the ramp structure subsequent to that a disconnecting operation between the connecting parts is made, where structure that the first connecting part is a part of thus can be retrieved to the surface as required, while the or the other connecting parts remain parked in respective ramp structures on the seabed.

The guiding means of the ramp structure can include a projecting plate part, and the cooperating means of the second connecting part include an incision, where the projecting plate part and the incision comes into engagement with each other when the pipe ends approach each other and then prevent possible tilting motion of the second connecting part.

The abutment surfaces of the ramp structure may include ramp surfaces that the cooperating surfaces of the second connecting part act against and provide fine alignment between the pipe ends when the second connecting part is advanced towards the first connecting part.

The guiding structure can be an upwardly projecting frame structure which is able to receive the corresponding control module arranged on the second connecting part.

The control module of the second connecting part can include a projecting bail structure that, in an initial phase, in a sliding manner, cooperates with the upwardly projecting frame structure of the first connecting part, and when the bail structure is completely

introduced into and bottoms out against a portion of the upwardly projecting frame structure, the second connecting part pivots until abutment with the ramp structure, said pipe ends are thus coarsely aligned.

- 5 The first connecting part can include at least one control pin and the second connecting part can correspondingly include at least a cooperating female part which together constitutes additional guiding means.

The connector can constitute an integrated part of the connecting device, where the
10 connector is secured to the second connecting part and the second connecting part is displaceable in a direction towards and away from the first connecting part, where the pipe ends in this way are positioned before final connection of the pipe ends is made by said connector.

- 15 Other and further objects, features and advantages will appear from the following description of preferred embodiments of the invention, which is given for the purpose of description, and given in context with the appended drawings where:

Fig. 1 shows in perspective view a tool according to the invention,
20 Fig. 2 shows in perspective view a tool according to the invention, where the individual main components are separated from each other and constitute modules,
Fig. 3 shows in elevational view, partly in section, the tool and a connecting part retained by the tool,
Fig. 4A and 4B show a cross section through the lifting frame module of the tool and
25 associate gripping means in open and closed position respectively,
Fig. 5A shows the tool viewed from above and indicates a cross section A-A (not rectilinear) which is shown in fig. 5B,
Fig. 5B shows the cross section along the line A-A (not rectilinear) in fig. 5A,
Fig. 5C shows a detail section B from fig. 5B which is encircled,
30 Fig. 5D shows a detail section C from fig. 5B which is encircled,
Fig. 5E shows a detail section D from fig. 5B which is encircled,
Fig. 6 shows in perspective view and with the parts apart from each other, the connecting device itself without the tool present,

Fig. 7 shows in perspective view the tool when it carries along one pipeline end including a connecting part to be connected to a second connecting part, and Fig. 8A to 8H show sequences of a connecting operation.

5 Figure 1 shows the tool 20 as the tool appears alone when not in use, i.e. that no pipe end is present in the tool 20. As previously mentioned, such a tool is used to lower a pipeline end to the seabed. Pipelines for this purpose terminates in a connecting part 2 that can be clearest seen in fig. 6. This connecting part 2 is to be guided towards a first connecting part 1, which already has been put down onto the seabed, to be able to make
10 a connection between the connecting parts 1 and 2. After that the connecting operation is completed, the tool 20 is allowed to be brought to the surface again for later use.

The tool 20 includes a central lifting frame 30 which is able to retain, or support, a pipe end E_2 (not shown in fig.1 and 2, but 3). A lifting yoke 50 is connected to the lifting
15 frame 30. The lifting yoke 50 includes to rods that are pivotable connected to the lifting frame 30 via axle pins 31. The lifting yoke 50 has a limited freedom of motion to pivot about the axle pins 31. The limitation is set by two straps 53, or wires, that respectively extends between a shackle 54 at the top of the lifting yoke 50 and a shackle 45 secured in a padeye 44 of a control (guide) part 40. The control part 40 forms an extension of
20 the lifting frame 30. The function of the control part 40 and the mode of operation thereof are explained in closer detail in connection with the figures 6-8 when the tool 20 is used with a connecting part.

Figure 2 shows the same tool as in figure 1, now however, subdivided into modules, which will be convenient on many situations. This is explained at the very end of this
25 specification. The modularly constructed tool 20M is assembled of a central lifting frame module 30M, a control module 40M releasable from the lifting frame module 30M and forms an extension of the lifting frame module 30M, and a lifting yoke module 50M releasable from the lifting frame module 30M. Otherwise, the remaining
30 components are as before and have the same reference numbers as in figure 1.

Further the tool 20, 20M includes gripping mechanisms, which in a first situation can be activated to partly enclose and retain the pipeline end E_2 . In a second situation, the

gripping mechanisms can be released such that the pipeline end E_2 is released from the tool 20, 20M, typically when the tool 20, 20M is to be recovered to the surface.

5 The gripping mechanism is releasable from the pipeline end E_2 by operating actuation means 32. The actuation means 32 are entirely specific located and arranged such that they are easy accessible from above. The actuation means 32 are preferably operated by a remote controlled vessel (ROV), and is very easily operated from above.

10 In turn each gripping mechanism includes a pawl 33 which is pivotable arranged to the lifting frame 30, 30M. The pawl 33 is influenced by the actuation means 32. The lower end of the actuation means 32 acts against an inclined surface 34 of the pawl 33 in order to effect the pivotal motion of the pawl 33.

15 Moreover, at the rear end of the control module 40M, two hooks 46 are arranged, which in a quick release way are designed to cooperate with an axle pin 39a extending through holes in support brackets 39 of the lifting frame module 30M. Then the control module 40M can be hooked onto the lifting frame module 30M via the hooks 46 and the axle pins 39a, and be locked to each other by means of quick operated lock pins 41.

20 Figure 3 shows in elevation view and partly in cross section, the tool 20, 20M and a connecting part 2 retained in the tool. The connecting part 2 retains securely the pipe end E_2 , and a connector 3 is standby ready for later connection. A more complete description is given later together with figure 6.

25 However, it is to be noted that the tool 20M as an entirety, alternatively the control module 40M alone, can be released from/alternatively connected to the connecting part 2. The control module 40M includes a lug or catch lever 43 that cooperates with a cutout or notch 23 arranged on the connecting part 2. The lug 43 and the notch 23 cooperate to securely retain the connecting part 2 to the control module 40M, yet with
30 some freedom of motion. Fig. 2 shows a screw 47 that can be turned in and out. In that end facing forwards in figure 2, the screw is free of threads and is designed to be screwed as a plug into a hole 24 in an end plate 9 of the connecting part 2, see figure 6.

An alternative to the screw 47 can be a bayonet locking mechanism, which is a still more rapid locking mechanism.

Figure 4A and 4B shows in closer detail the gripping mechanisms and associated actuation means 32 and pawls 33. Fig. 4A shows the pawls 33 in open position, i.e. in a position where a pipe end E_2 can be brought up and into the lifting frame 30, alternatively be released therefrom. Fig. 4B shows the pawls in closed position, i.e. in a position where the pipe end E_2 is fixedly retained in the lifting frame 30. The inclined surface 34 that the actuation means 32 acts against is also indicated. The actuation means 32 is here shown in the form of an actuation rod 35 having a lower end in the form of a mandrel body 36 that acts against the inclined surface 34 of the pawl 33.

A bayonet locking mechanism is arranged in the upper end of the actuation rod 35. The bayonet locking mechanism includes a sleeve part 37, having coulisse guides 37a, which is fixedly secured to the lifting frame 30, 30M. It further includes a mandrel part 38 having a projecting pin 38a which follows the coulisse guide 37a. The coulisse guide 37a can be a J-slot.

The operation of the bayonet locking mechanism takes place in that the actuation means 32 is influenced by a ROV that turns the means 32 in a quarter to half a revolution at the same time as the rod 35 is pushed down. This locks the pipe end E_2 to the lifting frame 30, 30M. By release, it is to be understood that the pawl 33 is self-releasable in the sense that when the rod 35 is elevated, the pawl is pivoting down by virtue of its own weight and thus opens for release from the pipe end E_2 .

In one variant (not shown), the actuation rod can be a screw rod which is threaded and extends through a sleeve body (corresponding to the sleeve part 37) which is equipped with internal threads which allows the rod to be screwed up and down in order to act on the pawl 33.

The above described gripping mechanisms are mechanical solutions that are very sturdy and reliable in order to be fully failsafe. It is also to be explained that the locking mechanism is such designed that the high load forces extend right through the lock pawl

and vertical rod 35 out to the lifting frame itself. Thereby one avoids that the loads extend up to the interface with the ROV, which enables the ROV to operate with small forces.

5 Fig. 5A shows the tool 20, 20M from above including a cross section line A-A (not rectilinear). The sections are to show different details of the tool 20, 20M. These details shall for example show that the control module 40M is releasable from the lifting frame module 30M by means of quick release means, here shown in the form of the lock pin 41, or a cotter pin. See fig. 5A and 5D (Detail C). This in combination with the hooks
10 46 described above in connection with figure 2.

As shown in fig. 5E (Detail D), the lifting yoke module 50M is in turn releasable from the lifting frame module 30M by means of quick release means, such as cotter pins (not shown) at the end of the axle pins 31, to which the rods 51 are attached, and snap hooks
15 56 at the end of the straps 53 for attachment to the shackles 45 etc.

Fig. 5C (Detail B) shows a lock pin or cotter pin 42 for adjustment of a dampening effect that can be arranged in the control part 40. As indicated, three different positions (holes) exist into which one or more pins 42 can be put.

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Reference is now made to figure 6 that shows a complete connecting device 10 to which the tool 20, 20M is designed. The connecting device 10 is as previously mentioned assembled by a first connecting part 1, a second connecting part 2 and a ramp structure 6.

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The first connecting part 1 is secured to a subsea structure (not shown), such as a manifold structure or a Christmas tree structure. The first connecting part 1 can be considered as stationary relative to the subsea structure. The first connecting part 1 is such arranged that it supports, or retains, the end E_1 of a first pipeline, which then will
30 be located within the subsea structure. It is to be understood that the first connecting part 1 and the first pipeline will firstly be landed on the seabed (together with the subsea structure). The first connecting part 1 includes a control structure 4 located some distance apart from the pipe end E_1 .

Later on, the second connecting part 2 is to be lowered from the surface in a direction towards the subsea structure, more precisely towards the first connecting part 1. With that, the second connecting part 2 can be considered as mobile relative to the subsea
5 structure. The second connecting part 2 is such arranged that it retains the end E_2 of a second pipeline. The second connecting part 2 is moved by means of the tool 20, 20M described above.

The ramp structure 6 is located close to or adjacent to the first connecting part 1. The
10 ramp structure 6 has a major function when the connecting parts 1, 2 are to be mated, and possibly at later occasions if disconnection is to be made. The ramp structure 6 is equipped with abutment surfaces and guiding means which are designed for engagement with cooperating surfaces and means on the second connecting part 2 when the second connecting part 2 is advanced towards the first connecting part 1. When this
15 is performed fine alignment between the pipe ends E_1 , E_2 is achieved.

A connector 3 is arranged on one of the connecting parts 1, 2, here shown on the second connecting part 2. After that the pipe ends E_1 , E_2 are fine aligned with each other and pulled together until contact flange to flange, possibly with a seal therebetween, the
20 connector 3 is activated and makes final, lasting connection between the pipe ends E_1 , E_2 . The connector 3 is operated by a ROV that turns a threaded bolt 3a on the connector 3.

The connector 3 will normally be of that type clamp connector having internally
25 arranged, annular inclined surfaces, which by activation forces two pipe flanges axially towards each other. One of the pipe flanges has a sealing ring installed thereon having externally arranged, annular inclined surfaces. As a contemplated alternative, the connector can be of the type "collet connector".

30 It is to be emphasized that the ramp structure 6, in a preferred embodiment, is physically separated from the first connecting part 1. Then the second connecting part 2 can at desire, be parked on the ramp structure 6 after that a disconnecting operation between the connecting parts 1, 2 has been made. Then the subsea structure, which the first

connecting part 1 is part of, can be recovered to the surface. Normally there are many such first and second connecting parts 1, 2 for each subsea structure and, as one will understand, all the second connecting parts 2 will remain parked on the ramp structure 6 on the seabed when the subsea structures need to be recovered to the surface for maintenance, modifications, repair, etc. The described physical separation is, however, not necessarily totally definite.

Further details of the ramp structure 6 and the first and second connecting part 1, 2, will now be described. To be precise, the guiding means of the ramp structure 6 are designed and shown as a projecting plate part 6a in the area adjacent to the first connecting part 1, as shown on the figures. Still to be precise, the cooperating means of the second connecting part 2 are designed and shown as an incision 2a, or a notch. Then it is to be understood that the projecting plate part 6a on the ramp structure 6 becomes in slidable engagement with the incision 2a when the pipe ends E_1 , E_2 are moved towards each other in the terminating phase of the mating operation. When they are in complete engagement such prevents any tilting motion of the second connecting part 2 relative to the first connecting part 1.

The abutment, or contact surfaces of the ramp structure 6 can in turn include ramp surfaces as suggested by the reference number 6b. Correspondingly, the second connecting part 2 has contact surfaces 2b that cooperate with the ramp surfaces 6b when the second connecting part 2 is moved towards the first connecting part 1. When the notches 2a are in engagement with the plate parts 6a at the same time as the contact surfaces 2b are lifted by the ramp surfaces 6b during advancement of the second connecting part 2 towards the first connecting part 1, this motion provides fine alignment between the pipe ends E_1 and E_2 .

Further, it is to be noted that at the very rear end of the ramp structure 6, upwardly projecting, inclined surfaces 6c are arranged, which surfaces terminate in a straight edge 6d down to the ramp structure 6. This inclined surface 6c is functioning to control the second connecting part 2, via the contact surfaces 2b, down to a base surface 6e on the top side of the ramp structure. When the contact surfaces 2b really has arrived at and in contact with the base surfaces 6e, the second connecting part 2 is prevented from

unintentional motion rearwards due to the straight stop edge 6d. Also note that at the front end of the base surface 6e a smaller edge 6f is arranged. This edge 6f has the important function to be able to prevent the connecting part 2 from sliding in an uncontrolled way towards the connecting part 1, i.e. without any active mating by means of a pull/push tool (not shown), normally in the form of a linear motor of suitable and per se known type. By means of the stop edges 6d and 6f, the second connecting part 2 rests in peace on the base surfaces 6e due to its own weight.

Further details of the first connecting part 1 consist of a rear plate 7 and a front plate 8. The front plate 8 supports the first pipe end E_1 . A plurality of braces is arranged between the rear plate 7 and front plate 8 in per se known manner. The front plate 8 has at least one adapted mounting 8a in the form of a U-shaped recess which is designed for insertion of the pull/push tool. Moreover, the front plate 8 includes at least one control pin 8b, here shown two in number, which are located in the lower portion of the front plate 8 and are pointing in a direction towards the second connecting part 2.

Further details of the second connecting part 2 consist of a main plate 9 that supports the second pipe end E_2 . A plurality of tubular braces are perpendicularly located on the main plate 9 and the lower hollow braces 9b simultaneously constitute guiding means in the form of a female part that is to cooperate with the above described control pin 8b during the finishing part of the mating operation of the connecting parts 1, 2. The main plate 9 also has at least one adapted mount 9a in the form of a U-shaped recess or cut-out, which is designed for insertion of the above described pull/push tool.

Further, a first connecting plate 9c is rigidly connected between the hollow braces 9b in that end facing toward the first connecting part 1, and a second connecting plate 9d is rigidly connected between the hollow braces 9b in that end facing away from the first connecting part 1. The first connecting plate 9c includes the previously described incisions 2a, or notches, that cooperate with the plate edges 6a on the ramp structure 6, i.e. more precisely those plate parts 6a that are facing inwardly of the ramp structure 6. The second connecting plate 9d includes the previously described contact surfaces 2b that in sequence cooperate firstly with the inclined surfaces 6c, then the base surface 6e

and the stop edges 6d and 6f of the ramp structure 6, before the contact surfaces 2b start to ride on the ramp surfaces 6b during last phase of the mating operation.

Described in closer detail, the control structure 4 consists of an upwardly projecting frame structure 4a in two parts standing like a “Y” relative to each other and that are able to receive a corresponding control module 40M, which is arranged on the second connecting part 2 in the form of a removable tool 20. The control module 40M of the second connecting part 2 consists of a projecting bail structure 5a which, in an initial phase, in a sliding manner cooperates with the upwards projecting frame structure 4a of the first connecting part 1. When the bail structure 5a is completely introduced and bottoms against a part 4d of the upwardly projecting frame structure 4a, the second connecting part 2 is forced to pivot till abutment against the ramp structure 6. During this phase the pipe ends E_1 , E_2 are coarse aligned relative to each other. The projecting bail structure 5a of the second connecting part 2 can, as mentioned, preferably be in the form of a tool that is releasable arranged and can be recovered to the surface after that the connection is made up.

Fig. 7 shows the complete tool 20, 20M that carries along the second connecting part 2 which in turn supports the pipe end E_2 .

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Fig. 8A to 8H show sequences of the mating operation that takes place between the connecting parts 1, 2 and by use of the ramp structure 6 as assisting means. Fig. 8A shows that the second connecting part 2 is lowered from the surface, for example from a surface vessel. The second connecting part 2 is designed to land on the ramp structure 6 as described above.

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Fig. 8B shows that moment when the second connecting part 2 hits the first connecting part 1, in that the bail structure 5a hits the Y-configured, upwardly facing mouth of the frame structure 4a.

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Fig. 8C shows that moment when the bail structure 5a bottoms in the frame structure 4a and starts to pivot towards the ramp structure 6 about a pivot point which is exactly located in the bottom of the frame structure 4a.

Fig. 8D shows that moment when the second connecting part 2 is landing on the ramp structure 6 and is controlled in by means of the inclined surfaces 6c. This is also that situation when the incisions 2a are controlled in and over the plate parts 6a in order to make engagement with each other.

Fig. 8E shows first intermediate position before final connection is made. Now the contact surfaces 2b stand resting against the base surfaces 6e and are prevented by the stop edge 6d from rearward movement. The notches 2a are advanced to engagement with the plate parts 6a and prevent tilting motion as previously described.

Fig. 8F shows the same situation for the connecting device 10 as fig. 8E, but the installation tool 20 is removed and recovered to the surface for later use. When the tool 20 is removed, it is the edge 6f that prevents forward motion.

Fig. 8G shows the situation that the second connecting part 2 has been pulled toward the first connecting part 1 by means of the pull/push tool (not shown). The contact surfaces 2b has started to climb onto the ramp surfaces 6b and tilt the second pipe end E_2 upwards.

Fig. 8H shows the situation when the second connecting part 2 is completely mated with the first connecting part 1 and ready for actuation of the clamp connector 3 for final connection. The notches 2a have passed beyond the plate parts 6a and now remain in the free and are disengaged. After that final connection is made, also the contact surfaces 2b are lifted from the ramp surfaces 6b. Thus the entire second connecting part 2 is free from the ramp structure 6.

It is further to be understood that the above described solution is functioning as well on flexible pipeline as umbilical. The entire connecting operation is functioning in the same way, but with more pipes in the pipe end E_2 , in addition to a connecting box (terminal) behind the end E_2 having electric/optical connectors.

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When it comes to the modular construction, this has its particular benefit if one look into the solution according to previously mentioned Norwegian Patent Application NO2009 3107. In that application only the control module is shown, there given the reference number 5, and called a guide means 5. It is, however, to be understood that

5 the guide means also acts as a tool which is used on the first end of a pipeline which is lowered from a surface vessel. Here, neither a lifting frame nor a lifting yoke is used, but a lifting means in the form of a chain including a shackle in its upper end which is secured directly to padeyes at the rear end of the guide means (or the tool). Since this is a tool, the same basic tool can be used in both ends of the pipeline, subsequent to some

10 modifications.

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P a t e n t c l a i m s

1.

A tool for lowering, alternatively later retrieval, of a pipeline end which is provided
5 with a connecting part (2) designed for mating and connection with a first connecting
part (1) on the sea bed, and is so arranged that the tool (20) can be brought to the
surface again for reuse, **characterized in that** the tool (20) comprises a central lifting
frame (30), a guiding part (40) forming an extension of the lifting frame (30) and a
lifting yoke (50), which tool (20) includes gripping mechanisms (32, 33, 35) which, in
10 one situation, are actuatable to partly circumscribe and retain the pipeline end (E2), and,
in a second situation, the gripping mechanisms are releasable to release the pipeline end
(E2) from the lifting frame (30).

2.

15 The tool according to claim 1, **characterized in that** the gripping mechanisms (32, 33,
35) are releasable from the pipeline end (E₂) by operation (by ROV) of actuating means
(32), preferably accessible from above.

3.

20 The tool according to claim 1 or 2, **characterized in that** each gripping mechanism
includes a pawl (33) pivotable arranged to the lifting frame (30) and that the pawl (33)
is influenced by said actuating means (32) that acts against an inclined surface (34) of
the pawl (33) in order to cause said pivoting motion.

25 4.

The tool according to claim 1, 2 or 3, **characterized in that** the tool (20) is assembled
of modules including a central lifting frame module (30M), one control module (40M)
releasable from the lifting frame module (30M) forming an extension of the lifting
frame module (30M), and a lifting yoke module (50M) releasable from the lifting frame
30 module (30M), which lifting frame module (30M) includes said gripping mechanisms
(32, 33, 35).

5.

The tool according to claim 4, **characterized in that** the control module (40M) is releasable from the lifting frame module (30M) by means of quick release means, such as a hook (46), lock pin (41) or cotter pin.

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6.

The tool according to claim 4 or 5, **characterized in that** the lifting yoke module (50M) is releasable from the lifting frame module (30M) by means of quick release means, such as a lock pin or cotter pin.

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7.

The tool according to any of the claims 1-6, **characterized in that** the tool is designed to operate a connecting device, including:

15 a first connecting part (1) retaining a first end (E_1) of a first pipeline, which first connecting part (1) and first pipeline are designed to be lowered and deployed on the seabed in beforehand, and where the first connecting part (1) includes a control structure (4) located a distance apart from the pipe end (E_1),

20 a second submersible connecting part (2) retaining a second end (E_2) of a second pipeline, which second connecting part (2) and second pipeline are designed to be lowered from the surface towards the first connecting part (1), and where the second connecting part (2) includes the control module (40M) located a distance apart from the pipe end (E_2), and

25 a connector (3) arranged between the connecting parts (1, 2) for final connection between the pipe ends (E_1 ; E_2).

8.

The tool according to claim 7, **characterized in that**

30 the control module (40M) cooperates with the guiding structure (4) during lowering motion of the second connecting part (2) and pivots the second connecting part (2) into coarse alignment of the second pipe end (E_2) in a direction towards the first pipe end (E_1) such that the first and second pipelines are brought to align with each other on the sea bed, and

the first connecting part (1) includes an adjacent ramp structure (6) having abutment surfaces and guiding means designed for engagement with cooperating surfaces and means on the second connecting part (2) when the second connecting part (2) is advanced towards the first connecting part (1) to fine alignment of the pipe ends (E₁, E₂).

9.

The tool according to claim 8, **characterized in that** the adjacent ramp structure (6) is physically separated from the first connecting part (1) such that the second connecting part (2) can be parked on the ramp structure (6) subsequent to a disconnecting operation between the connecting parts (1, 2), wherein the structure that the first connecting part (1) is a part of can be retrieved to the surface as required, while the or the other connecting parts (2) remain parked in respective ramp structures (6) on the seabed.

10.

The tool according to claim 8 or 9, **characterized in that** the guiding means of the ramp structure (6) includes a projecting plate part (6a), and the cooperating means of the second connecting part (2) include an incision (2a), where the projecting plate part (6a) and said incision (2a) comes into engagement with each other when the pipe ends (E₁, E₂) approach each other and then prevent possible tilting motion of the second connecting part (2).

11.

The tool according to claim 8, 9 or 10, **characterized in that** the abutment surfaces of the ramp structure (6) includes ramp like surfaces (6b) that the cooperating surfaces (2b) of the second connecting part (2) act against, and then provides fine alignment between the pipe ends (E₁, E₂) when the second connecting part (2) is advanced towards the first connecting part (1).

12.

The tool according to any of the claim 7 to 11, **characterized in that** the guiding structure (4) is an upwardly projecting frame structure (4a) which is able to receive the corresponding control module (40M) arranged on the second connecting part (2).

13.

The tool according to claim 12, **characterized in that** the control module (40M) of the second connecting part (2) includes a projecting bail structure (5a) that, in an initial
5 phase, in a sliding manner, cooperates with the upwardly projecting frame structure (4a) of the first connecting part (1), and when the bail structure (5a) is completely introduced into and bottoms out against a portion (4b) of the upwardly projecting frame structure (4a), the second connecting part (2) pivots until abutment with the ramp structure (6), said pipe ends (E₁, E₂) are then coarsely aligned relative to each other.

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14.

The tool according to any of the claims 7 to 13, **characterized in that** the first connecting part (1) includes at least one control pin (1a) and the second connecting part (2) correspondingly includes at least a cooperating female part (2c), which together
15 constitutes further guiding means.

15.

The tool according to any of the claims 7 to 14, **characterized in that** the connector (3) constitutes an integrated part of the connecting device (10), where the
20 connector (3) is secured onto the second connecting part (2) and the second connecting part (2) is displaceable in a direction towards and away from the first connecting part (1), where the pipe ends (E₁, E₂) thus are positioned before final connection of the pipe ends by said connector (3).

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