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mathematical model and simulation program  
with verification**

Leo, Don G.; Boncal, Richard

Monterey, California. Naval Postgraduate School

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XR-3 SURFACE EFFECTS  
SHIP TEST CRAFT:  
A MATHEMATICAL MODEL AND SIMULATION  
PROGRAM WITH VERIFICATION

Don G. Leo

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# NAVAL POSTGRADUATE SCHOOL

## Monterey, California



# THESIS

XR-3 SURFACE EFFECTS

SHIP TEST CRAFT:

A MATHEMATICAL MODEL AND SIMULATION

PROGRAM WITH VERIFICATION

by

Don G. Leo and Richard Boncal

Thesis Advisor:

Alex Gerba, Jr.

December 1973

*Approved for public release; distribution unlimited.*

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XR-3 Surface Effects Ship Test Craft:

A Mathematical Model and Simulation Program with Verification

by

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Submitted in partial fulfillment of the  
requirements for the degree of

MASTER OF SCIENCE IN ELECTRICAL ENGINEERING

from the

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December 1973

17



## ABSTRACT

The digital computer simulation of the six degrees of freedom equations of motion for the XR-3 captive air bubble testcraft is presented. The origin of this computer program is the SES Loads and Motion Program developed by Oceanics Inc. for the Bell 100 ton (100B) surface effect ship. Modifications and procedures used in the revision of the subroutines to convert the L & M Program from the 100B model to the XR-3 model is documented. Measurement data from XR-3 test runs are used to verify the model for steady-state operating conditions in calm water. Computer output for turn maneuvers in calm waters and for regular sea conditions are included.



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TABLE OF SYMBOLS AND ABBREVIATIONS

AEROD	=	aerodynamics
BOWSL	=	bow seal
FORIT	=	fourier analysis
FXAED	=	aerodynamic force in x direction
FXBS	=	bow seal force in x direction
FXPWAV	=	bubble-type force in x direction due to drag between bubble and wave surface
FXRUD	=	rudder force in x direction
FXSS	=	stern seal force in x direction
FXSW	=	sidewall force in x direction
$I_{xx}$	=	mass moment of inertia about x-axis
$I_{xz}$	=	mass moment of inertial about xz-axis
$I_{yy}$	=	mass moment of inertia about y-axis
$I_{zz}$	=	mass moment of inertia about z-axis
INCON	=	initial conditon
INTGRL	=	integral
K	=	roll moment
$\lambda$	=	length of craft (24 feet)
m	=	mass
$m_b$	=	mass of the air bubble
N	=	pitch moment
$P=p$	=	rotational velocity about x-axis
$P_b$	=	pressure in the bubble
$\text{PHI}=\phi$	=	roll angle
PROP	=	propeller



NSRDC = Naval Ship Research and Development Center  
 PSF = pounds per square foot  
 PSI= $\psi$  = yaw angle  
 Q = rotational velocity about y-axis  
 Q<sub>in</sub> = air flow rate in  
 Q<sub>out</sub> = air flow rate out  
 R = rotational velocity about z-axis  
 RHS = right hand side  
 SAM = shear and moment  
 SIDWL = sidewall  
 STNSL = stern seal  
 $\rho_a$  = standard atmospheric reference  
 T = arbitrary steady-state time  
 THETA= $\theta$  = roll angle  
 U = longitudinal velocity  
 V = lateral velocity  
 W = vertical velocity  
 X = horizontal distance in direction of motion  
 Y = horizontal distance perpendicular to direction  
     of motion  
 Z = vertical distance  
 C.G. = center of gravity  
 psf = pounds per square foot  
 SES = Surface Effect Ship  
 ACV = Air Cushion Vehicle  
 CAB = Captured Air Bubble



plenum chamber = cavity beneath the wet deck of the XR-3,  
formed by the two sidewalls and the bow  
and stern seals

hump speed = speed at which testcraft overcomes large  
low velocity drag and begins to operate  
on the cushion of captured pressurized  
air





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Last, but not least, the authors wish to extend their sincere appreciation to their wives, who labored many hours over a typewriter in order that these pages might be presented.



## I. INTRODUCTION

### A. BACKGROUND

Conventional monohull displacement type ships are drag force limited to speeds of approximately 50 knots. A very cursory study of the frictional drag component and its direct dependence on the square of velocity will bear this out. It can be shown that the power plant requirements to overcome the drag force at the higher speeds requires such large plants that the ship weight increases significantly resulting in a speed barrier due to drag forces. The desire for speeds above the drag barrier speed has led to some new approaches in ship design. The Surface Effects Ship is one of these approaches.

Surface Effects Ship is a broad category which includes the ACV, Air Cushion Vehicle, GEM, Ground Effects Machine and the CAB, Captured Air Bubble. Navy Magazine of May 1967 has a very informative article on different ACV and GEM concepts. However, we shall confine our discussion to the CAB type of craft.

Captured Air Bubble Concept - The captured air bubble craft consists of rigid side walls with flexible soft seals between the water surface and the ship at bow and stern. This provides a chamber into which air is blown and captured. The resulting pressure in the plenum provides a vertical force sufficient to allow shallow draft operation.

The shallow draft produces a lower drag and a higher speed for the same thrust than would be had for a corresponding



displacement hull. The reason for this effect is that the CAB ship drag is composed of two distinctly different type of forces. The drag resulting from skin friction on the immersed surface is directly proportional to velocity squared. The drag resulting from the friction of the bubble at the air-water interface is inversely proportional to velocity to the 1.566 power. Thus the sum of these two drag forces has a point at which an increase in speed actually results in a reduction in drag.

With the development of faster submarines and the spectacular increases in speed of aircraft the Navy is rightfully searching for a method of increasing the surface ship speed. A special project office, Surface Effects Ship Project Office (SESPO), has been created to specifically look into this problem and to evaluate proposals.

At the present time two 100-ton Captured Air Bubble vessels have been constructed. They are the Aerojet General 100-A and the Bell Aerospace Systems 100-B. These two craft are prototypes of a projected 2000 ton craft. Prior to construction of the 100-ton crafts, experimental models were constructed in the 3-ton range. One such craft, the XR-3 built by NSRDC, is presently being used in experiments at the Naval Postgraduate School. Additionally, Oceanics Incorporated was commissioned to develop a digital computer simulation of the CAB ship loads and motions. The program delivered to NPGS in October 1972, was a model of the 100-B.





## B. OBJECTIVES

Development of the equations of motion for the CAB ship were made in terms of the various elements contributing separate forces to the different degrees of freedom. The objectives of the simulation given in reference 9 are here restated.

1. To provide a computerized form of six degree of freedom equations for SES craft that will yield time domain outputs of motions for the on-bubble mode of operation.

2. To determine the motions of specified, SES configurations with special references to human habitability, platform requirements (for military or commercial applications) and maneuvering requirements for the on-bubble mode of operation.

3. To establish a mathematical model for predicting maximum wave-induced bending moments, both longitudinal and transverse, on SES craft to provide techniques that would yield slamming responses for on-bubble mode of operation.

4. To determine the stability derivatives in the vertical plane from measured data of the vertical plane motions of existing SES craft in a random seaway.

The objective of this thesis is to closely examine and attempt to improve the mathematical model. Our method is one of revising and changing the 100-B model L&M program so that it accurately describes the motion of the XR-3 model test craft. Program conversion consists of subroutine modifications. In certain subroutines it was necessary only to



input to the program new data, based upon measured data from the test craft. In other subroutines the method of calculation, coefficients, or entire equations had to be revised. The thesis discusses thoroughly these changes and their corresponding rationale. In addition, a comparison of measured test craft data with the L&M program output for steady-state, calm water operating condition is used to establish the accuracy of the simulation.

A users manual for this Fortran IV program is in Appendix A which includes descriptions of the subroutines and the method of inputting data. The program is designed to be operated in six degrees of freedom. Since many of the crafts parameters are input through the use of data cards a thorough reading of the subroutine descriptions and their corresponding inputs should be made before attempting to exercise this program as it presently exists.



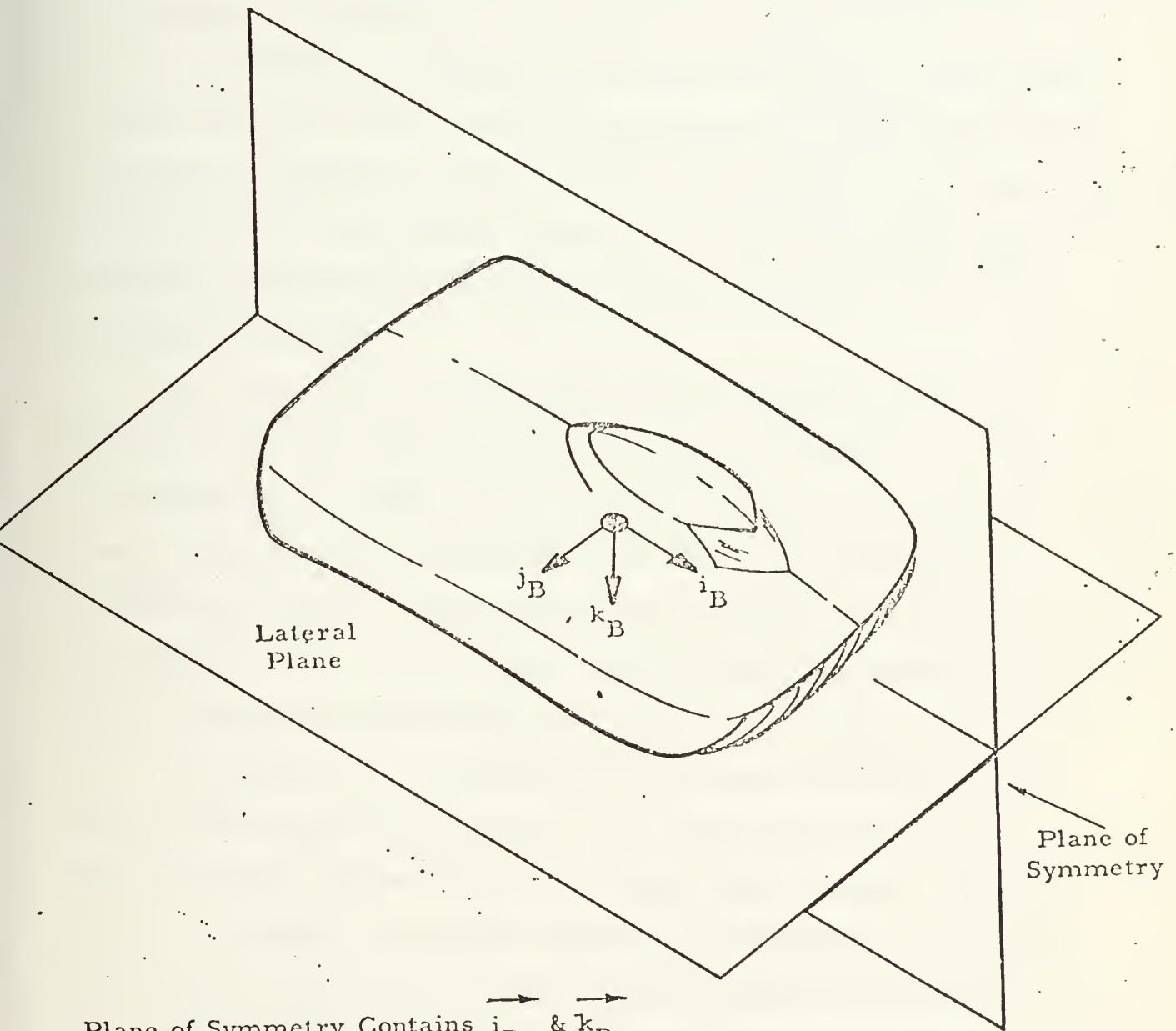
## II. EQUATIONS OF MOTION

### INTRODUCTION

Motion of any vehicle which is free to move in a three dimensional space is made up of six degrees of freedom. That is, the vehicle (in this case the XR-3) may have translational motion in any one or more of three coordinate directions and it may also have rotational motion about any of these coordinate directions. In order to study these motions and the control problems of the XR-3, a mathematical model consisting of these six equations is required. These equations can then be used as the basis of a computer model suitable for simulation studies. In general, these above equations will be complex and nonlinear. The initial development and computerization of the six degree of freedom motion equations was based on the use of model test data, limited XR-3 test data, and theory for estimating the coefficients or constituent terms that appear in the equations. The inherent motion characteristics of the XR-3 are determined by exercising this computer model. These results are compared with available test data and finally used to predict other motion characteristics not readily obtainable through XR-3 craft testing.

Early analyses of motions within the vertical and lateral planes were considered separately and revealed that linear equations provided an acceptable description of motions within the vertical plane (the symmetrical plane for the XR-3 as shown in Figure 1.). However, the linear lateral





Plane of Symmetry Contains  $i_B$  &  $k_B$

Lateral Plane Contains  $i_B$  &  $j_B$

Figure 1 SES Plane of Symmetry





plane equations proved to be inadequate and it was clear that nonlinear effects were significant in the description of asymmetric motions.

To produce a resultant functional form for the equations that will be the most simple form possible in order to achieve an ease of computer representation and solution while still including the main factors that affect craft motion, a simplified nonlinear representation was developed.

#### COORDINATE SYSTEM

The equations of motion describe the craft's movement in terms of an inertial reference frame in order to determine its position in space. Since the XR-3 is expected to have small angles of pitch and roll, the main angle indicating orientation of the ship relative to the inertial frame is the yaw angle. The range of this angle is large in order to properly describe craft turning motion in the horizontal plane.

A second set of coordinate axes, used to describe craft roll, pitch and heave, is the local level reference frame. The horizontal plane of this reference frame remains parallel to the horizontal inertial reference plane however its origin is placed at the craft's center of gravity above the mean free surface and its x-axis is in the craft's heading direction. The transformation between the local level and the inertial reference planes is given by

$$\begin{vmatrix} \hat{i}_L \\ \hat{j}_L \\ \hat{k}_L \end{vmatrix} = \begin{vmatrix} \cos \Psi, & \sin \Psi, & 0 \\ -\sin \Psi, & \cos \Psi, & 0 \\ 0, & 0, & 1 \end{vmatrix} \begin{vmatrix} \hat{i}_I \\ \hat{j}_I \\ \hat{k}_I \end{vmatrix}$$



The craft's heave, pitch, and roll motions are related to the local level reference plane through a third set of coordinate axes called the Body Frame. The Body Frame, also called the ship axis system, has its origin at the ship's center of gravity and its positive x-axis is also aligned in the direction of the ship's bow, the y-axis is positive to starboard, and the z-axis is positive downward. The transformation between the body axes and the local level axes is given by

$$\begin{bmatrix} \hat{i}_B \\ \hat{j}_B \\ \hat{k}_B \end{bmatrix} = \begin{bmatrix} A_{xx} & A_{xy} & A_{xz} \\ A_{yx} & A_{yy} & A_{yz} \\ A_{zx} & A_{zy} & A_{zz} \end{bmatrix} \begin{bmatrix} \hat{i}_L \\ \hat{j}_L \\ \hat{k}_L \end{bmatrix}$$

where:

$$\begin{aligned} A_{xx} &= \cos\theta \\ A_{xy} &= 0 \\ A_{xz} &= -\sin\theta \\ A_{yx} &= \sin\phi\sin\theta \\ A_{yy} &= \cos\phi \\ A_{yz} &= \sin\phi\cos\theta \\ A_{zx} &= \cos\phi\sin\theta \\ A_{zy} &= -\sin\phi \\ A_{zz} &= \cos\phi\cos\theta \end{aligned}$$

Finally, to describe the orientation of the fixed body frame with respect to the inertial frame a set of single axis rotations are performed. These rotations, through what are known as Euler Angles, bring the inertial frame into



alignment with the body frame. Taking the sequence to be positive rotations about the  $\hat{k}$ ,  $\hat{j}$  and  $\hat{i}$  axes, in that order, the corresponding rotations are  $\Psi$  (yaw),  $\theta$  (pitch), and  $\phi$  (roll), and the transformation between reference frames is given in terms of these Euler angles by:

$$\begin{vmatrix} \hat{i}_B \\ \hat{j}_B \\ \hat{k}_B \end{vmatrix} = \begin{vmatrix} B_{xx} & B_{xy} & B_{xz} \\ B_{yx} & B_{yy} & B_{yz} \\ B_{zx} & B_{zy} & B_{zz} \end{vmatrix} \begin{vmatrix} \hat{i}_I \\ \hat{j}_I \\ \hat{k}_I \end{vmatrix}$$

where:

$$\begin{aligned} B_{xx} &= \cos\theta\cos\Psi \\ B_{xy} &= \cos\theta\sin\Psi \\ B_{xz} &= \sin\theta \\ B_{yx} &= \sin\phi\sin\theta\cos\Psi - \cos\phi\sin\Psi \\ B_{yy} &= \sin\phi\sin\theta\sin\Psi + \cos\phi\cos\Psi \\ B_{yz} &= \sin\phi\cos\theta \\ B_{zx} &= \cos\phi\sin\theta\cos\Psi + \sin\phi\sin\Psi \\ B_{zy} &= \cos\phi\sin\theta\sin\Psi - \sin\phi\cos\Psi \\ B_{zz} &= \cos\phi\cos\theta \end{aligned}$$

Figure 2 illustrates the relative orientation of the above mentioned reference frames.

During normal operation of an SES vehicle, roll angle  $\phi$  and pitch angle  $\theta$  remain within a range where no great error is introduced by using linear approximations for the trigonometric functions. The resultant transformation between the inertial frame and the body frame now becomes:



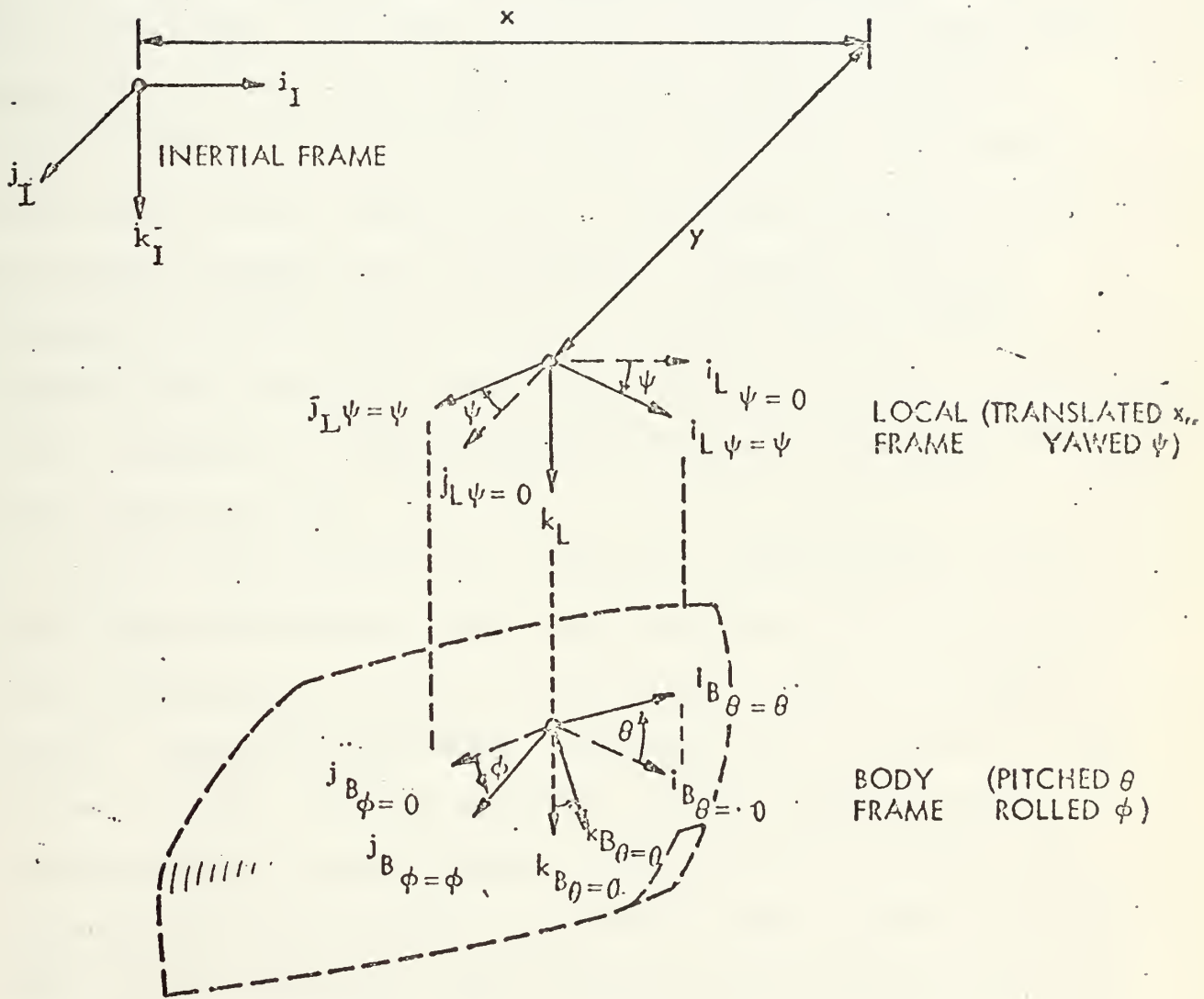


Figure 2 Relative Orientation of Reference Frames





$$\begin{vmatrix} \hat{i}_B \\ \hat{j}_B \\ \hat{k}_B \end{vmatrix} = \begin{vmatrix} \cos \Psi, & \sin \Psi, & -\theta \\ -\sin \Psi, & \cos \Psi, & \emptyset \\ \theta \cos \Psi + \emptyset \sin \Psi, & \theta \sin \Psi - \emptyset \cos \Psi, & 1 \end{vmatrix} \begin{vmatrix} \hat{i}_I \\ \hat{j}_I \\ \hat{k}_I \end{vmatrix}$$

## DYNAMICS AND KINEMATICS

There are three general categories of forces acting on the XR-3 type craft. The first category of forces are those acting upon the hard structural elements of the ship (rigid body forces) such as the sidewalls, rudder, and deck. The second group of forces are those acting on the seals and transmitted to the ship through their attachments. Finally, the last category are those forces which act on the ship and water surface due to the air bubble and the lift fan system. Figure 3 is a simplified illustration of three force categories acting on an SES type craft.

Craft motion occurs as a result of a combination of all three force categories. When the vector sum of all these forces are in balance, the craft will continue in a state of uniform motion. Motions in the plane of symmetry are: forward and aft motion or surge; vertical motion or heave; and pitch motion or rotation in the vertical plane. Motions in the lateral plane are; sway motion or lateral translation; yaw motion a rotation about the vertical axis; and roll motion or rotation about the forward and aft axis.

The craft will accelerate in the forward direction as a result of propulsive thrust at some equilibrium velocity. The pitch motions of the craft are determined by the interactions between thrust, drag, lift and gravitational forces. Heave



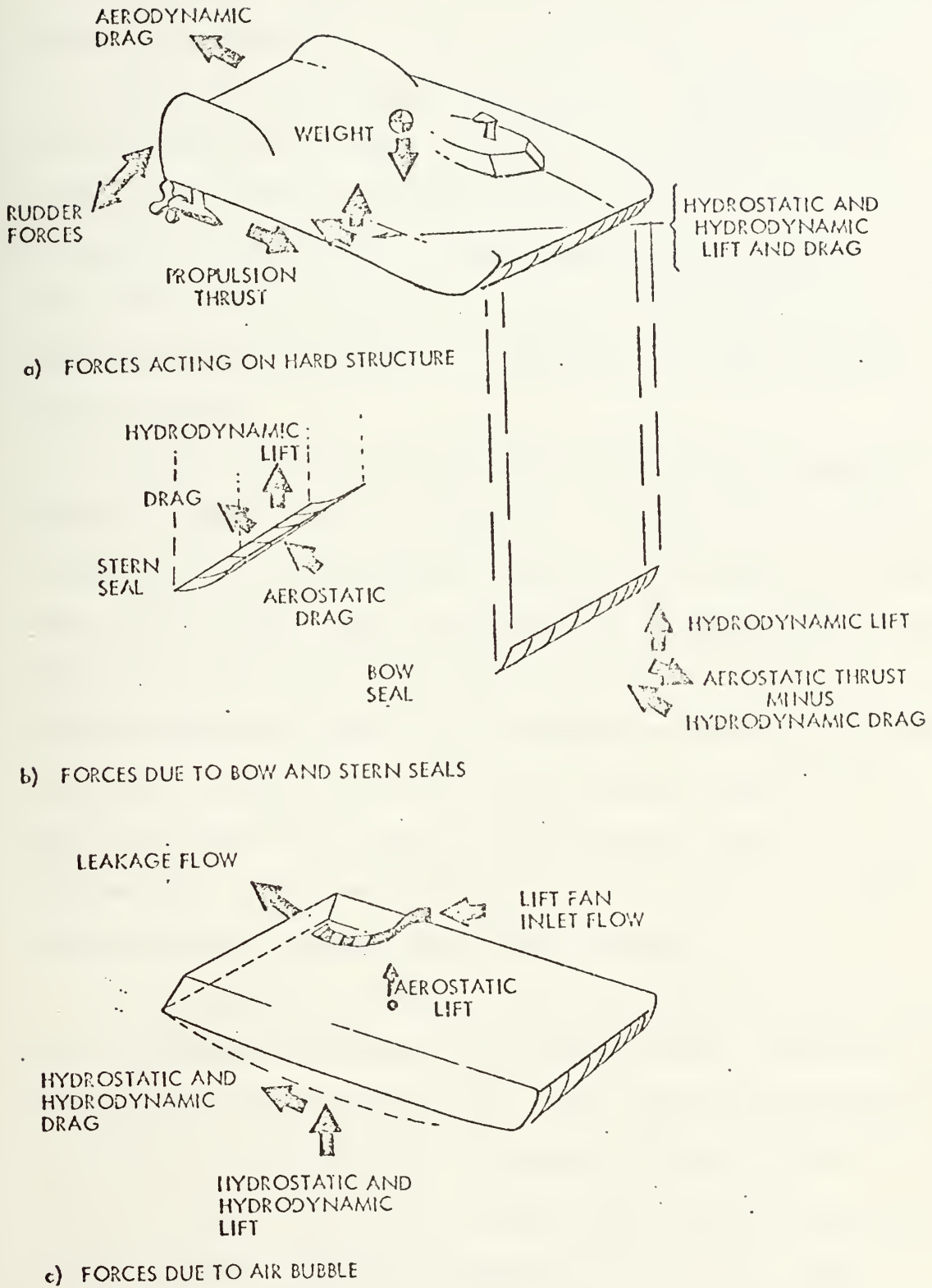


Figure 3. Static Forces Acting on a Surface Effect Ship



motions result from variations in bubble pressure, buoyant forces on seals, sidewalls, and waves reacting against the weight of the craft.

Motions in the lateral plane result from sideforces acting through the center of gravity to produce lateral translation or sway, sideforce offset longitudinally from the center of gravity to produce angular yawing motion, and lift force offset laterally as well as sideforce offset vertically from the center of gravity to produce angular rolling motion.

In order to describe the above motions in a simple and accurate manner which is conducive to computer programming, a correct choice of kinematic variables and coordinate systems must be made. When the equations of motion have been solved for that set of variables, all other variables can then be evaluated using the relationships between kinematic variables; and when the orientation of the body frame has been established, all other vectors however expressed can be resolved into any common frame using the previously given transformations between coordinate systems.

The equations of motion have been based on the following chosen kinematic variables: the Euler angle, and their time derivatives:  $\psi, \theta, \phi; \dot{\psi}, \dot{\theta}, \dot{\phi}; \ddot{\psi}, \ddot{\theta}, \ddot{\phi}$ ; and the components of the velocity of the origin of the body frame, resolved in the direction of the local level frame axes; and the time derivatives of these velocity components,  $u_L, v_L, w_L$ , and  $\dot{u}_L, \dot{v}_L, \dot{w}_L$ , where  $u_L$  is the component in the  $\hat{i}_L$  direction,



$v_L$  is in the  $\hat{j}_L$  direction, and  $w_L$  is in the  $\hat{k}_L$  direction.

The equations of motion are to be solved for

$$\ddot{\psi}, \ddot{\theta}, \ddot{\phi}, \dot{u}_L, \dot{v}_L, \dot{w}_L.$$

Two advantages to this choice of variables and reference frames are; first, the simplicity in the integrations required to determine the orientation of the body frame and the location of its origin, and second, is that it facilitates a reduction of degrees of freedom. That is, the equation for  $\ddot{z}$  can be easily reduced to obtain a representation of the heave-only mode which is a readily interpretable motion.

One inescapable disadvantage to the above choice is that the transformations required to resolve components into local level frame axes and to express relationships in terms of selected kinematic variables are nonlinear. In most cases this process has been simplified by using only the first order terms in the Euler angles. It is to be noted that, in comparison to the bubble lift force, the other forces acting on the craft are generally small; hence, first order transformations from body frame to local level frame axes actually provide representative second order accuracy.

As previously stated a net unbalance of forces or moments along or about any axis will cause the craft to accelerate along or about that axis. This acceleration is called a kinetic reaction. This principle known as D'Alemdert's principle can be more formally stated that when the kinetic





reaction contributions are included, the sum of all forces and moments vanish. Stated mathematically we have:

$$\begin{aligned}
 0 &= X - \sum_i F_i \hat{i} \\
 0 &= Y - \sum_i F_i \hat{j} \\
 0 &= Z - \sum_i F_i \hat{k} \\
 0 &= K - \sum_i M_i \hat{i} \\
 0 &= M - \sum_i M_i \hat{j} \\
 0 &= N - \sum_i M_i \hat{k}
 \end{aligned}$$

where X, Y and Z are the kinetic reactions and  $F_i \hat{i}$ ,  $F_i \hat{j}$ , and  $F_i \hat{k}$  and  $M_i \hat{i}$ ,  $M_i \hat{j}$ , and  $M_i \hat{k}$  are the various forces and moments due to thrust, drag, gravity, bubble pressure, and buoyancy in the X, Y and Z directions of the local level reference frames.

To evaluate the kinetic reactions it is assumed that the moments of inertia of the craft are constant with respect to the local level coordinate system. Now, the direct application of Newton's laws of motion for a rigid body relative to this coordinate system leads to the following equations of motion or kinetic reactions:

$$\begin{aligned}
 m (\dot{u} - v\dot{\psi}) &= X \\
 m (\dot{v} + u\dot{\psi}) &= Y \\
 m \dot{w} &= Z \\
 I_{xx} \ddot{\theta} - I_{xz} \ddot{\psi} - I_{yy} \dot{\psi} \dot{\theta} &= K \\
 I_{yy} \ddot{\theta} - I_{xz} (\dot{\psi})^2 + I_{xx} \dot{\psi} &= M \\
 I_{zz} \ddot{\psi} - I_{xz} \ddot{\theta} &= N
 \end{aligned}$$



Computations using analog computers have revealed that the nonlinear inertial coupling terms included in the above equations contributed only negligible differences to the responses of expected forcing functions (see reference 9). Hence, the decision was made to simplify the equations of motions to be used by deleting all nonlinear inertial coupling terms. The resulting equations are then given by:

$$\begin{aligned}
 m\dot{u} &= X \\
 m\dot{v} &= Y - \mu u\dot{\psi} \\
 m\dot{w} &= Z \\
 I_{xx}\ddot{\theta} - I_{xz}\dot{\psi} &= K \\
 I_{yy}\ddot{\theta} &= M \\
 I_{zz}\dot{\psi} - I_{xz}\ddot{\theta} &= N
 \end{aligned}$$

Note: The  $u\dot{\psi}$  product is retained since it is not a small quantity.

The above simplified equations can be represented in matrix form by:

$$\begin{vmatrix}
 m & 0 & 0 & 0 & 0 & 0 \\
 0 & m & 0 & 0 & 0 & 0 \\
 0 & 0 & m & 0 & 0 & 0 \\
 0 & 0 & 0 & I_{xx} & 0 & -I_{xz} \\
 0 & 0 & 0 & 0 & I_{yy} & 0 \\
 0 & 0 & 0 & -I_{xz} & 0 & I_{zz}
 \end{vmatrix}
 \begin{vmatrix}
 \dot{u} \\
 \dot{v} \\
 \dot{w} \\
 \ddot{\theta} \\
 \ddot{\theta} \\
 \dot{\psi}
 \end{vmatrix}
 =
 \begin{vmatrix}
 X \\
 Y - \mu u\dot{\psi} \\
 Z \\
 K \\
 M \\
 N
 \end{vmatrix}$$

This matrix representation is used to establish a procedure by which the digital computer solves the equations of motion.



Detailed descriptions of the component forces and moments which contribute to the motion of the XR-3 craft are provided in the subroutine descriptions that follow this section.



### III. PROGRAM SUBROUTINE MODIFICATIONS

#### A. MAIN

The only changes to the main portion of the program was the introduction of the term VEL and the corresponding format change so that velocity is written in knots instead of feet per second.

#### B. SUBROUTINE BOW SEAL

The XR-3 is presently equipped with soft air-spring type bow and stern seals. These seals were designed and constructed by NSRDC and installed by NPGS. The seals illustrated in Figure 4 are double-celled air bags consisting of a 46" X 120" frame and fabric ends, sides, and bottom. Twelve equally spaced steel spring stiffeners reinforce the bottom of the seals. The divider membrane has holes in it which serve as a damping device. Winches and cables have been attached to the rings shown in Figure 4, so that the shape of the inflated seal may be changed.

To inflate the seals ducted fans are used. The characteristics of these fans are shown in Figure 5 and the ducting arrangement in Figure 6. As can be seen from Figures 5 and 6, two ducted fans supply air to the bow seal. The rate of flow is 125 cubic feet per second per fan; hence, the total flow to the bow seal is 250 cubic feet per second. The return ducting, shown in Figure 6, allows the vane axial fans to deliver flow and not cause the seal to inflate like a balloon. There is sufficient fan flow to produce a pressure





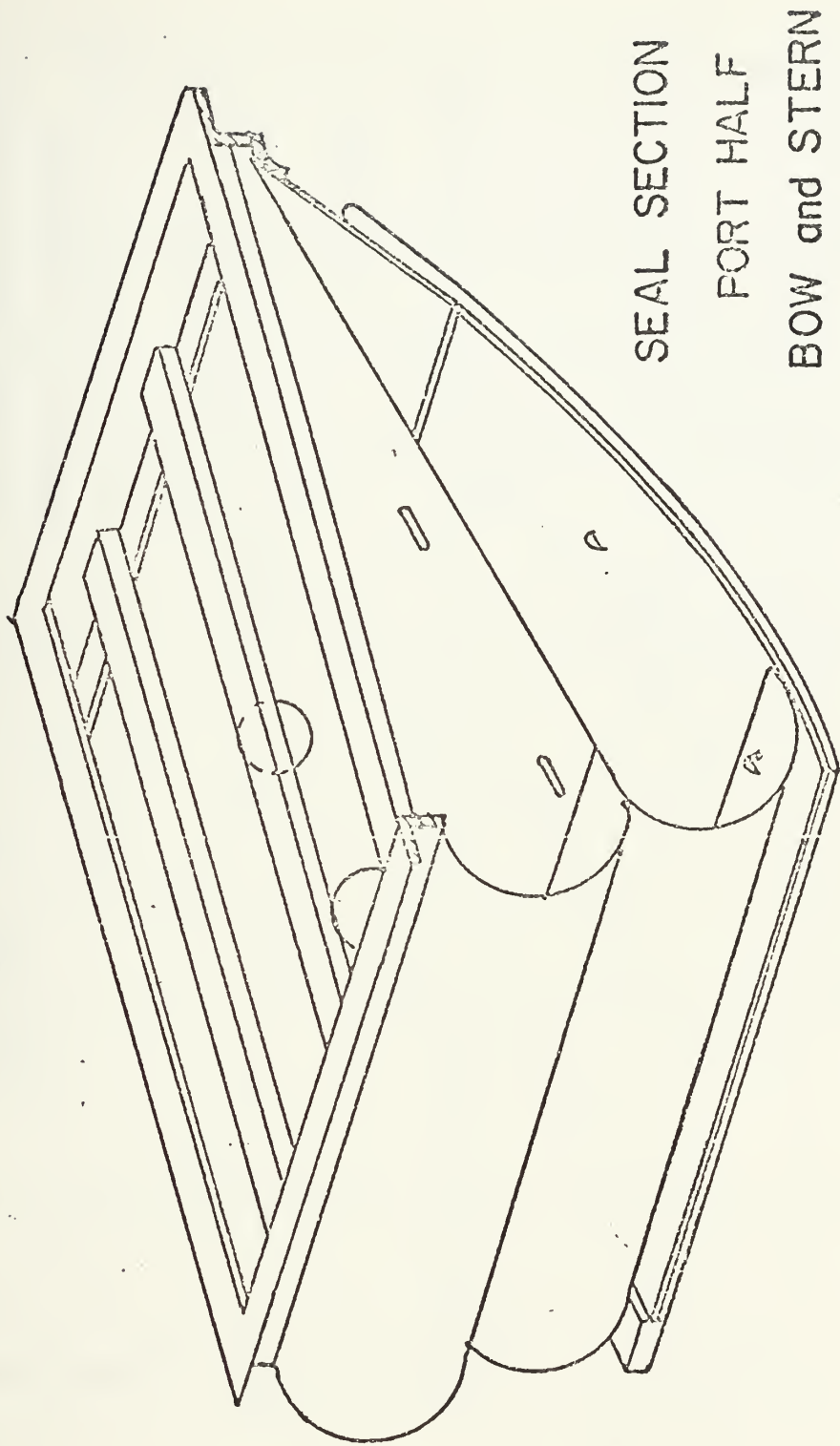
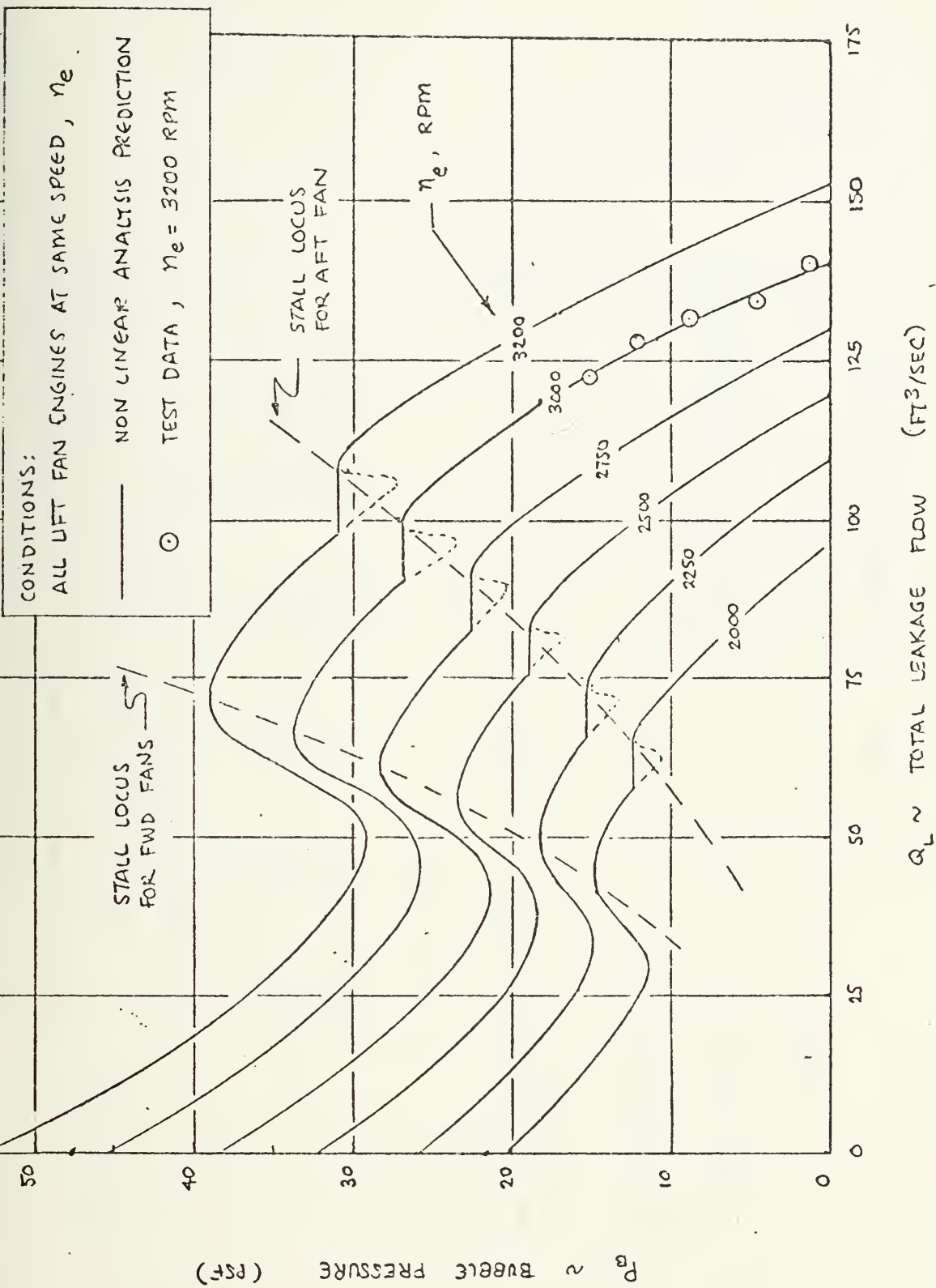


Figure 4

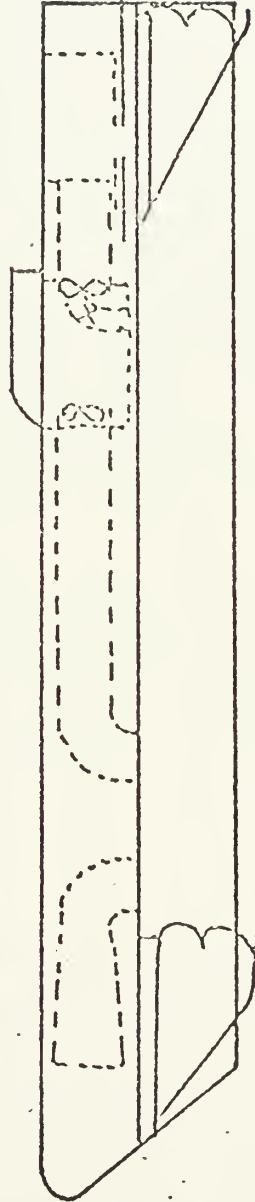
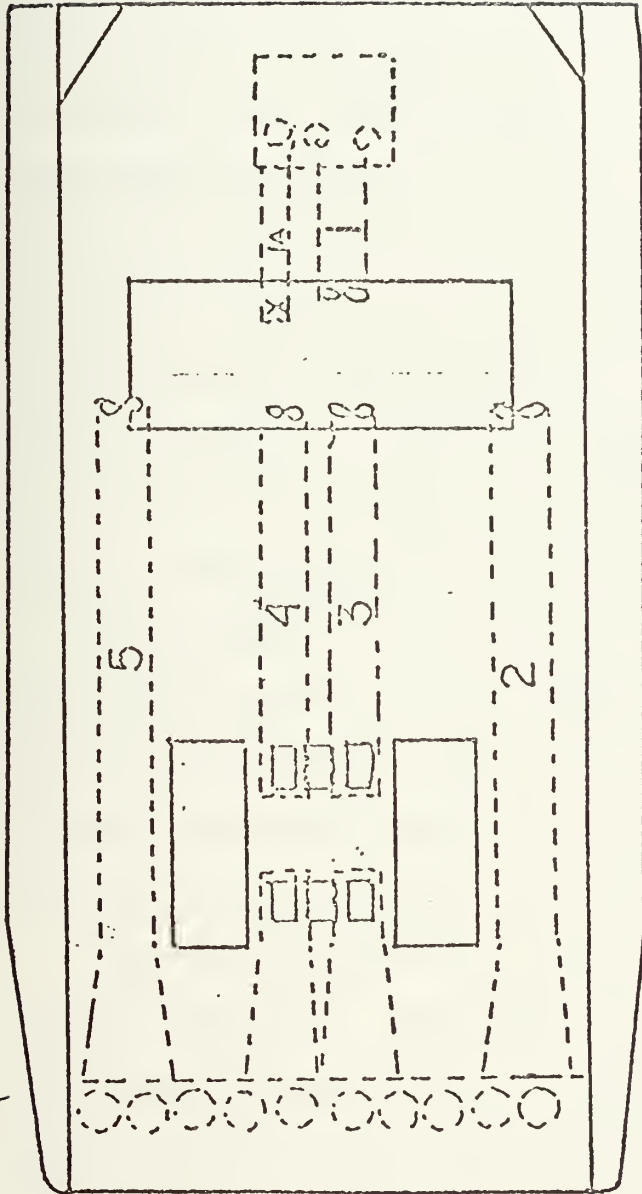




FAN FLOW CHARACTERISTICS

Figure 5





DUCTING CONFIGURATION

Figure 6



differential between the seals and the plenum chamber of about 1 to 2 psf. depending on the plenum pressure.

The stern seal of the 100B is of similar construction to the bow seal presently installed in the XR-3 and therefore the 100B Stern Seal Subroutine was used as the basis for computer representation. By comparison of Figures 4 and 7, the XR-3 seal configuration and the 100B stern seal configuration respectively, we can note strong similarities. Both are of pressurized fabric-type material that is assumed to have no inertia or dynamics and are constructed with a vented membrane separating the lobed air bags. The throttle shown in Figure 7 is merely a controllable path for the air to return to the plenum. This throttle corresponds to the return ducting previously mentioned.

The process of modification of the program involved the identification of the elements of the 100B stern seal calculations so that proper substitutions could be made without destroying the continuity as well as the way in which the program coupled with itself.

The first computation considered was the calculation of the bow seal gap. GAP is here defined as that space resulting from lifting the seal beyond the surface of the water, that is, an air gap resulting in a loss of air from the plenum and increased air flow. The equation is here reproduced without its iterative subscripts.





# SES 100 STERN SEAL

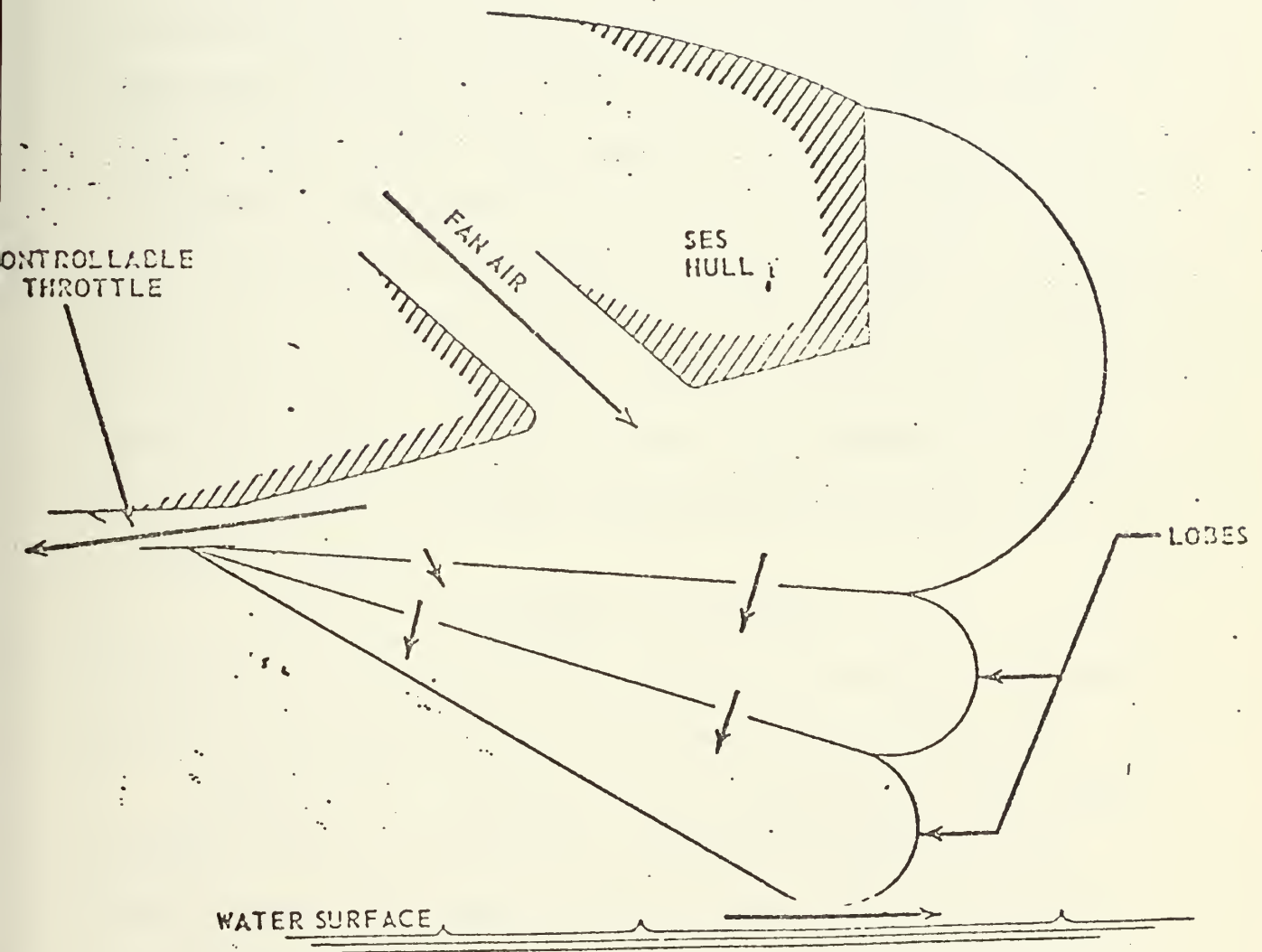


Figure. 7



$$GAP = -(Z+ZS-XX(3,K)*THETA+YY(3,K)*PHI+ETA(3,K))$$

$$XX(3,K) = XBS+RBS*COS(ANG)$$

$$YY(3,K) = RBS*SIN(ANG)$$

This calculation results in the distance DS as shown in Figure 9.

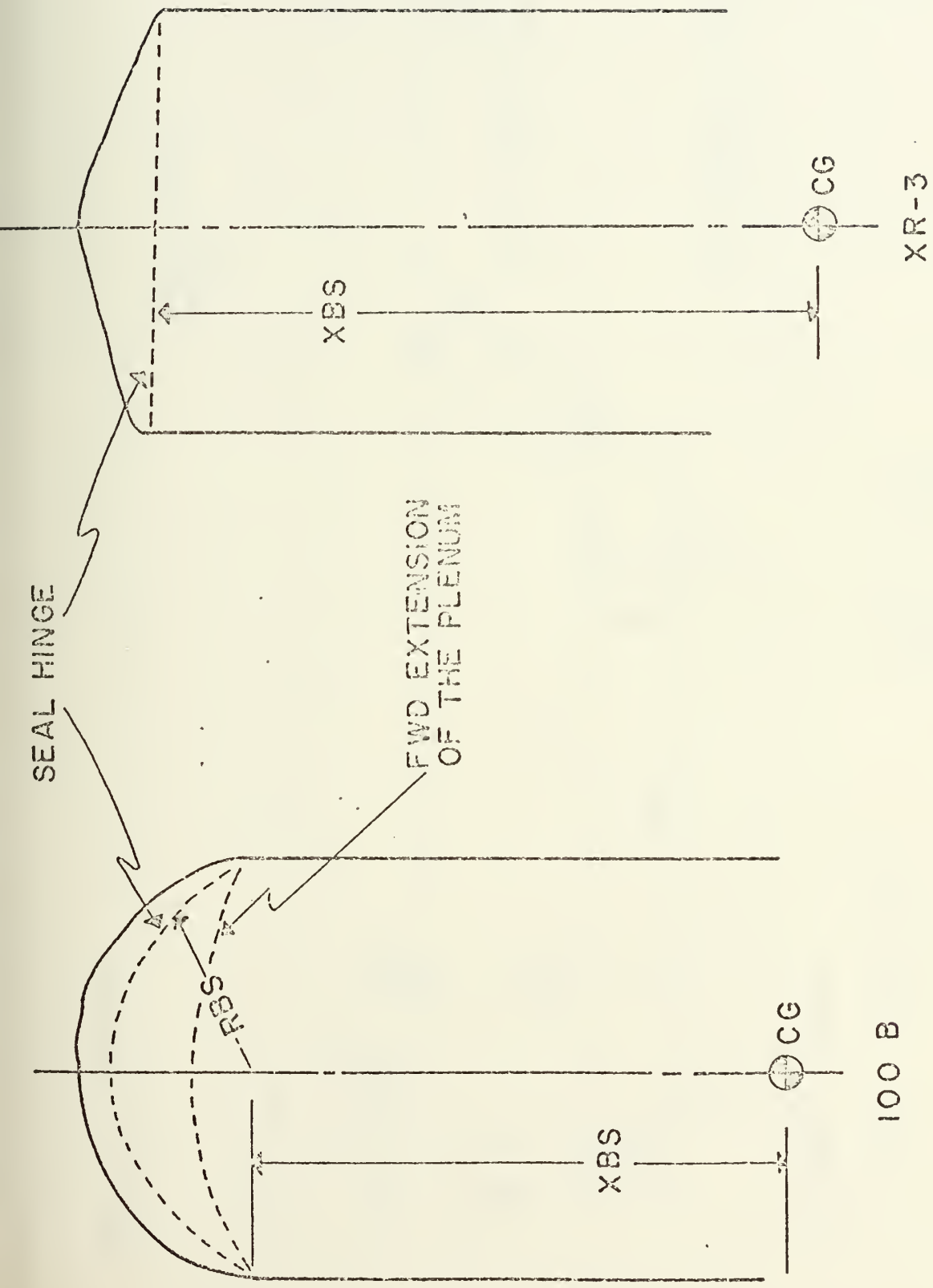
The purpose of the XX(3,K) and YY(3,K) calculations are to locate points along the perimeter of the hinge. The distances XBS, XX(3,K) and YY(3,K) can all be found in Subroutine INCON. RBS is not required for the XR-3 seal and is removed. The reason for the calculation of RBS was that the 100B hinge is semicircular in shape as shown in Figure 8. The XR-3, on the other hand, has a seal that has its hinge on the bow of the ship and is affixed straight across, athwartships, therefore  $XX(3,J) = XBS$ . The distance, YY(3,J) is an incremental distance athwartships and is also calculated in INCON.

$$YY(3,J) = 0.5*XBBW+(J-1)*DELYBS$$

In this way we have located a series of straight line segments running athwartships at the seal hinge location.

Initially the overhang of the bag portion of the 100B bowseal had been calculated as ELBAG by Subroutine FGL. Since the XR-3 bow seal has no overhang, this calculation has been removed. The bow and stern seal of the XR-3 are basically alike and therefore the only differences are in the definition of terms used in the equations. The corresponding changes have been made in INCON, RUDDER, RHS, and wherever else the Common Block ties were made. New



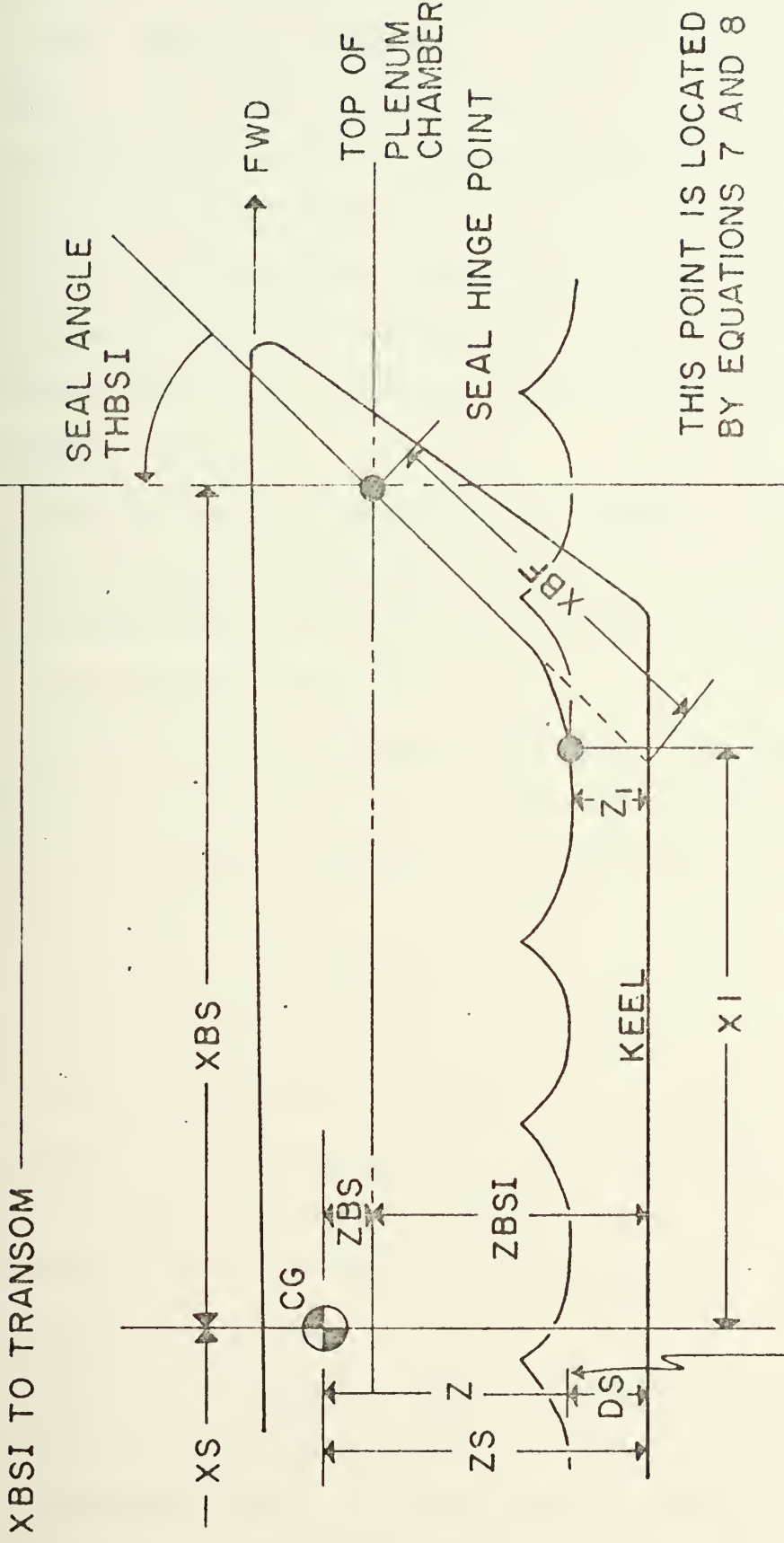


BOW SEAL HINGE ARRANGEMENTS

Figure 8



CURTAIN VERTICAL



THIS POINT IS LOCATED BY EQUATIONS 7 AND 8

PITCH = 0.0  
ROLL = 0.0

STBD SIDE VIEW

### BOW SEAL CONFIGURATION

Figure 9





terms that were included match their corresponding terms in the 100B Stern Seal Subroutine. With reference to Figure 9, these are XBF which is the length of the seal from hinge to transom, THBSI which is the angle between the craft vertical and the seal, BLEAK which is the seal base leakage area, ZBS which is the distance from the CG to the seal hinge, COSBS and SINBS, which correspond to SINTH and COSTH in the 100B program. These later two terms are the SIN and COS of the THBSI bow seal.

The following is an equation by equation discussion of the XR-3 Bow Seal Subroutine. The first few statements serve to zero the force, GAP vector, SKI vector and leakage area.

$$(1) \text{ DELPBG} = \text{PBS} - \text{PB}$$

Equation (1) calculates the differential in pressure between the bubble (plenum) PB, and the bow seal bags, PBS. PB is calculated in Subroutine RHS and PBS is an INCON Subroutine input.

$$(2) \text{ PBAR} = \text{PB} - \text{PINF}$$

$$(3) \text{ DELP} = \text{PBAR}$$

$$(4) \text{ IF (DELP.LT.0.0.) DELP} = 0.0$$

Equations (2) through (4) calculate the pressure difference between the bubble, PB, and the sea level value PINF, insuring that DELP is never negative since we cannot create a vacuum in the plenum.

$$(5) \text{ SINDIF} = \text{SINBS} - \text{COSBS} * \text{THETA}$$

$$(6) \text{ COSDIF} = \text{COSBS} - \text{SINBS} * \text{THETA}$$

COSBS and SINBS are calculated in Subroutine INCON.



THETA is the pitch angle and is considered small enough to use the small angle approximation for the sin. Therefore, equations (5) and (6) represent adjustments to the INCON values, COSBS and SINBS, due to pitch angle.

$$(7) X1 = XBS + ZBS * THETA - XBF * SINDIF$$

$$(8) Z1 = -Z - ZBS + XBS * THETA - XBF * COSDIF$$

Equations (7) and (8) locate a line on the water's surface of the seal based upon the draft and pitch angle. Referencing Figure 9 which assumes no pitch or roll it can be seen that the distance determined by equation (7) is indeed X1. Similarly we see that equation (8) locates the distance Z1. It is assumed that the forces acting upon the seal and the craft act along this line which is centered in the wetted area at the water's surface. The assumption is that the seal, being a buoyant body does not penetrate sufficiently the water's surface, but floats upon it.

The next task is to calculate the wetted area of the seal and the gap, if any. The seal may be divided into as many as eleven segments according to NSTA(3).

$$(9) \text{ELSKI}(K) = (\text{ETA}(3,K) - \text{DETABX}(K)) * (\text{XX}(3,K) - X1) - Z1 + W(3,K) * \text{PHI}$$

$$(10) \text{GAP}(K) = \text{ELSKI}(K)$$

$$(11) \text{IF} (\text{GAP}(K) .\text{LT.} 0.0) \text{GAP}(K) = 0.0$$

ELSKI represents the wetted length of the small segment corrected for waves,  $(\text{ETA}(3,K) - \text{DETABX}(K))$ : and roll, PHI. Equation (11) provides that as long as ELSKI is negative no gap exists. Equation (12) computes an average of ELSKI over the segments previously determined.



$$(12) \text{ ELSKIA} = (\text{ELSKI}(J+1) + \text{ELSKIA}(J)) / 2.0$$

Obviously if the average wetted length computes to be less than zero there is no need to make any of the following computations and gap is the only meaningful term. However, as is usually the case, ELSKIA has a value and it is then necessary to next test ELSKIA and determine if it exceeds the maximum wetted length permissible. If so, it is then set to the maximum value. This is reasonable since the maximum wetted area would exist when the top of the plenum was contacted by the water and the computations would stop. The succeeding equations calculate a coefficient of drag based upon the craft velocity and then the resulting drag forces. Similarly the remaining forces and moments are calculated.

The leakage flow,  $\dot{Q}_L$ , was not permitted in the 100B unless the seal broached the surface and GAP became non-zero. In the case of the XR-3 it was found that there existed a leakage area between the sidewalls and the bow seal itself. This gap was calculated and input as CFBS in Block 6 of Subroutine INCON. This small area accounts for a flow of approximately 10 cubic feet per second.

Inputs to Subroutine BOWSL will be discussed in the section covering Subroutine INCON.

### C. SUBROUTINE COLFIL

The Colfil Subroutine controls output, both form and content. Since substantial changes to the Oceanics L&M



program have been made, a user's manual for this subroutine is included in Appendix A. The modifications herein described were made for the purpose of arranging the output in a more convenient form for the purposes of this report. Presently time histories of 16 variables may be printed in two tabled summaries of values and up to 10 graphs plotted in each run. Additional variables may be output by a single change to the present format. The graphs may be drawn on either the off-line (calcomp) or on-line (print) plot. Changing this routine necessitated minor changes in both the RHS and INCON Subroutines.

The changes in RHS consisted of modifying the method of writing the variables on the temporary storage device. Only one temporary storage device is used. This was done in order that the list can be searched by variable number instead of searching by variable name.

The changes in INCON necessitated the creation of new blocks 20, 21, and 22. Information input and the form of that information can be found in the user's manual, Appendix A.

#### D. SUBROUTINE INCON

The INCON Subroutine is the most difficult of all the subroutines to discuss since it reads and computes the initial conditions of all variables and constants which affects how the entire program functions. The thorough understanding of this subroutines' function and operation are a prerequisite





to exercising the program. To assist in this understanding a description of the operation of the Subroutine and where necessary full description of the important functional computations is presented in this section.

The INCON Subroutine is divided into numbered blocks which are controlled by the read statement number 10. (see Appendix B). Notice that the method is to read a 3 digit integer followed by a 2 digit integer. The first 3 digits are called the block number and the next 2 digits the option tag. By executing the computed go to statement according to the block number the statement next executed can be controlled. Consider as an example the number 01601. The block number is 016 and the option tag is 01. Hence, the block number will cause the program to flow to statement number 1600 by the GO TO control and then be routed to statement 1605 by option tag number in another GO TO control. Using this flow control all of the necessary information is input to the program from the card reader and disk.

What follows is not a block by block description of the input, but rather a description of those places in which changes have been made and in which particular calculations of interest occur. A block by block explanation of the input is contained in the user's manual Appendix A.

#### Block 2 option 1

This input block is the summary mass and inertia input. Option 2 allows a discrete mass input to be read. It is important to point out the source of the numbers presently



being used for the XR-3. As a first approximation the moments of inertia found on page 1 of reference 2 were scaled up to the present XR-3 configuration. The craft weight given in reference 2 was 4192 pounds and a ratio of  $\frac{5813}{4192} = 1.39$  was used to compute the following inertias.

$$I_X = 2941 \text{ slug ft}^2$$

$$I_Y = 9320 \text{ slug ft}^2$$

$$I_Z = 11300 \text{ slug ft}^2$$

However, the numbers presently employed are those provided by NSRDC and are:

$$I_X = 2870 \text{ slug ft}^2$$

$$I_Y = 9320 \text{ slug ft}^2$$

$$I_Z = 10580 \text{ slug ft}^2$$

As can be seen, the difference is minimal. No information was available for the product inertia  $I_{XZ}$  and therefore it was assumed to be zero value.

#### Block 4 option 2

The appendages section of the program has been removed since there are no fins or other appendages on the XR-3.

#### Block 5

The measured data inputs to the stern seal block consists of the X and Z coordinate of the seal hinge, the seal angle, the length of the seal leading edge, the pressure differential between the seal bag and the plenum chamber, seal leakage orifice coefficient and the base leakage area.

It was assumed that the leakage orifice of the XR-3 had the same characteristics as the stern seal orifice of the



100B. Thus the seal leakage orifice coefficient remains unchanged.

The base leakage area refers to that area over which the leakage coefficient exerts influence. This is the gap that allows a flow from the plenum to the atmosphere. The leakage flow is the control over the plenum pressure, fan flow rate and thence the fan horsepower calculations. The leakage area is distributed throughout the craft and it is necessary that this number be adjusted to bring the above three calculations into balance at a steady state operating condition. If the base leakage area is reduced it causes the craft to either rise, or the pressure to increase, or the fan flow rate to be reduced. The number presently being input is the result of such an adjustment and the three calculations are in agreement with experimental data concerning draft and plenum pressure.

#### Block 6

These bow seal inputs correspond to those of the stern seal in Block 5.

#### Block 7 option 2

The critical Froude Number was obtained as follows.

$$Fn \text{ critical} = \frac{V}{\sqrt{GL}} = \frac{13.4}{\sqrt{(20)(32)}} = .556$$

Where: V = speed in feet per second (critical or hump speed)  
L = length of the plenum (nominal) in feet  
G = gravitation constant



### Block 8 option 1

Those inputs that correspond to thrust have been removed and are found in block 16.

### Block 9 option 1

Although there is no rudder on the XR-3, it was considered necessary to provide information for the rudder effect produced by the propulsion system. Refer to Figure 10 which shows a crosssectional view of one of the outboard motors. Dimensions in the figure are inches and must be converted to feet and square feet for input.

The first assumption made was that the effect of the outboard motors could be separated into two parts, first, the forces contributed only by rudder action and secondly the forces which result from the thrust.

The second assumption was that the dashed line represents the water surface under most operating conditions. That is, at the stern, the water level doesn't change much; at least, not enough to reflect great rudder force changes. Additionally, waves do not interrupt flow at the rudder. Therefore, all that is required is to determine the respective areas and lengths, convert them to feet and enter them properly through the card reader. The wetted surface rudder effect area, therefore, is that region which is cross hatched in Figure 10.

Rudder span is defined as the vertical length of the rudder. This distance is the wetted surface distance. Based upon the foregoing assumptions only 2/3 of the block marked





# RUDDER GEOMETRY

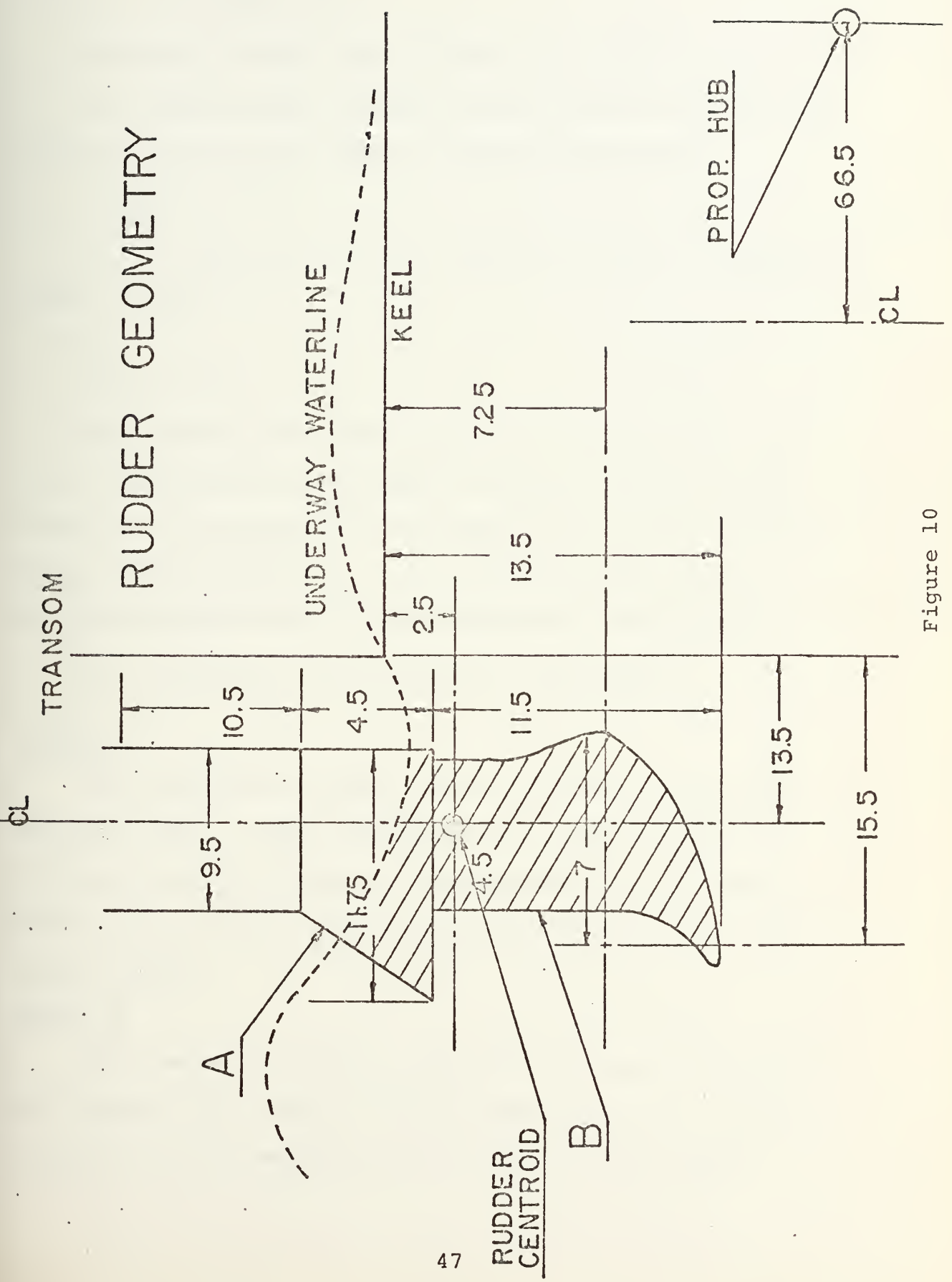


Figure 10



A in Figure 10 through which the water line passes contributes to wetted area.

$$\text{Therefore, rudder span} = \frac{2}{3}(4\frac{1}{2}) + 11\frac{1}{2} = 14.5" = (1.21 \text{ ft.}).$$

The rudder aspect ratio is defined as the rudder span squared divided by the area, a dimensionless term.

$$\frac{(1.21)^2}{.68} = 2.15$$

Total rudder area is the summation of the cross-hatched area; A and B.

$$\frac{2}{3A+B} = R_A$$

The area of B is taken to be the average width 5.75 inches multiplied by the length. The area of Block A is taken to be a rectangle 11.75 inches by 4.5 inches with a small triangle removed. It is felt that these approximations will not lead to any gross force inaccuracies.

$$R_A = 31.9 + 66.1 = 98.0 \text{ inches}^2 \quad (.68 \text{ feet}^2)$$

#### Block 10

The aerodynamic inputs are the reference length and reference width. These dimensions are used to compute a reference area to be used in conjunction with the particular values of the coefficients obtained from the wind tunnel tests.

#### Block 15

The shears and moments calculations have been removed and replaced by a dummy subroutine SAM, since no stress analysis will be performed on the XR-3. This removal



provides a convenience for the purposes of this report.

#### Block 16 option tag 1

Entries input in block 16 option tag 1 permit the user to input a predetermined time history of thrust on the starboard screw as a map. That is, either constant or variable thrust may be selected. The user must input data points from the map of the variable thruster and the function sub-program FGI is used to determine the functional value of thrust at any given time. A maximum of 24 data points may be used to describe the map.

#### Block 16 option tag 2

Exactly the same as option tag 1, except that these entries apply to the port screw.

#### Block 16 option tag 3

The entries in block 16 option tag 3 allow the user to input a rudder motion map. Positive rudder angles are right rudder angles which cause the craft to turn to the right.

#### Block 17

Option tags 1 and 2 permit the user to vary bow and stern seal differential pressures as the program run progresses. The differential pressure is taken to be that between the seal and the plenum. This represents a revision to the original program.

#### Block 19 option tags 1, 2, and 3

These inputs allow the user to input fan map data and thus control air flow in both the seals and plenum.



## E. SUBROUTINE PROP

The forces and moments associated with the propulsion and steering systems for CAB craft are somewhat unique for each propeller and rudder system type. In the original Oceanics' program, written to simulate the Bell 100 ton SES, the system described consisted of two fixed super-cavitating propellers each with a rudder mounted directly astern. Both the propellers and rudders were located close to the transom of the craft. In the XR-3, the propulsion system consists of two forty horsepower outboard motors each is fitted with a two bladed screw. The port screw has a right hand rotation and the starboard has a left hand rotation. With this system steering is accomplished by rotating these motors in the horizontal plane. In turn, the main thrust vector produced by each propeller is rotated in the horizontal plane to provide a desired turning moment. Additional turning moment is provided by the motor/propeller housings which are essentially shaped like a rudder foil. However the surface areas of these housings are significantly reduced from typical rudder areas associated with a fixed propeller system. The rudder characteristics are further described in the RUDDER Subroutine.

The rotation of the propeller thrust vector in the horizontal plane adds a complication factor to the XR-3 description which was not present in the 100B craft simulation. Hence, the original PROP Subroutine required major changes in order to make it properly describe the XR-3 craft.





In the XR-3 description, as in the 100B, specific propeller characteristics such as; RPM, Blade pitch, and the various propeller coefficients are not included to determine the thrust and torque produced by each propeller. In both simulations the thrusts are either input values or calculated from the equations of motion for the associated input velocities.

The propeller representation allows either propeller to provide any desired thrust and side thrust independent of the opposite propeller. This feature is available through the use of function routine FGl. FGl is used to describe the thrust of each propeller as a function of time. When the program operates in this mode the velocities and accelerations of the XR-3 are obtained from the equations of motion as a result of the input propeller thrusts. Another operating mode provides for velocity to be input and the resultant total propeller thrust is obtained from the motion equations. In this mode of operation, it is assumed that the total thrust is divided equally between both propellers, and function FGl is not used since the propeller thrusts are not input.

The above two modes of operation allow for maximum program flexibility and simplicity. Test run data of both thrust and velocity is available from the installed XR-3 instrumentation. Thus, the simulation can easily duplicate any given set of operating conditions.



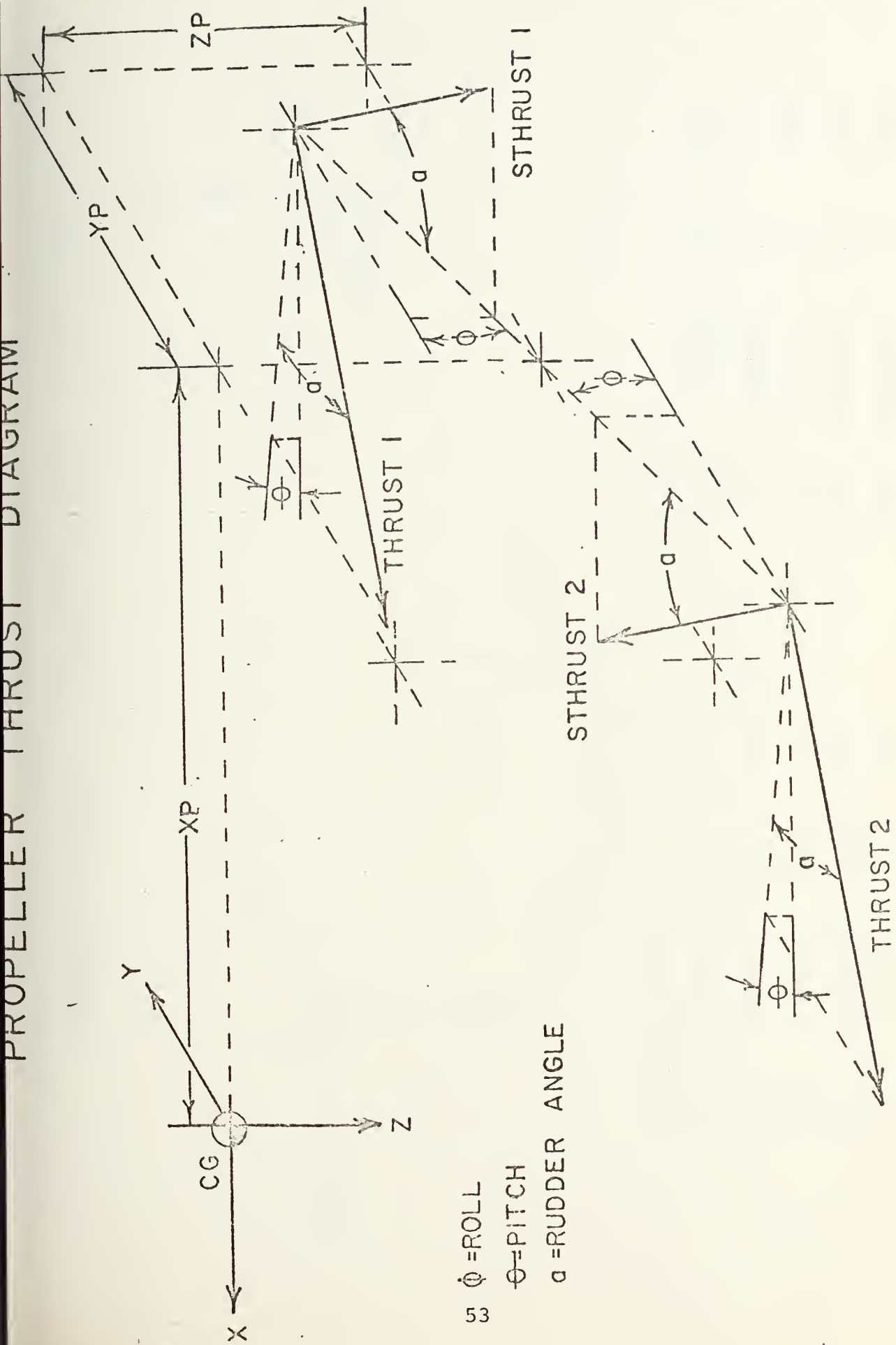
The force and moment equations for the propeller system of the XR-3 are derived from the propeller thrust diagram given in Figure 11. The figure displays the main thrust and side thrust vectors for both propellers positioned with right rudder angle  $a$ , positive pitch angle  $\theta$ , and negative roll angle  $\theta$  present. The thrust vectors act through the port and starboard propeller positions;  $x_p$ ,  $y_p$ , and  $z_p$ , from the craft center of gravity in the Body Reference coordinate system. These thrusts are then converted to forces in the local level reference coordinate system for the calculation of craft pitch, roll, and heave and forces in the Inertial Reference frame for calculation of craft trajectory. That is, the craft yaw angle  $\psi$ , and  $x$  and  $y$  displacements.

The forces associated with the propeller arrangement of Figure 11 are depicted vectorially in Figure 12 in the Local Level Coordinate system. Employing the simplifications used in the derivation of the equations of motion namely that the pitch angle  $\theta$  and roll angle  $\theta$  are limited to small values, such that  $\sin\theta \cong \theta$ ,  $\cos\theta \cong 1$ , and  $\sin\theta \cong \theta$ ,  $\cos\theta \cong 1$  the following force equations result:

$$\begin{aligned}
 T1X &= \text{THRUST 1} * \text{COS}a \\
 T2X &= \text{THRUST 2} * \text{COS}a \\
 ST1X &= \text{STHRUST 1} * \text{SIN}a \\
 ST2X &= \text{STHRUST 2} * \text{SIN}a \\
 T1Y &= \text{THRUST 1} * \text{SIN}a \\
 T2Y &= \text{THRUST 2} * \text{SIN}a
 \end{aligned}$$



PROPELLER THRUST DIAGRAM



53  $\phi$  = ROLL

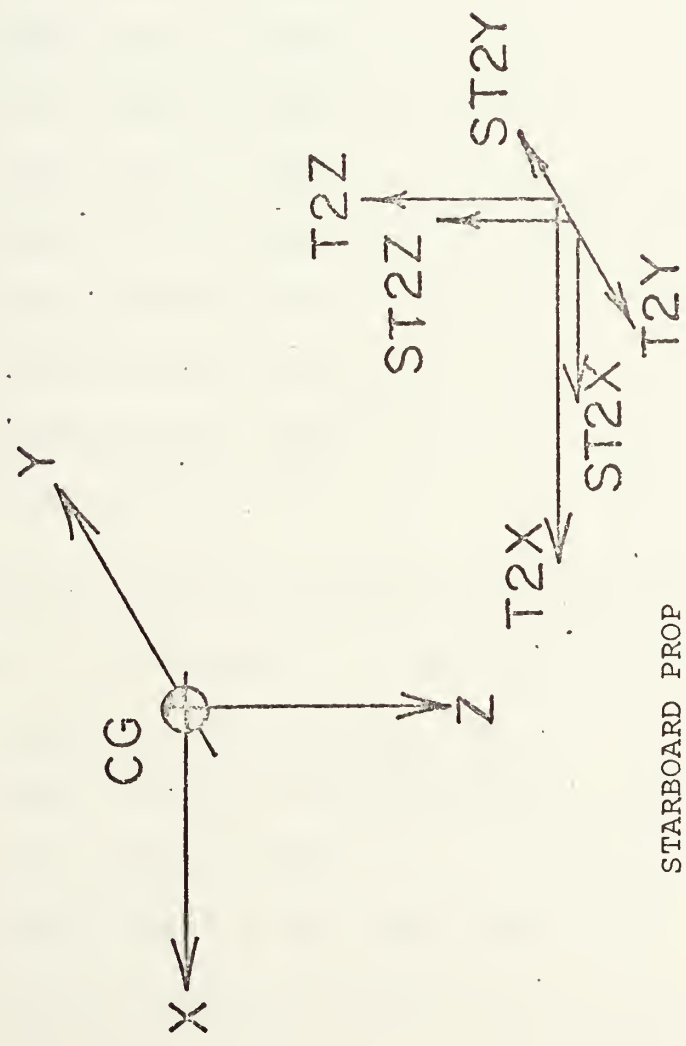
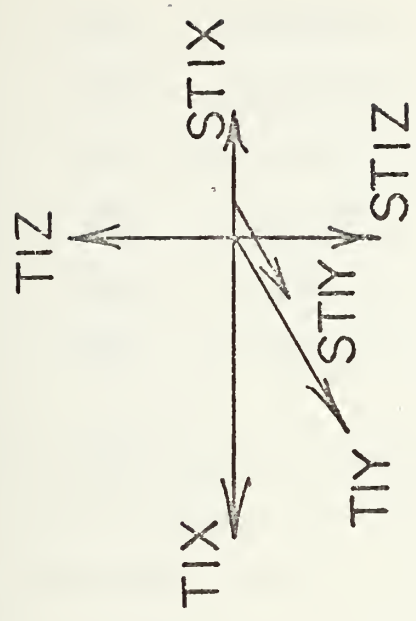
$\theta$  = PITCH

$\alpha$  = RUDDER ANGLE

Figure 11



# RESULTANT PROPELLER FORCES



STARBOARD PROP	Port Prop	
$T1X = THRUST\ 1 * COS\alpha * COS\theta$	$T2X = THRUST\ 2 * COS\alpha * COS\theta$	
$T1Y = THRUST\ 1 * SIN\alpha * COS\theta$	$T2Y = THRUST\ 2 * SIN\alpha * COS\theta$	
$T1Z = THRUST\ 1 * COS\alpha * SIN\theta$	$T2Z = THRUST\ 2 * COS\alpha * SIN\theta$	
$ST1Y = STHRUST\ 1 * SIN\alpha * COS\theta$	$ST2X = STHRUST\ 2 * SIN\alpha * COS\theta$	
$ST1X = STHRUST\ 1 * COS\alpha * COS\theta$	$ST2Y = STHRUST\ 2 * COS\alpha * COS\theta$	
$ST1Z = STHRUST\ 1 * COS\alpha * SIN\theta$	$ST2Z = STHRUST\ 2 * COS\alpha * SIN\theta$	

Figure 12





$$\begin{aligned}
ST1Y &= STHRUST\ 1 * COSa \\
ST2Y &= STHRUST\ 2 * COSa \\
T1Z &= THRUST\ 1 * COSa * \theta \\
T2Z &= THRUST\ 2 * COSa * \theta \\
ST1Z &= STHRUST\ 1 * COSa * \phi \\
ST2Z &= STHRUST\ 2 * COSa * \phi
\end{aligned}$$

By summation of forces in the three coordinate directions the following port and starboard propeller and total force equations result:

$$\begin{aligned}
FXS &= T1X + ST1X \\
FXP &= T2Z - ST2X \\
FX &= FXS + FXP \\
FYS &= T1Y - ST1Y \\
FYP &= T2Y + ST2Y \\
FY &= FYS + FYP \\
FZS &= -T1Z - ST1Z \\
FZP &= -T2Z + ST2Z \\
FZ &= FZS + FZP
\end{aligned}$$

The moment equations associated with the preceding force equations are given as:

$$\begin{aligned}
FKS &= FZS * YP - FYS * ZP \\
FKP &= FZP * YP - FYP * ZP \\
FK &= FKS + FKP \\
FMS &= -FZS * XP + FXS * ZP \\
FMP &= FZP * XP + FXP * ZP
\end{aligned}$$



$$FM = FMS + FMP$$

$$FNS = -FXS * YP + FYS * YP$$

$$FNP = FXP * YP + FYP * XP$$

$$FN = FNS + FNP$$

Throughout the preceding representation it is assumed that the magnitudes of the main and side thrust vectors remain independent of the various rudder deflection angles  $\alpha$ . It is also assumed that both port and starboard propellers rotate together through the same rudder deflection angles.

#### F. SUBROUTINE RHS

Subroutine RHS contains the expressions of the right hand side of the force and moment differential equations. These forces are calculated and summed in this subroutine.

Changes in this subroutine consist of modification of the Bubble Drag Coefficient of Friction, Common Block ties, and Center of Pressure Location. The rationale for these changes is presented in the section concerning the presentation of data.

#### G. SUBROUTINE RUDDER

The rudder subroutine used in the XR-3 simulation remains essentially unchanged with respect to its force and moment equations. However, some changes are introduced in the calculation of rudder deflection angle ' $\alpha$ ' and in the input data to reflect the proper XR-3 rudder location and dimensions.



Rudder deflection angle can either be input as a constant angle in the input data set or it can be made to vary with time by using function FGL. Note, this rudder deflection angle is the same angle input to PROP subroutine to control the main thrust vector orientation.

As previously noted in the description of subroutine PROP, the motor/propeller housings constitute the XR-3 rudders. Physical measurements of these housings were used as rudder dimensions in the input data set. Each rudder/housing is located directly astern of its associated sidewall. They are vertically mounted and rotate in the horizontal plane.

The analysis of the XR-3 rudders assumes that they produce only lateral and drag forces. Lift or Z direction forces are considered negligible and hence they are set equal to zero.

The development of the force equations associated with the rudders of the XR-3 follows the analyses from references 9 and 7. The lateral force produced by both rudders is given by :

$$FY=2*RHO*U*U*A_r*(1+d/h)*RCLB*(a-(1+d/h)*V_h/U)$$

where  $A_r$  is the rudder area,  $RHO$  is the water mass density,  $U$  is the velocity in the X direction,  $d$  is the draft at the rudder,  $h$  is the draft plus the rudder span or length,  $RCLB$  is the lift coefficient for the rudder given as  $RCLB = 2AR/(AR+3)$  where  $AR$  is the aspect ratio,  $a$  is the rudder deflection angle,  $V_h$  is the first order approximation



rudder velocity in the lateral direction  $V_h$  is given by:

$$V_h = V + XR * R - ZR * P$$

with XR and ZR the coordinate locations of the rudder center with respect to the craft center of gravity.

The drag force produced by the rudders is given by

$$F_X = -2 * C_D * A_r + \rho * U^2.$$

The drag coefficient is given by

$$C_D = 2 * C_{FR} + \frac{\pi}{8} * \left(\frac{Tr}{C}\right)^2 * \left(1 + \frac{G(h-d)}{U^2}\right) + \frac{RCLB * V_h'}{U}$$

where G is the gravity, Tr is the rudder thickness, C is the rudder chord, and CFR is the coefficient of friction given by the Schultz-Grünow formula

$$C_{FR} = .427 / (\log REY - .407)^{2.64}$$

where  $REY = U * Ar / (h-d) / \nu$ .

REY is commonly referred to as the Reynold's Number and  $\nu$  is the kinetic viscosity =  $1.28 \times 10^{-5} \text{ft}^2/\text{sec}$ .

The two preceding force equations produce the following moments:

$$F_K = -Z_R * F_Y$$

$$F_M = Z_R * F_X$$

$$F_H = X_R * F_Y$$





## H. SUBROUTINE SIDEWALL

Changes made to the sidewall subroutine consist of the removal of force computations associated with ventral fins which are not present in the XR-3 testcraft. The remainder of the subroutine is unchanged from the Bell 100 ton craft version described in reference 9 .

The hydrodynamic and hydrostatic forces and moments acting on the sidewalls are found by application of slender body theory. This theory, based on motion of a foil in a viscous medium, develops methods for finding the lift and drag forces associated with moving underwater bodies. These methods are primarily linear in nature as shown in references 1 and 9 with the effect of instantaneous changes in immersed sectional area, draft, etc. due to orientation changes arising from heave, pitch, and roll motions reflecting the most significant nonlinear variations. The sidewall forces also contain certain nonlinear terms due to cross-flow drag, which are important for the case of very low aspect ratio lifting surfaces as are the XR-3 sidewalls. The sidewall forces will then be composed of two separate contributions; first the terms due to sidewall buoyancy and slender body hydrodynamic reactions and second the effect of cross-flow drag, i.e.

$$R_{\text{sidewalls}} = F_{H_{sw}} + F_{D_{sw}}$$

where  $F_H$  forces result from slender body theory, and  $F_D$  forces are the result of the cross-flow drag terms.



Although no changes were made to the sidewall subroutine force and moment equations they were considered of adequate importance to be here discussed.

Before computing the forces on the sidewalls, the subroutine first calculates the draft of or the gap beneath the sidewalls. The draft/gap is found for each X-direction section after it has been corrected for craft roll and pitch angles and waves. If gaps are present, then the total sidewall leakage area ALSW is computed by summing the products of gap heights and sidewall section lengths for both sidewalls.

#### 1. Cross-Flow Drag Terms

The cross-flow drag force components are assumed to only be significant for the lateral force, yaw moment, and roll moment. While such forces are also present in the vertical force and pitch moment, they are not as large relative to the predominant forces due to bubble pressure and are neglected. The lateral force due to cross-flow drag on a single sidewall is given by:

$$FYD = -RHO/2 * CDC * VREL * ABS(VREL) * DELX * DSWAV$$

where  $VREL = V + XAVG * R - ((ZS - DSWAV) / 2) * P$  and DELX is the length of each sidewall section, DSWAV is the draft of the ith sidewall section corrected for waves,  $(ZS - DSWAV) / 2$  is the average Z distance of the ith sidewall section from XREF where XREF is input as 9 feet forward of the transom.



These expressions are appropriate to the particular values associated with sidewall sections in either the port or starboard side. The yaw moment due to cross-flow drag is

$$FND = FYD * XAVG$$

where XAVG is the average X distance of the ith sidewall element from XREF. The roll moment is given by

$$FKD = FYD * (ZS - DSWAV / 2)$$

The total force and moment values due to cross-flow drag are then

$$FYD = FYD (1) + FYD (2)$$

$$FND = FND (1) + FND (2)$$

$$FKD = FKD (1) + FKD (2)$$

where the subscripts (2) and (1) indicate the port and starboard sidewalls respectively.

The cross-flow drag coefficient is the value corresponding to that for flow normal to a long flat plate, with a value of CDC = 1.28.

## 2. Slender Body Theory Terms

Following the procedures indicated in reference 9, together with evaluation of all integral terms involving derivatives of sectional properties by means of integration by parts the following results are found for a single sidewall (port or starboard, using appropriate values for each): The X-direction sidewall drag force is given by



$$FXH = -RHO/2 * CDT * WAREA * U * U$$

where WAREA is the wetted area of a sidewall section corrected for draft, roll, and pitch. CDT is the computed drag coefficient.

The Z-direction sidewall force corrected for added mass effect is given by

$$FZH = -G * BCO - U * U * A33S * THETA - U * A33S * W + Q * U * (A33S * XSS - BC2) - U * A33S * P * YLSW$$

where BCO is the mass of the water displaced by the ith sidewall element which causes a negative buoyant force, A33S is the vertical added mass of the ith sidewall element given by  $A33S = RHO * \pi * BS **2/8$ , where BS is its beam. BC2 is the total sidewall vertical added mass and YLSW is the lateral distance of the ith sidewall element from the centerline.

The hydrodynamic lateral force is given by

$$FYH = -A22S * U * (V + XSS * R - ZS * P)$$

where A22S is the lateral added mass at the stern given by

$$A22S = RHO * .4 * PI * DSS **2/2$$

where DSS is the sidewall draft. The moment about the Y-axis is given by

$$FMH = -U * XSS * XSS * ASS3 * Q + G * BCOO + U * (A33 * XSS + BC2) * (W + U * THETA + YLSW * P)$$





Where BCOO is associated with the sidewall volume between XREF and XS. This computation is available by entering a table of values computed offline in program SIDETAB and stored in common block WAVTAB by the INCON subroutine.

The moment about the Z axis is given by

$$FNH = FYH * XSS - U * ((V-ZS * P) * BC5 + BC 6 * R)$$

where BC5 is the total lateral added mass and BC 6 is the moment associated with the total lateral added mass.

The total slender body theory and crossflow forces, and moments for both sidewalls are then given by

$$FX = FXH (1) + FXH (2)$$

$$FY = FYH (1) + FYH (2) - FYD$$

$$FZ = FZH (1) + FZH (2)$$

$$FK = (FZH (2) - FZH (1)) * YSW - ZS * FY + FKD$$

$$FM = (FMH (1) + FMH (2)) + ZS * FX$$

$$FN = (FXH (1) - FXH (2)) * YSW + FNH (1) + FNH (2) + FND$$

In the calculation of the individual sidewall force terms it is understood that the computation is appropriate to the instantaneous values of the separate elements as the vehicle moves.



## I. SUBROUTINE STERN SEAL

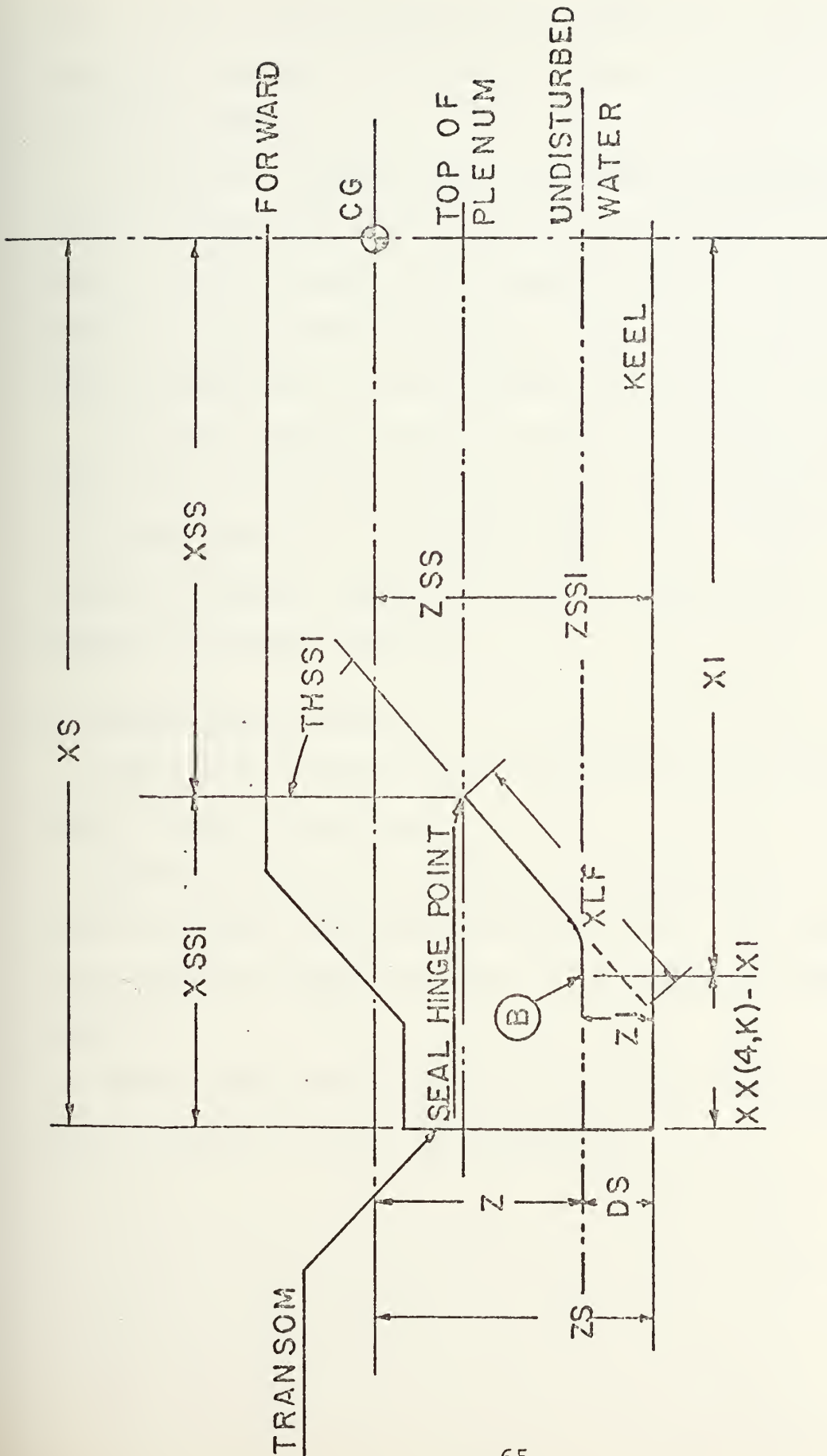
Since the bow and stern seals of the XR-3 are similar except for location the subroutines also are similar except for variable names.

Reference to Figure 13 and the list below will acquaint the reader with the important variable names.

Dimension	Origin
XS	INCON ROUTINE BLOCK 225. XS is calculated by locating the CG and there calculating the distance to the transom.
XSSI	INCON ROUTINE BLOCK 500. This is input as the distance from the transom to the hinge point of the seal.
ZS	INCON ROUTINE BLOCK 200. ZS is calculated in the same manner as XS except that it measures the vertical distance from CG to the keel.
ZSSI	INCON ROUTINE BLOCK 500. This is the vertical distance from the hinge to the keel.
XSS	This is calculated in INCON BLOCK 1302, using the information XSSI and XS and represents the horizontal distance from the center of gravity to the seal hinge.
ZSS	This is calculated in INCON BLOCK 1302 using the information provided by ZSSI and ZS and represents the distance from the center of gravity to the hinge.
THSSI	This is the angle of the seal face made with the craft vertical and is input in block 500 of INCON.

Lift and drag forces in the stern seal result from the pressure differential between the seal and the plenum and the amount of the seal in contact with the water respectively. Since the plenum exhausts mainly under the stern seal we assume the bubble to extend to the tip of the stern seal.





CALM WATER  
 ROLL = 0.0  
 PITCH = 0.0

# STERN SEAL CONFIGURATION

Figure 13



Thus the stern seal becomes an air lubricated surface and the plenum pressure is extended all the way under the seal to the atmosphere.

We can then assume that the forces acting upward concentrate themselves at the point (B) in Figure 13 which represents the mid-point of the wetted surface. It is also logical to exert the drag forces at this same point, since they act along the wetted surface, the surface of friction.

We find that the forces in the Z direction are much less than in the bow seal because the differential pressure is so much less than in the bow seal. The bow seal is acting against atmospheric pressure while the stern seal is acting against the plenum pressure.

#### J. COMMON BLOCK TIE MAP

The Common Block Tie Map shows which common blocks appear in each subroutine.

The map is read by finding the common block in the left hand column and then reading to the right. An X appears in each column under the subroutine in which that common block appears.

Some common ties have only one entry. This results from the removal of the SAM subroutine.





COMMON BLOCK TIE MAP

SUBROUTINE NAME	COMMON BLOCK NAME	MAIN	AEROD	BOWSL	COLFIL	FAN	INCON	INTGRL	PROP	RHS	RUDDR	SIDEWL	STNSL	WAVES
AIR		X		X		X	X			X		X	X	
AXIS					X		X							
BMCO		X					X	X		X		X		X
COLUMN					X		X			X				
CONST		X		X			X		X	X	X	X	X	X
CNTRL							X			X				
CURVE					X		X							
ENGINE		X					X		X	X				
EQNCO		X					X	X						
FAERO			X							X				
FAIR			X				X							
FANMAP						X	X			X				
FORBS				X						X				
FORSS										X			X	
FPROP		X							X	X				
FROUDE		X					X			X				
FRUD										X	X			
GBOW							X			X				
GEOM				X			X			X		X	X	X
GEOMBS				X						X				X
GEOMSS										X			X	X
GEOMSW							X					X		



COMMON BLOCK TIE MAP (CONT.)

SUBROUTINE NAME	MAIN	AEROD	BOWSL	COLFIL	FAN	INCON	INTGRL	PROP	RHS	RUDDR	SIDWL	STNSL	WAVES
COMMON BLOCK NAME													
GRAF				X		X							
HEADG				X		X							
KSWITCH							X		X		X	X	
LEAKER			X			X						X	
MASSES			X			X	X		X	X	X	X	X
MATRIX						X			X				
MSIDW									X		X		
MWAVE									X				X
OPTION						X			X				
PLENUM						X			X		X		X
PRIME	X					X	X		X		X		
PRTINT	X	X	X		X	X	X	X	X	X	X	X	X
PWAVE						X			X				
RISER						X							X
ROLL	X					X							
RUDDR	X					X		X	X	X			
SIDE						X			X		X		X
SOFTBS		X			X	X			X				
SOFTSS					X	X			X			X	
STABLE						X	X						
STSLR						X						X	
SUM				X		X							



COMMON BLOCK TIE MAP (CONT.)

SUBROUTINE NAME	MAIN	AEROD	BOWSL	COLFIL	FAN	INCON	INTGRL	PROP	RHS	RUDDR	SIDWL	STNSL	WAVES
VALOLD	X					X	X		X			X	
VARBLE	X	X	X		X	X	X	X	X	X	X	X	X
WAVE	X		X			X			X		X	X	X
WAVEF						X							
WAVTAB						X					X		X



#### IV. PROCEDURES

##### A. OBTAINING STEADY STATE

Following program modification to reflect the geometry of the XR-3, program runs were made to obtain steady state conditions. This was accomplished by comparing steady state program outputs of thrust and pitch angle with measured data obtained from the XR-3 testcraft. The testcraft measured data consisted of steady state thrust and pitch angle measurements made at several velocities between 10 and 25 knots in calm water. These measured data formed the basis upon which program modifications were to be made.

It was first necessary to change the thrust versus velocity curve produced by the program so that it coincided with the measured data. This was accomplished by adjusting the bubble frictional drag coefficient to bring the lower portion of the curves into agreement. A similar agreement was obtained at the high end of the curve by adjusting the skin frictional drag. This drag is a direct result of craft draft, and is therefore not easily obtained. Adjusting draft requires that both plenum pressure and fan flow be maintained in such a manner that the appropriate lift is attained without exceeding the horse power limitation of the fan engines. Successive runs using the constant speed, trim option of the program were made at various drafts until the appropriate values of thrust for a velocity was obtained.





Having found that draft which produces the required drag, hence, the proper thrust, bubble pressure and stern seal leakage were adjusted to bring the forces in the Z direction into balance. To accomplish this the plenum pressure that produced the required lift was found and then the stern seal leakage was adjusted to provide the proper fan flow which maintained fan engine horsepower within its limits. A small portion of the total seal leakage was assumed to exist at the joints between the bow seal and sidewalls, the remainder being under the stern seal.

No attempt has been made to provide agreement between the craft transient behavior and that of the program. However, the data herein presented appears to show that there is a fair amount of agreement in this area. The transient behavior of the craft and the simulation program provide a very fertile area for further investigation.

## B. DIFFERENCES ENCOUNTERED IN THE MODEL

### 1. Seal Configuration

For reasons previously stated, the mathematical model of the 100B stern seal was selected to represent both seals on the XR-3. The forces calculated by the simulation program employing this model appear to be reasonable. That is, they are of the same order of magnitude as those scaled from the 100B. Leakage coefficients were not changed since the type of orifices employed on the XR-3 were considered to be similar to the 100B.



## 2. Plenum Dimensions

For a first try at implementing craft plenum geometry actual craft measurements were taken and used as input data to the simulation program. However, it was found that these dimensions did not produce appropriate XR-3 force and moment relationships. Through investigation of XR-3 model data and subsequent program utilization the arbitrarily chosen nominal values of 10 and 20 feet, plenum width and length respectively, provided the desired results. Lift due to plenum pressure was highly sensitive to these plenum dimensions. Therefore, when more accurate plenum pressure data becomes available these dimensions may require some refinement.

### C. SENSITIVITY TO CHANGES TO INPUT DATA

It was found that the XR-3 is extremely sensitive to the initial conditions included in the input data set. Small disagreement between the required initial conditions and those input, produce violent transients that can cause the program to stop execution or to give erroneous results.

Two of the most critical input parameters are craft draft and plenum pressure. This is true because the plenum pressure and draft are closely interrelated and cannot be separated for analysis. The plenum, having a large surface area, exerts the greatest single force on craft dynamics. Hence, a very small change in plenum pressure operating on this large surface area, 200 square feet, produces a significant



change in the Z direction force. Thus, imbalance of either draft or pressure, or draft and pressure, cause transients too great for the simulation to accept. These results also suggest that rapid maneuvers or inputs approaching step-functions will also produce transients too great to be adequately computed.

It is recommended that an investigation be conducted to determine methods of improving the integration procedure to allow very rapid maneuvers.

#### D. POSSIBLE ERRORS IN THE PROGRAM

Many coefficients herein described were assumed to be correct. However, this may not be the case. Those coefficients that are calculated by their definitions such as Reynolds number and Froude number are most probable correct. However, leakage orifice coefficients, skin friction coefficients and the bubble drag coefficients have not been verified, though they seem to give adequate results.

Other coefficients unknown to be exact are the moments of inertia. The simulation program provides a method for accurately calculating the moments of inertia,  $I_X$ ,  $I_Y$ ,  $I_Z$  and  $I_{XZ}$ . This option was not employed because accurate weight distribution data was not available. The moments of inertia  $I_X$ ,  $I_Y$  and  $I_Z$  were obtained from references describing the craft prior to many major modifications. Not the least of which was the installation of the auxiliary power supply and the replacement of bow and stern seals.



These modifications added a considerable percentage to the total craft weight. These weight additions were concentrated in several locations. Hence, the scaled values of  $I_X$ ,  $I_Y$  and  $I_Z$  used in the simulation cannot be relied upon as being accurate.

No available data could be found concerning the product moment of inertia  $I_{XZ}$ . This moment of inertia is required when attempting to execute maneuvers involving turns or off centerline craft motions. Therefore, an estimated value using size scaling was employed and rendered reasonable craft motions under the above conditions.

To determine the correct moments of inertia, it is recommended that a thorough craft mass distribution analysis be conducted and the resulting parameters be input to the program utilizing the option mentioned above.

A third area open to further improvement is that of refining the dimensions input to the sidewall map of the side geometry subroutine. The present representation for the XR-3 sidewalls loses much computational accuracy due to the large vertical stepsize presently used.

A remapping of the sidewall geometry is required to more accurately describe the curvature in the lower regions of the sidewalls. This would result in the subroutine providing more refined values of sidewall volume and surface area for the various XR-3 drafts and attitudes which are important for the calculation of sidewall forces and moments.





Notwithstanding the above areas in which error exists it is felt that the craft data and figures tend to indicate that the simulation program is a valid representation of XR-3 motion.



## V. PROGRAM VERIFICATION

### A. INSTRUMENTATION AND RECORDED DATA

Instrumentation as presently installed in the XR-3 includes the following:

1. Two strain gauges mounted directly on the engine mounts measure the thrust of the propulsion system.
2. A rate Gyro mounted near C.G. is used to measure pitch and roll angles.
3. A turbine type flowmeter which extends forward in undisturbed water measures velocity.

Additional instrumentation presently operational on the XR-3 measures yaw, pressure in the plenum and seals, and rudder angles. The output from these sensing devices are recorded on a 14 track Pemco Model 120B Magnetic tape recorder. Hard copies of the measurement data are obtained using a Hewlett Packard two channel chart recorder. No filtering other than that natural filtering caused by the frequency response of the recorders was used with the result that the data was quite noisy. The noise was considered to be white and gaussian, therefore the mean value of the resultant curve was taken as the best estimate of the variable under consideration.

Shown in Table I are the data collected from test runs made by the XR-3 at Lake San Antonio, California, over a one-day period in calm water and no wind conditions. Each



entry represents a steady state condition.



Table I. Test Craft Measured Data

Velocity in kts.	Thrust in pounds	Pitch angle in degrees
8.5	405	Not available
9.0	425	Not available
10.5	520	1.6
12.0	475	1.55
13.0	453	Not available
14.0	490	1.4
14.5	400	Not available
15.0	465	.8
16.5	407	Not available
17.0	395	Not available
19.0	415	Not available
19.5	425	Not available
20.0	440	.2
21.0	455	Not available
22.0	460	Not available
22.5	455	Not available
23.0	480	Not available
24.0	496	Not available
24.5	510	0.1
25.0	509	Not available





## B. L&M PROGRAM DEVELOPED DATA

### 1. Steady State Trim Conditions

Steady state trim conditions for the XR-3 using the L&M program were difficult to obtain. It was observed that the program initial conditions must be very close to the steady state values or the imbalance in forces generated within the program is so great that one of two cases occurs.

#### Case 1 using Variable Time Step (R-K-M)

The force imbalance causes such a radical transient that, in order not to lose curve information, the integration step size is reduced until the minimum allowed step size is reached and the program execution stops.

#### Case 2 using Fixed Time Step (R-K)

The danger in this method is that the step size may be too great (note: in some cases, .01 seconds is too large) and curve information is lost. When information is lost the program calculations begin generating erratic number values thus causing an underflow or overflow condition to exist within the program which stops program execution. Thus, care must be exercised in selecting a stepsize to be used. The results shown in Table II were obtained using the fixed step size option with a step size of .001. The constant speed and variable thrust options of Block 1 of the INCON Subroutine were selected. Since the force equations of the program are dependent upon speed, using these options removes the surge equation from the computations and adjusts thrust to balance the forces in the X direction.



Table II. L&M Program Initial Conditions

Speed (in knots)	Thrust (in pounds)	Pitch Angle (in degrees)	Draft (in inches)
10.0	504.6	1.72	6.6
12.5	419.3	1.31	6.5
15.0	392.4	.94	6.35
17.5	397.8	.6	6.15
20.0	424.7	.29	5.98
22.5	464.7	.13	5.78
25.0	512.8	.09	5.56
27.5	567.3	.06	5.3
30.0	625.5	.05	3.02

Plenum pressure 24.86 psf



To balance the forces in the Z direction short time runs of .01 seconds or less were used. For each run adjustments were made to the initial draft and/or plenum pressure to bring these forces into balance. Care was taken to avoid fan flows and pressures above that level requiring greater than 15 horsepower, which is the maximum horsepower available from the fan engines. Continuing in this manner the initial trim conditions of draft, pitch angle, and thrust required were obtained for each of the speeds shown in Table II. Once these initial conditions were known, the step size was increased to .01 and it was found that no curve information was being lost indicating that the transient was of a less violent nature. Long time runs using the variable time step size verified that these values were the correct initial trim conditions. A straight line segment was used to join the points so that linear interpolations may be used between the tabular values.

To obtain good agreement between measured and simulated data required the manipulation of two quantities that produce total ship drag; the bubble drag,  $FXPWAV$ , and the skin friction drag  $FX$ . Adjustment of the forces in the X direction was accomplished by adjusting draft to provide the proper drag force at the upper end of the velocity curve where the frictional drag component exerts the greatest influence over total ship drag. The next step was to adjust the coefficient of the bubble drag to provide the minimum point in the total drag curve at the velocity indicated by Table II, about 17.0



knots, and to also provide the required drag at the low end of the drag curve where the bubble drag exerts the greatest influence.

To obtain agreement between measured and simulated pitch angle required some programming changes. Reference 11 indicates that a pressure gradient exists in the plenum chamber. This gradient is such that as the craft increases in speed the center of pressure moves aft. This causes the craft to have a pitch up attitude at slow speeds and a gradually smaller positive pitch as speed increases. Using the experimentally measured data shown in Table I, a set of points representing the craft center of pressure position as a function of speed was calculated which would produce the appropriate craft pitch angle for a given speed. A linear function used to approximate these points was then included in the simulation program.

Figures 14, 15 and 16 show plotted points of the two tables of data. Triangles represent experimentally determined data and squares the program output. Clearly the program simulates quite well the thrust and pitch angle curves. Accurate data on draft was not available from XR-3 tests due to a defective height sensing device. However, it is felt that the draft data when available will closely fit the curve shown.

## 2. Presentation of Unverified Program Data

Figures 17, 18 and 19 demonstrates the use of the variable thrust option. Thrust is input to Subroutine PROP





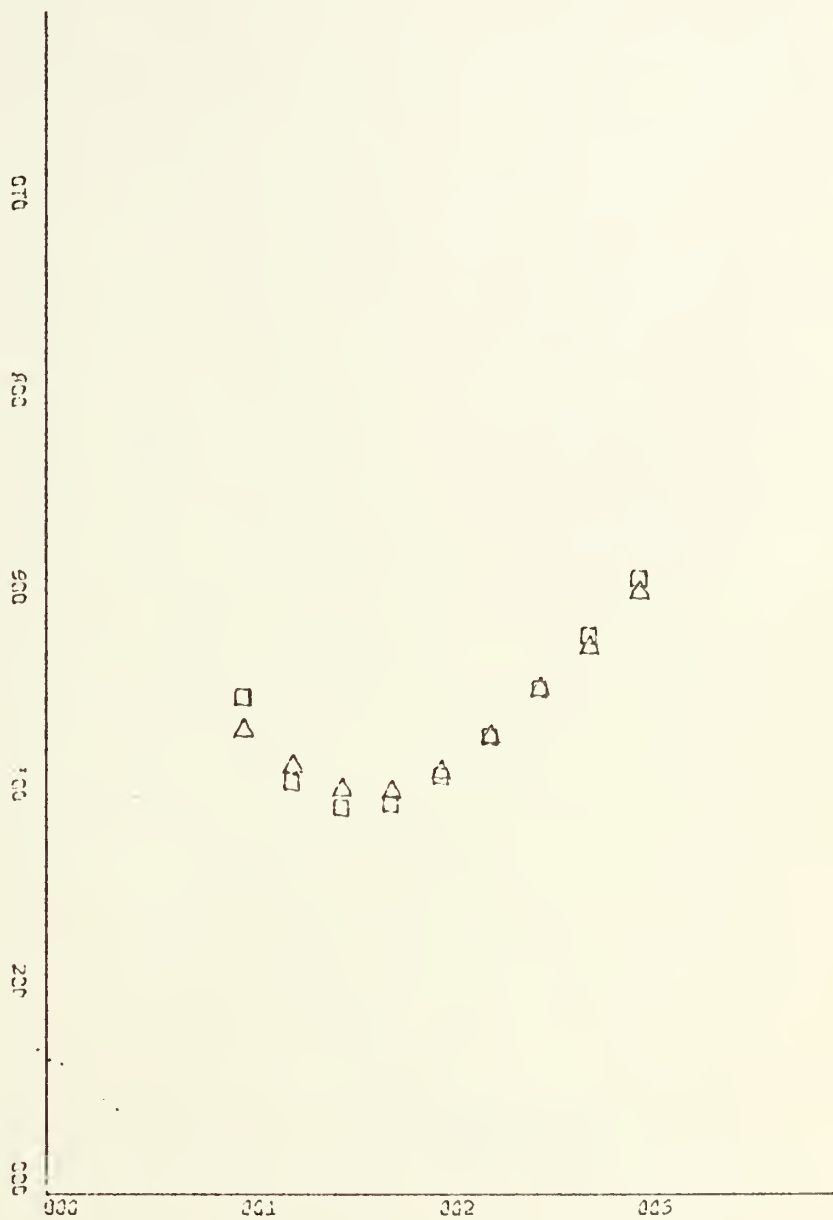


Figure 14

X-SCALE=1.00E+01 UNITS INCH.

Y-SCALE=2.00E+02 UNITS INCH.

XR-3 THRUST VS. VELOCITY





Figure 15

X-SCALE=1.00E+01 UNITS INCH.

Y-SCALE=5.00E-01 UNITS INCH.

XR-3 PITCH ANGLE VS. VELOCITY



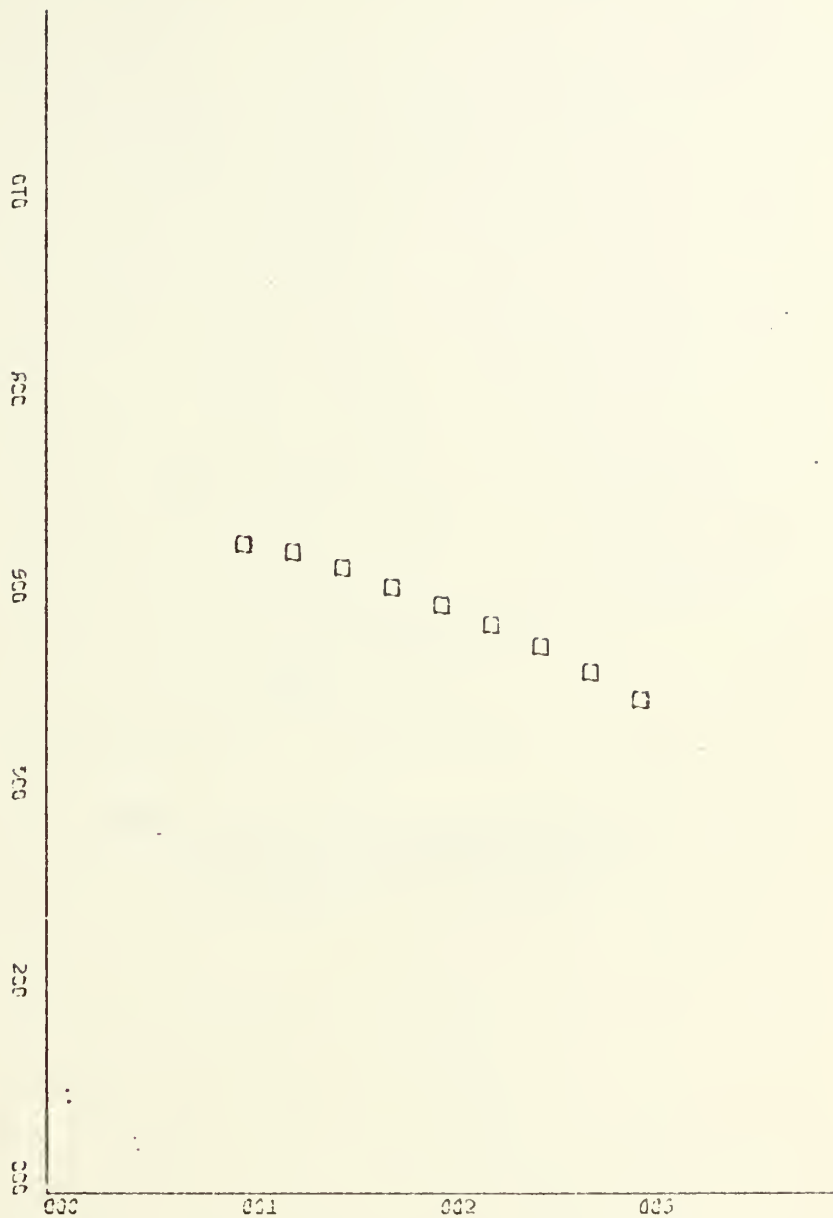


Figure 16

X-SCALE=1.00E+01 UNITS INCH.

Y-SCALE=2.00E+00 UNITS INCH.

XR-3 DRAFT VS. VELOCITY



Figure 17  
THRUST CHANGE: Speed versus Time

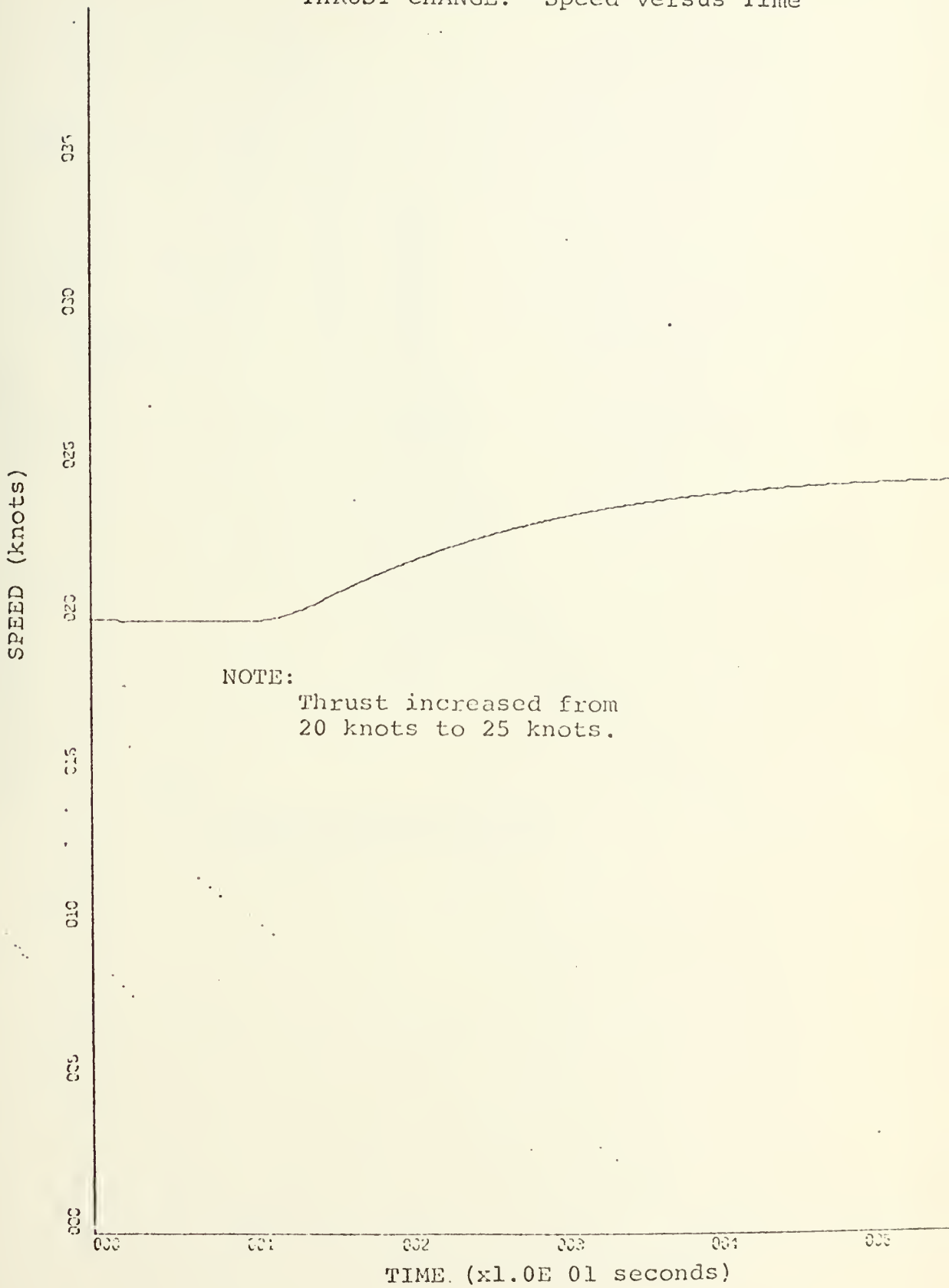






Figure 18

THRUST CHANGE: Pitch Angle Versus Time

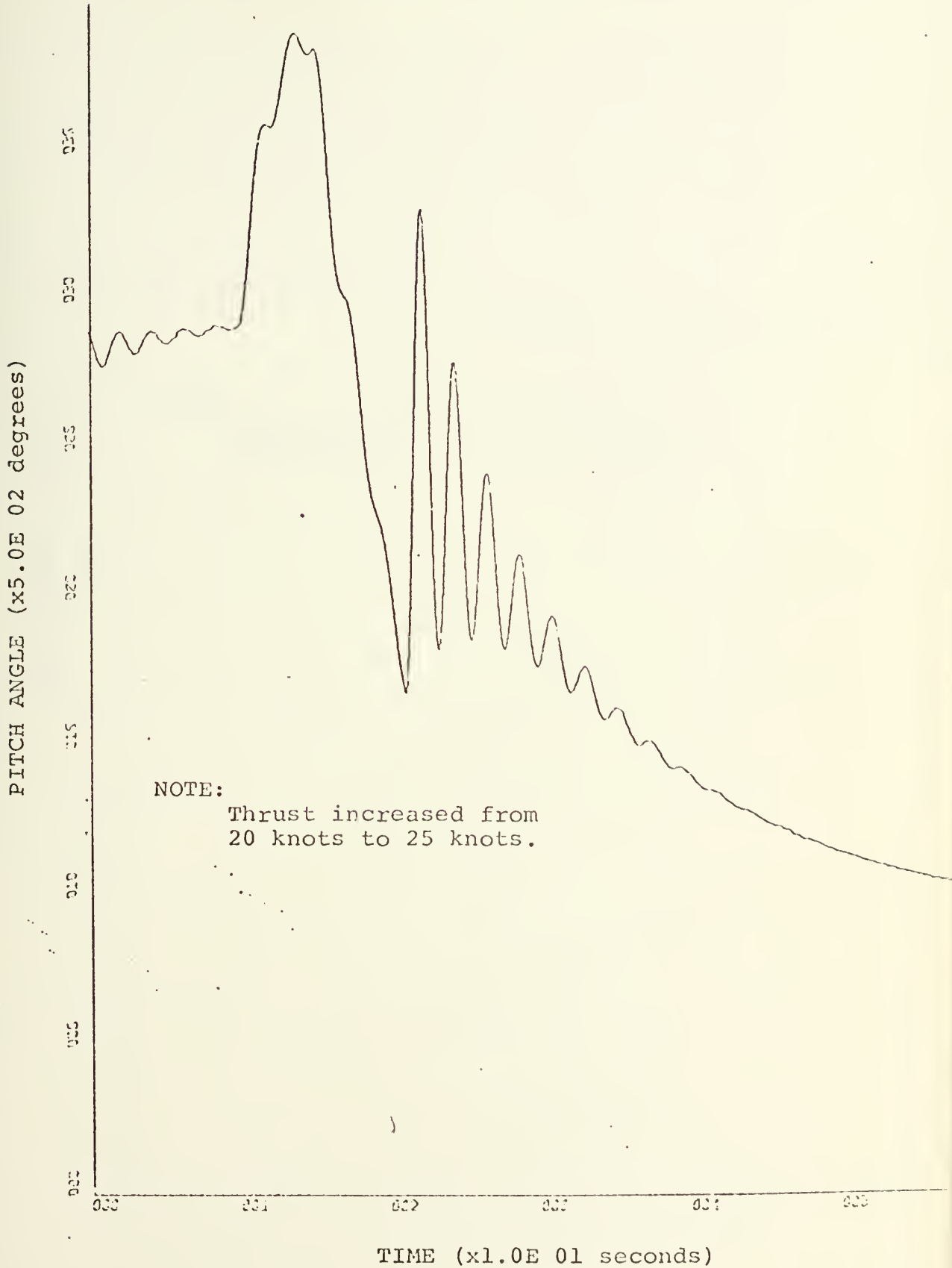
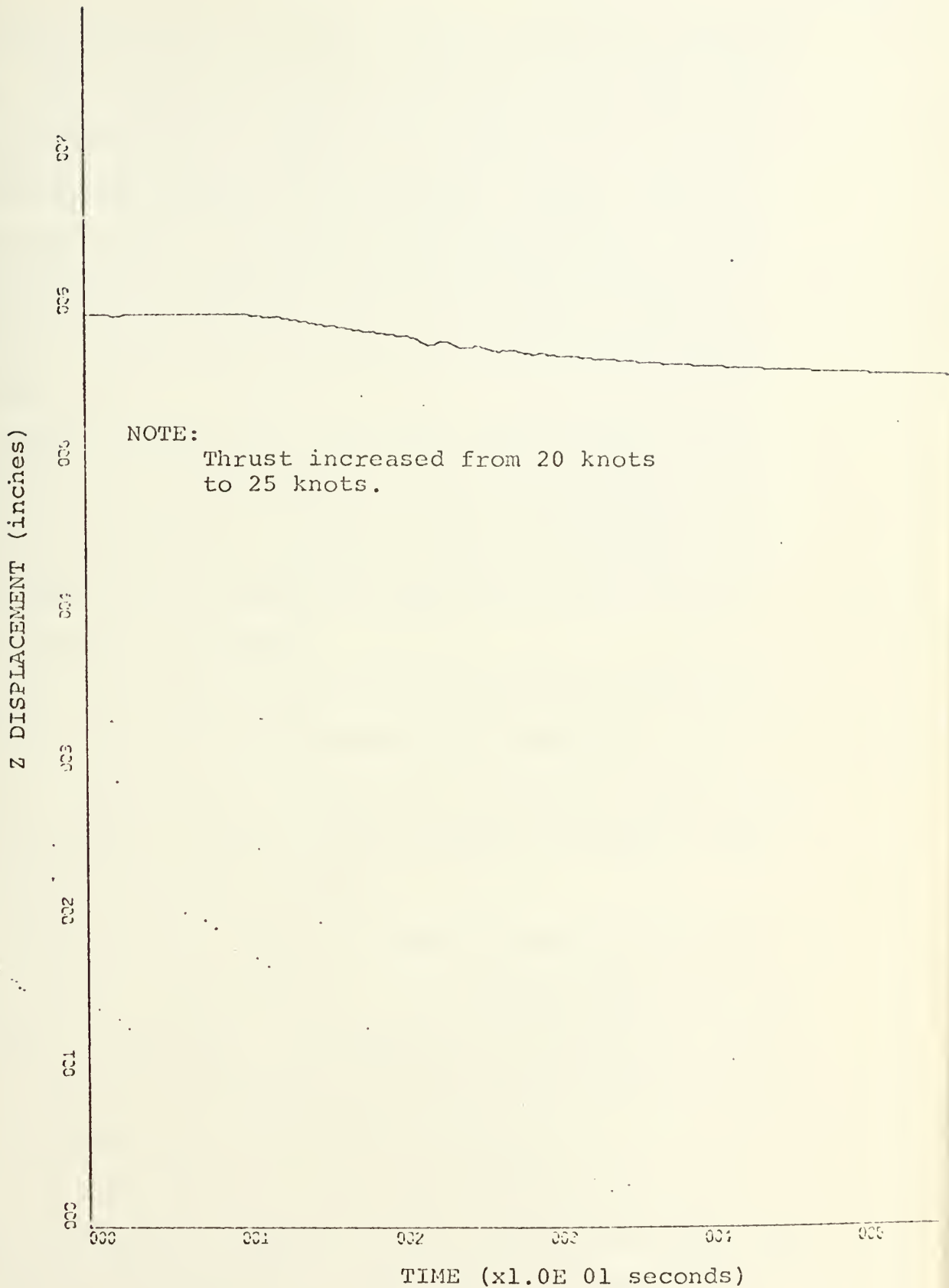




Figure 19  
THRUST CHANGE: Z Displacement versus Time





utilizing the Block 16 variable thrust option of Subroutine INCON. This thrust is applied equally to both screws and is mapped as follows. Thrust for 20 knots is initially applied and maintained for 10 seconds. Between time 10 seconds and time 15 seconds the craft experiences a ramp function of thrust building up to the tabular value for 25 knots. This thrust is maintained for the remainder of the run.

Figure 18 shows that the pitch angle follows the expected curve, in that initially pitch up is experienced as additional thrust is applied. This is followed by gradually dampening oscillations toward the value of pitch angle expected at 25 knots.

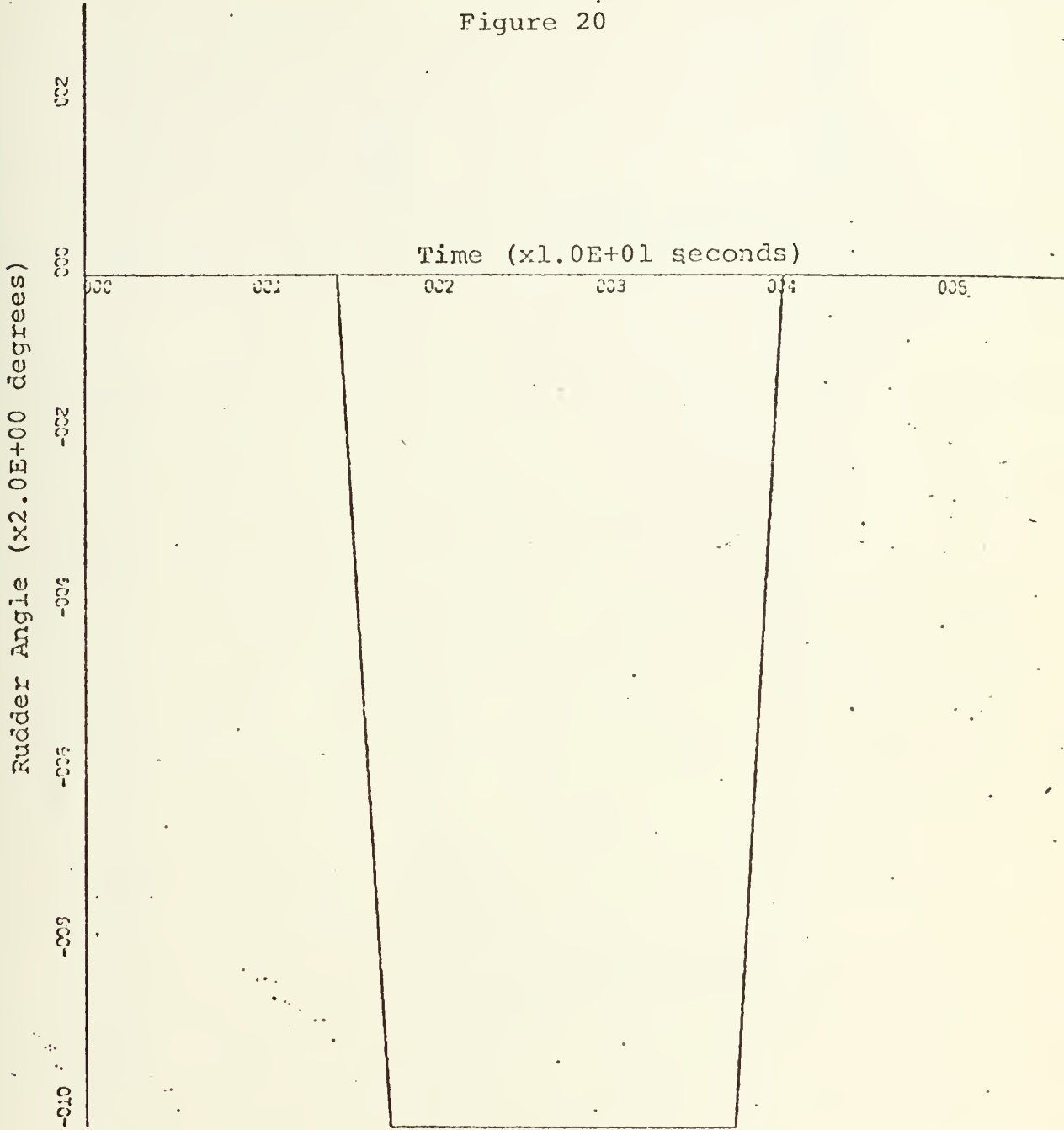
Figures 17 and 19 show that speed through the water increases and that draft decreases, as expected. Additionally, examination of Block 16 of Subroutine INCON makes it clear that the engines may be unevenly thrust rather than equally thrust as shown.

Figures 20, 21, 22 and 23 show the behavior of the program for a turning maneuver. The rudder input vs. time is shown in Figure 20. Corresponding roll angle vs. time, pitch angle vs. time, and the ship horizontal plane motion are in Figures 21, 22 and 23 respectively.

It is interesting to note that the roll and pitch damping coefficients appear to be different during the time the rudder is off centerline than when the rudder is returned to centerline. However, these differences are to



Figure 20



20 Knot Turn: Rudder Angle vs. Time





Figure 21

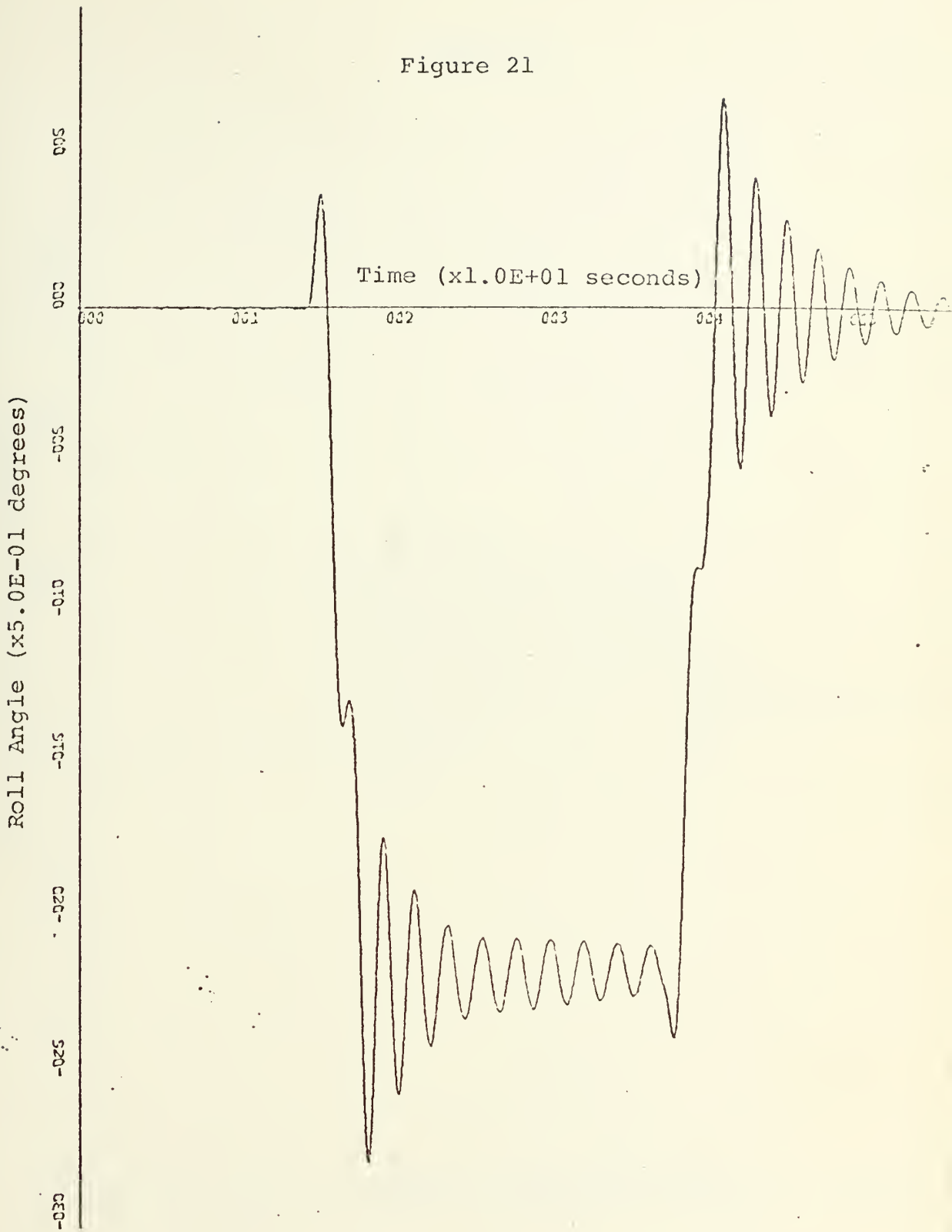
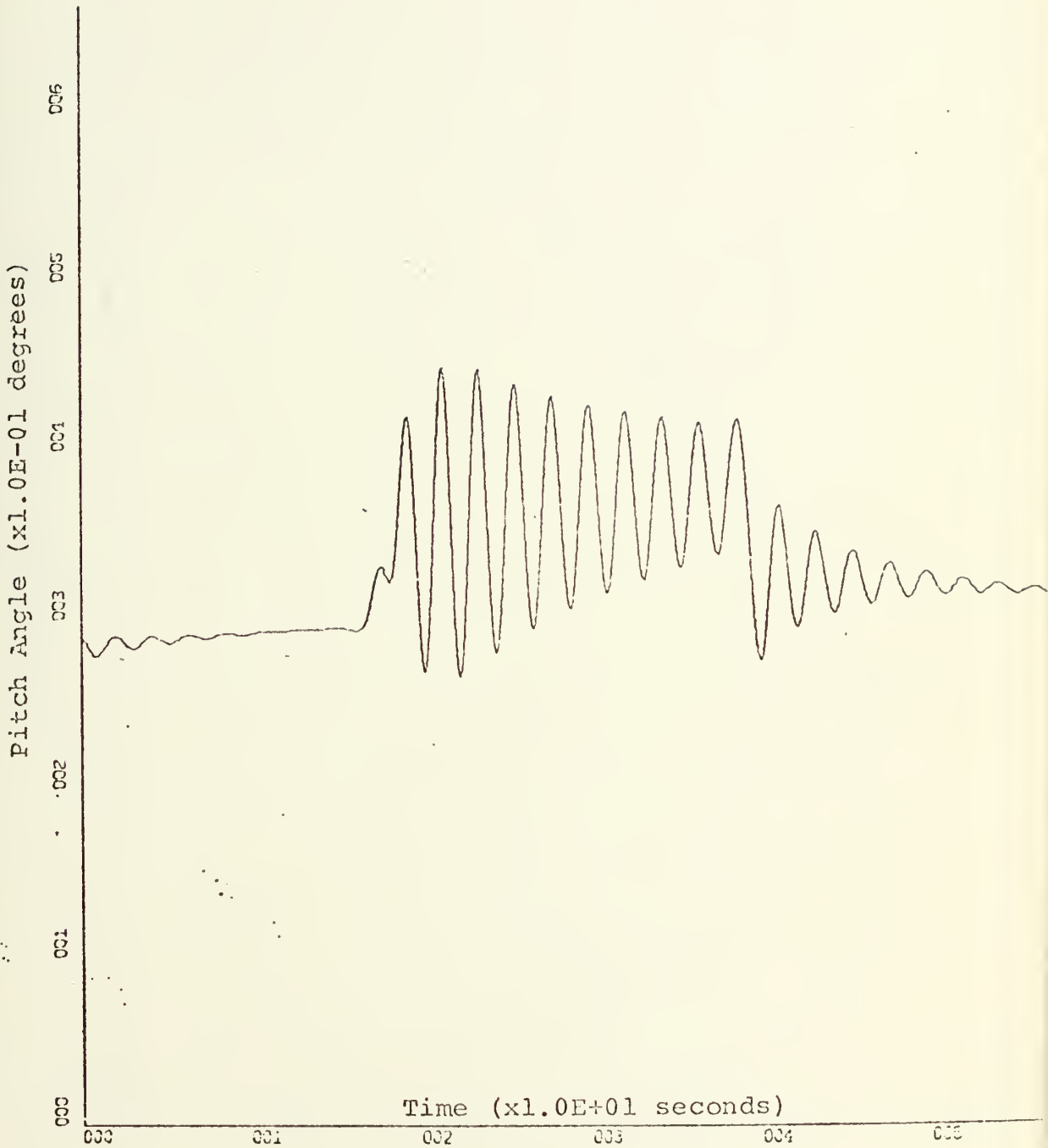


Fig. 20 Knot Turn: Roll Angle vs. Time



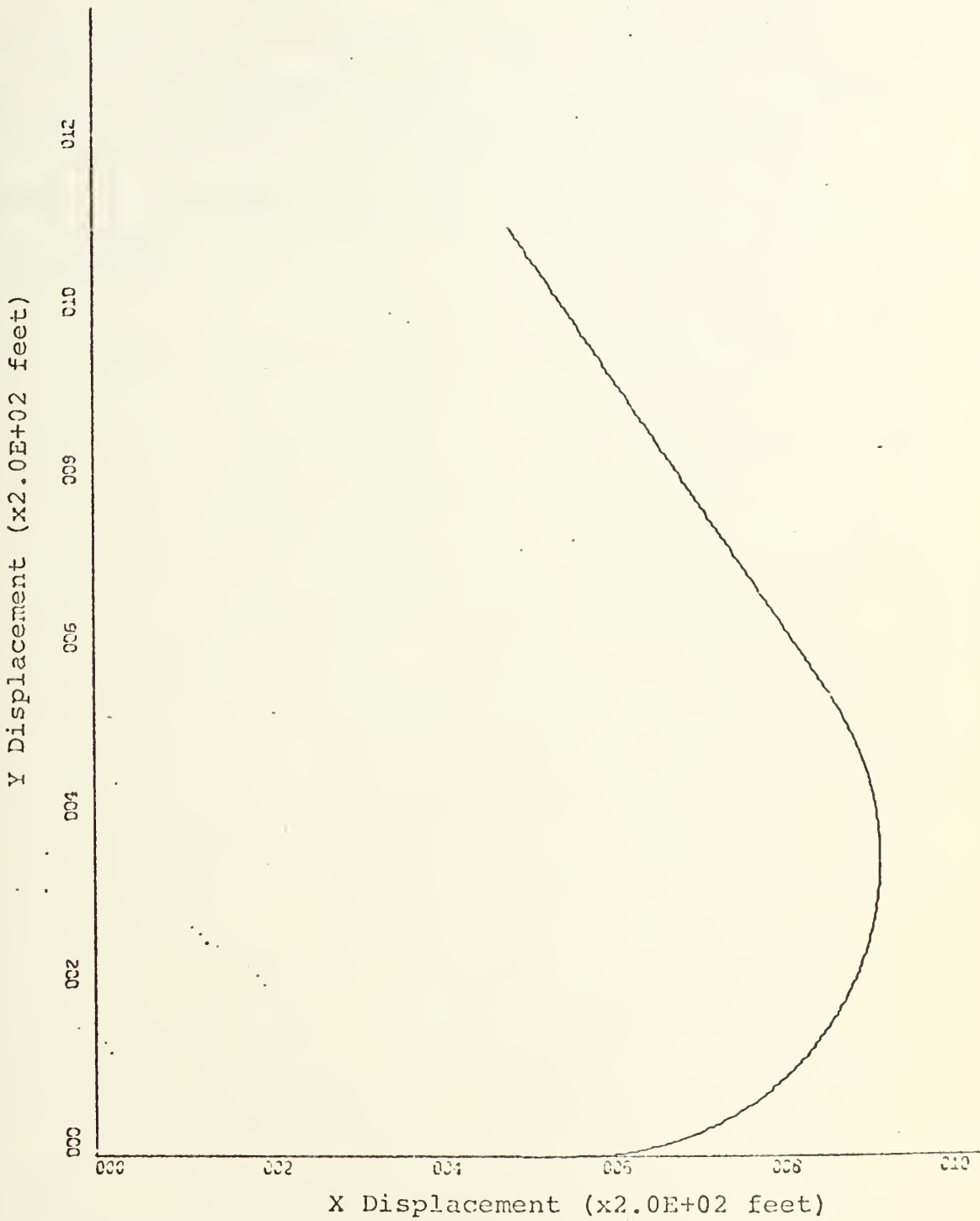
Figure 22



20 Knot Turn: Pitch Angle vs. Time



Figure 23



20 Knot Turn: X Y Displacement



be expected due to the nonlinearity of the system. The oscillation appears to be about  $0.5 \text{ Hz}$ . This oscillation was not felt by the authors during craft test runs. However, it may not be sensed due to its high frequency and small amplitude. Unfortunately at this writing no accurate turn data is available.





## VI. DISCUSSION AND EVALUATION OF SIMULATION RESULTS

### A. DISCUSSION OF PRODUCT MOMENT OF INERTIA; $I_{XZ}$

No information has been available on the value of the product moment of inertia  $I_{XZ}$  for the XR-3. Therefore, throughout the XR-3 program development the moment of inertia  $I_{XZ}$  was set equal to zero. This decision had no effect on craft motions for calm water straight runs since craft motion was restricted to translational movement in the Z and X direction and rotation about the Y axis. However, when turns were attempted and waves off the bow were introduced, program instabilities were observed. These may be seen by referring to Figures 24, 25 and 26 which show that for small perturbations the craft reacts in a stable manner, but as the rudder angle increases toward 20 degrees the craft becomes unstable even though waves have not yet been introduced. A weight scaled value of  $I_{XZ}$  was obtained from the 100B input data set and was later used as a representative value for the XR-3.

### B. 5 DEGREE TURNS WITH AND WITHOUT WAVES

In an attempt to verify conditions reported in Reference 8 for the 100B model, a 20 knot run with a 5 degree rudder turn with and without waves was introduced. The wavelength and wave height were scaled from Reference 8 according to relative craft size. Hence, a wavelength of 72 feet and a wave height of 0.16 feet were used with the XR-3 model. Wave amplitude and frequency of encounter are shown in Figure 29.



Figure 24  
FIVE, FIFTEEN AND TWENTY DEGREE TURNS:  
Roll Angle Versus Time,  $I_{xz}$  equal to zero

1. 20 degree rudder
2. 15 degree rudder
3. 5 degree rudder

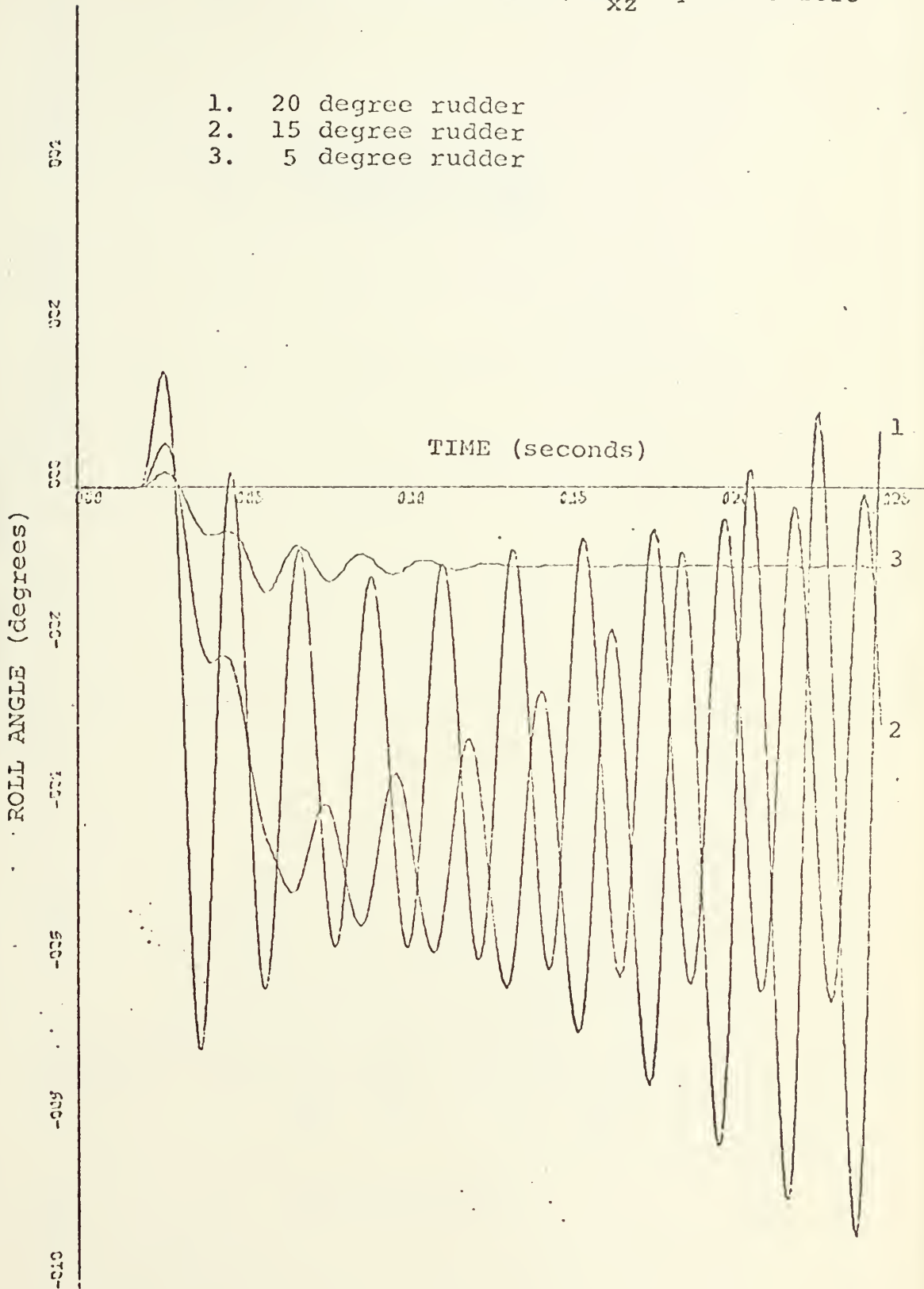




Figure 25  
FIVE, FIFTEEN AND 20 KNOT TURNS:  
Pitch Angle versus Time,  $I_{xz}$  equal to zero

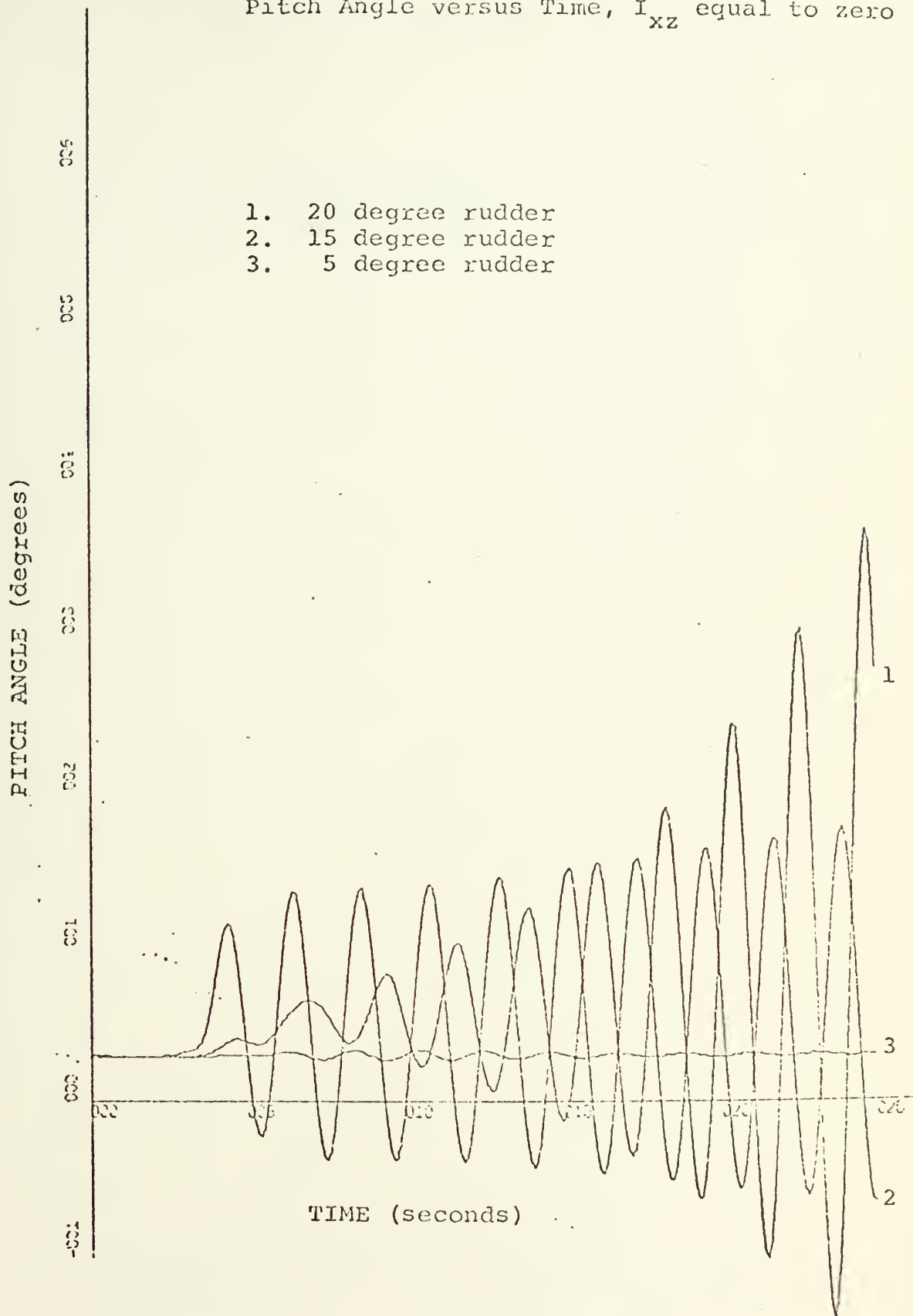
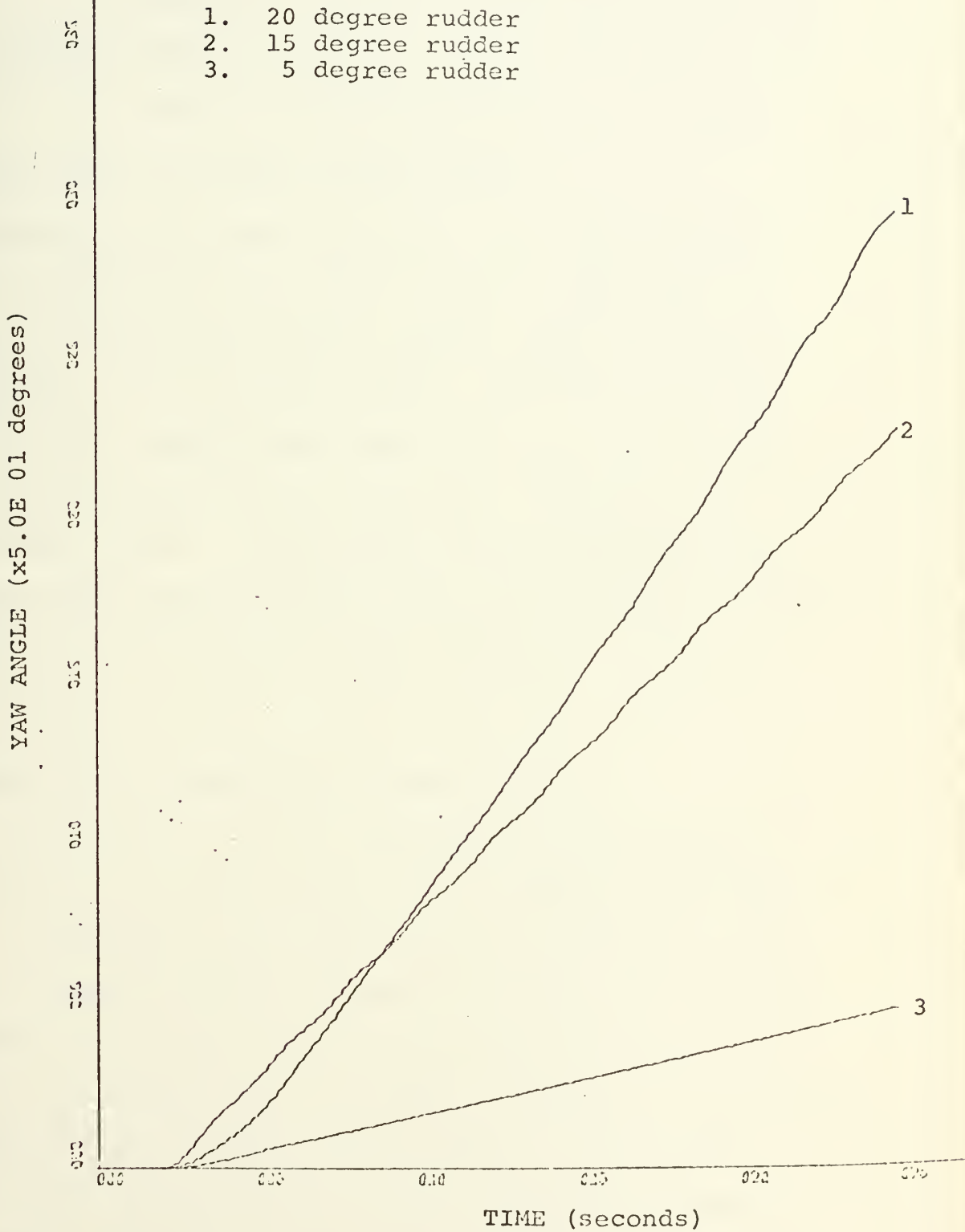




Figure 26

FIVE, FIFTEEN AND TWENTY DEGREE TURNS:  
Yaw Angle versus Time,  $I_{xz}$  equal to zero







It is interesting to note that this same frequency can be seen in roll angle and pitch angle as shown in Figures 27 and 28. It is observed in Figure 27 that the amplitude of roll increases almost linearly as the wave front moves away from the ship's head, as would be expected for beam seas.

#### C. TURNS WITH 5, 15 AND 20 DEGREE RUDDER

Figures 31, 32, and 33 show the roll, pitch, and yaw motions produced by 5, 15, and 20 degree rudder turns at 20 knots in calm water with the product moment of inertia  $I_{XZ}$  inserted. In all cases, damping and system stability were observed. Similar turns made with  $I_{XZ}$  equal to zero revealed the presence of roll and pitch instability for large rudder angles. In both cases where 5 degree rudder turns were made the variations in the roll and pitch angles remained small and decayed to zero within 15 seconds or about 5 cycles.

#### D. COMPARISON OF SIMULATION AND MEASURED DATA

At the time of this writing measured pitch and roll data was not in a form suitable for definitive comparisons. However, recorded data of testcraft motion during turn maneuvers as shown in Figure 34 tend to validate the presence of damped roll and pitch oscillations which are also present in the simulated turns as shown in Figures 31, 32 and 33.

Measured and recorded plenum pressures tend to correspond with those calculated by the simulation program. This pressure appears to vary between 24-25 pounds per square



Figure 27  
FIVE DEGREE TURN: Roll Angle Versus Time

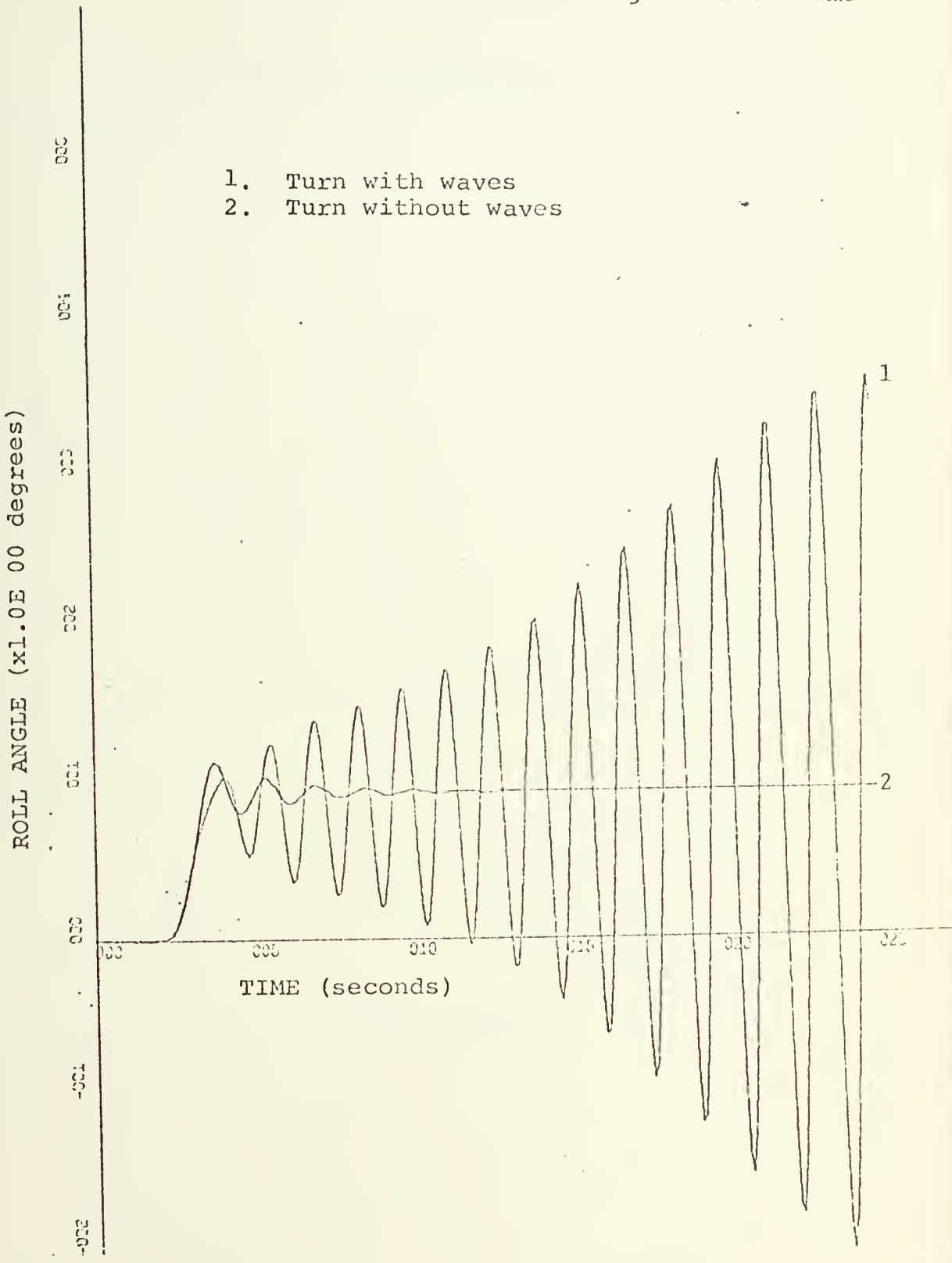




Figure 28

FIVE DEGREE TURN: Pitch Angle versus Time with and without waves

- 1. Turn with waves
- 2. Turn without waves

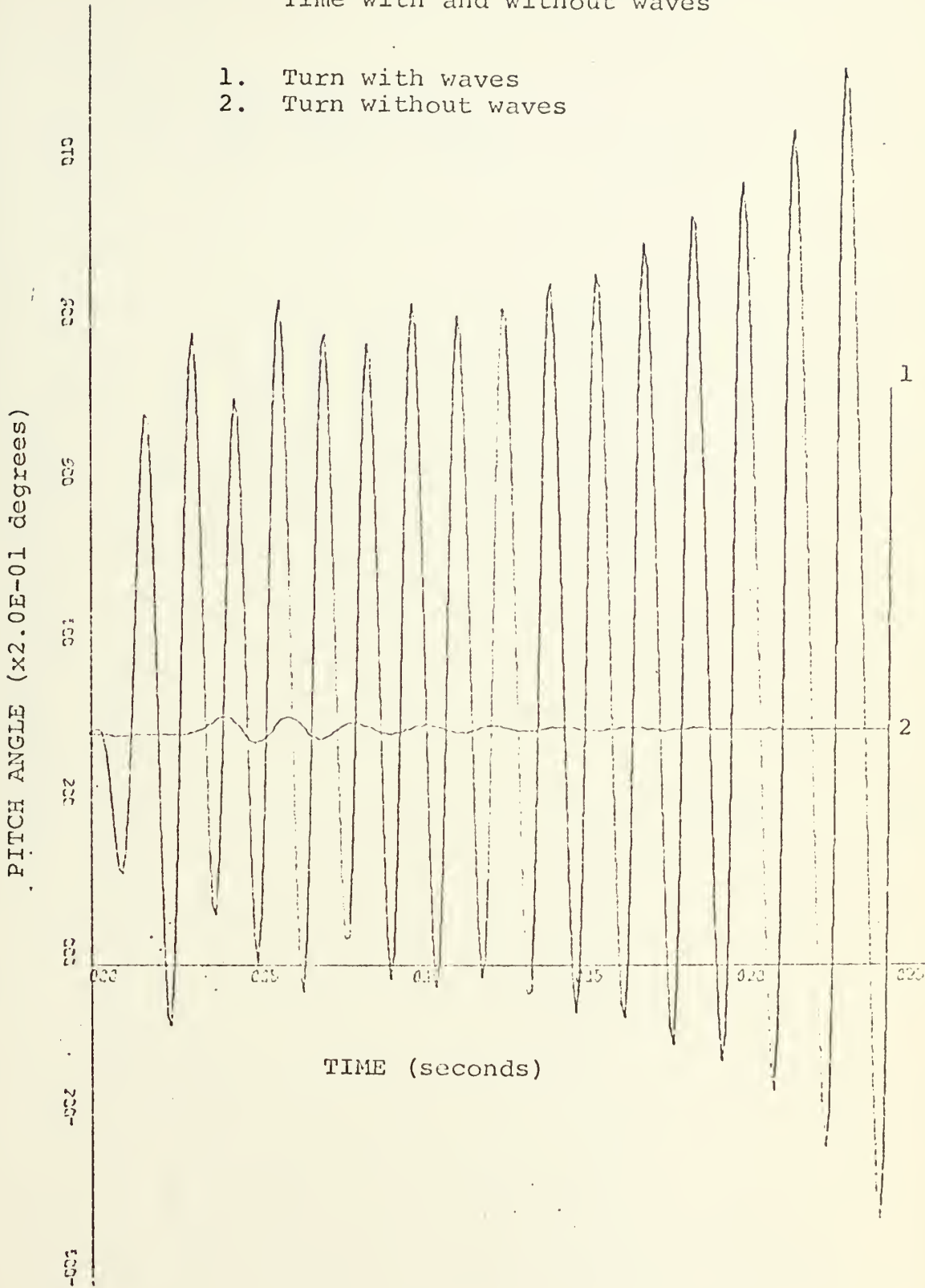




Figure 29  
FIVE DEGREE TURNS: Wave Height versus Time

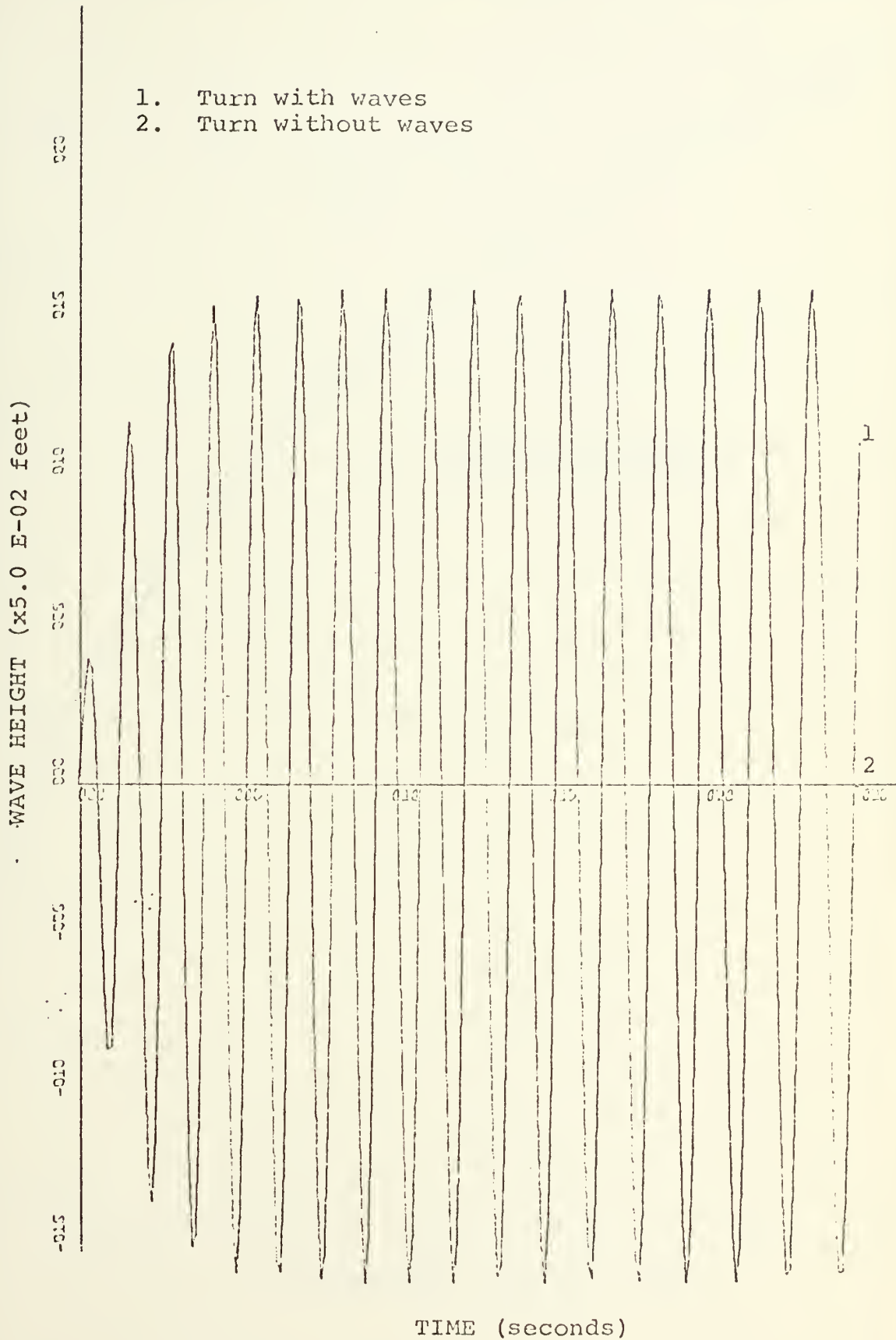






Figure 30

FIVE DEGREE TURN: X Displacement Versus Y Displacement

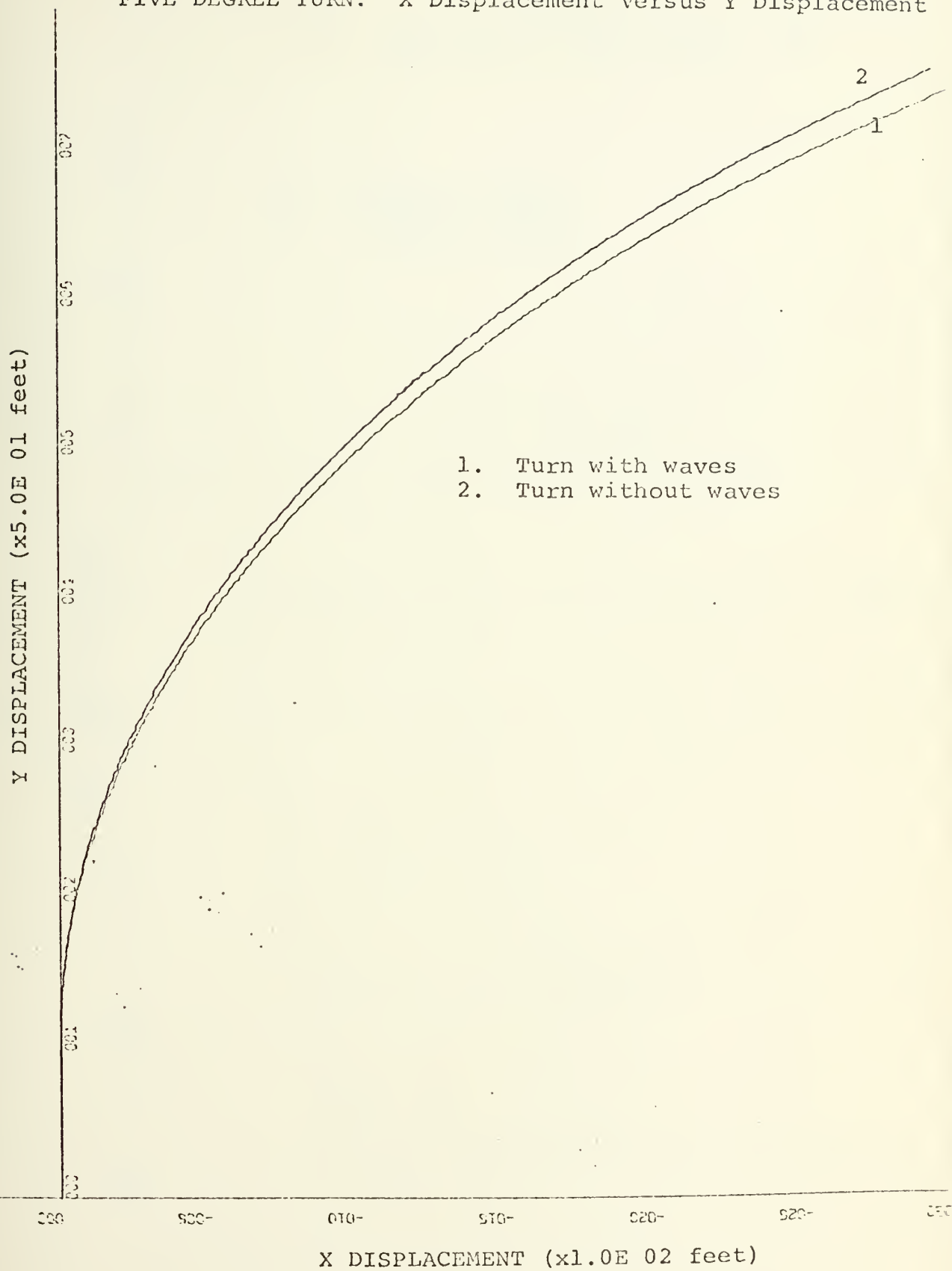




Figure 31

FIVE, FIFTEEN AND TWENTY DEGREE TURNS:  
Roll Angle versus Time

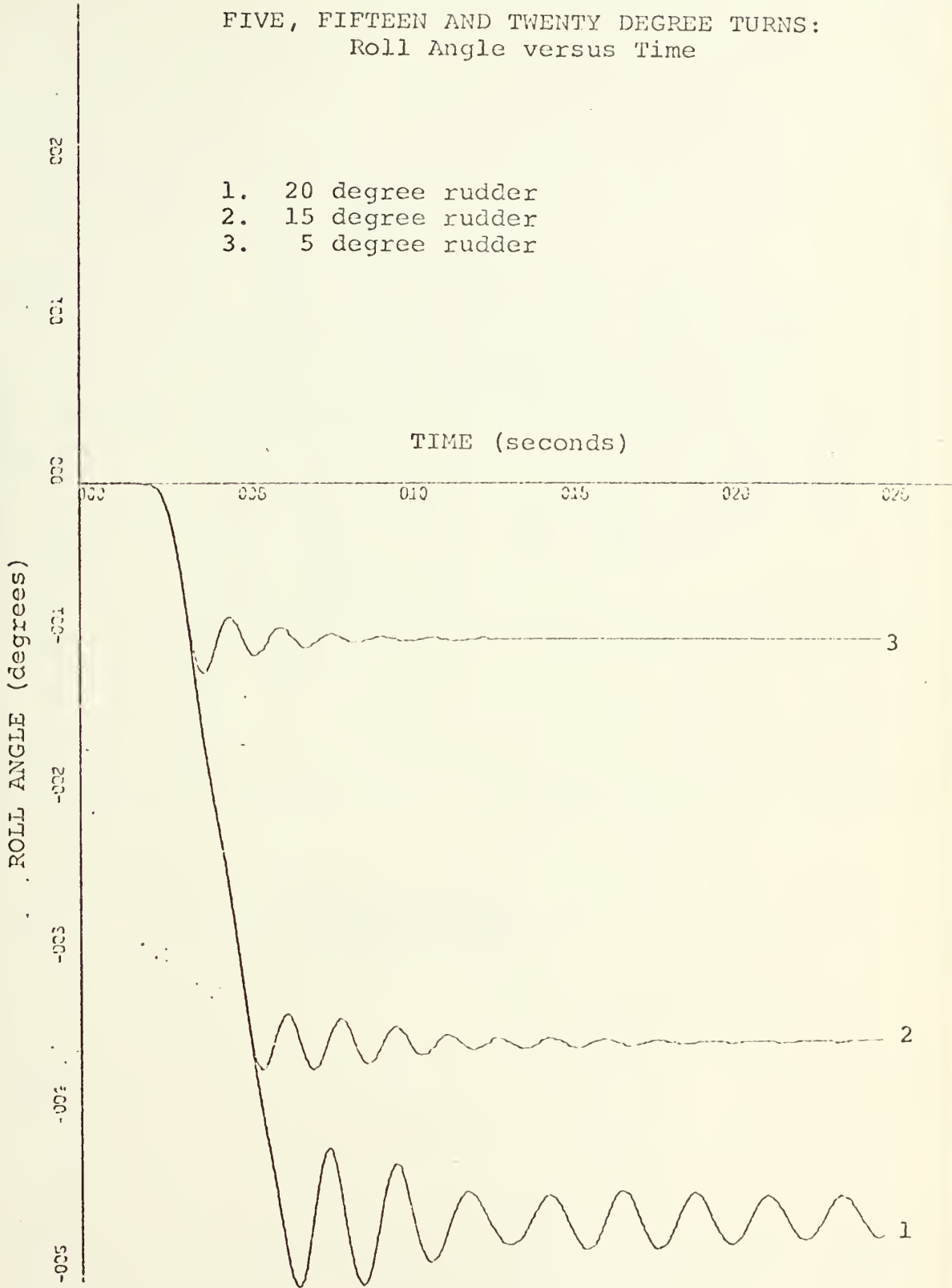




Figure 32  
FIVE, FIFTEEN AND TWENTY DEGREE TURNS:  
Pitch Angle Versus Time

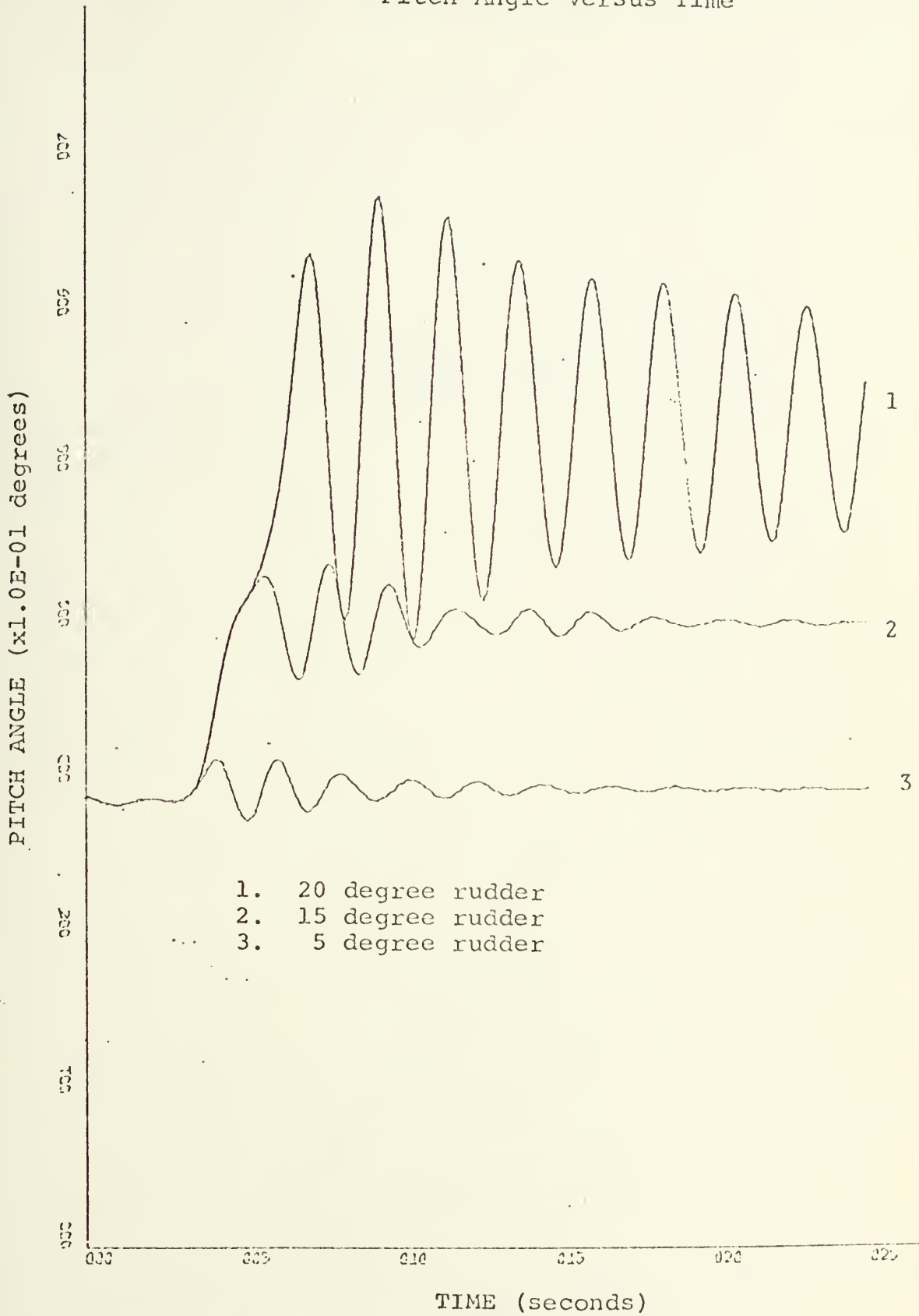
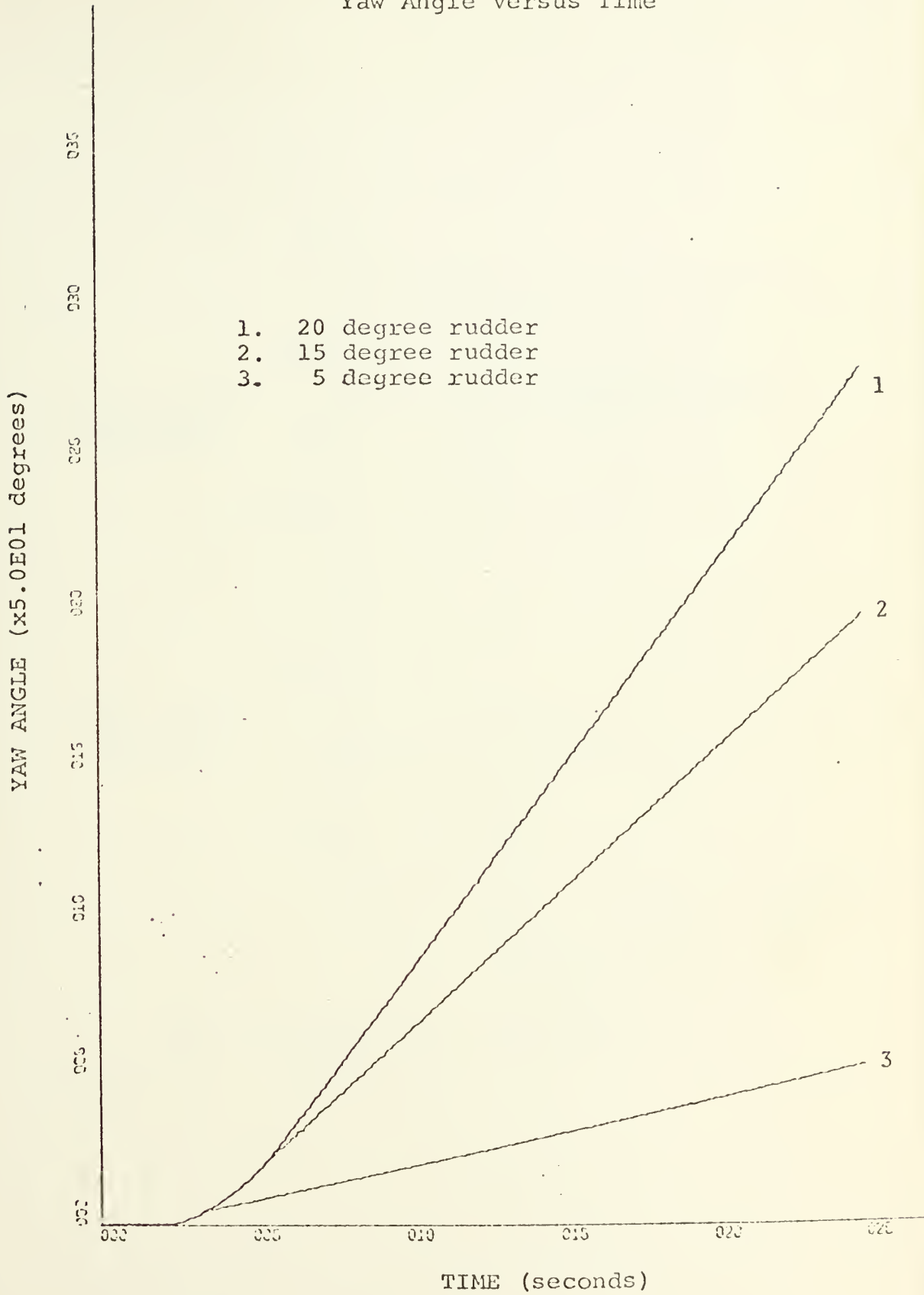




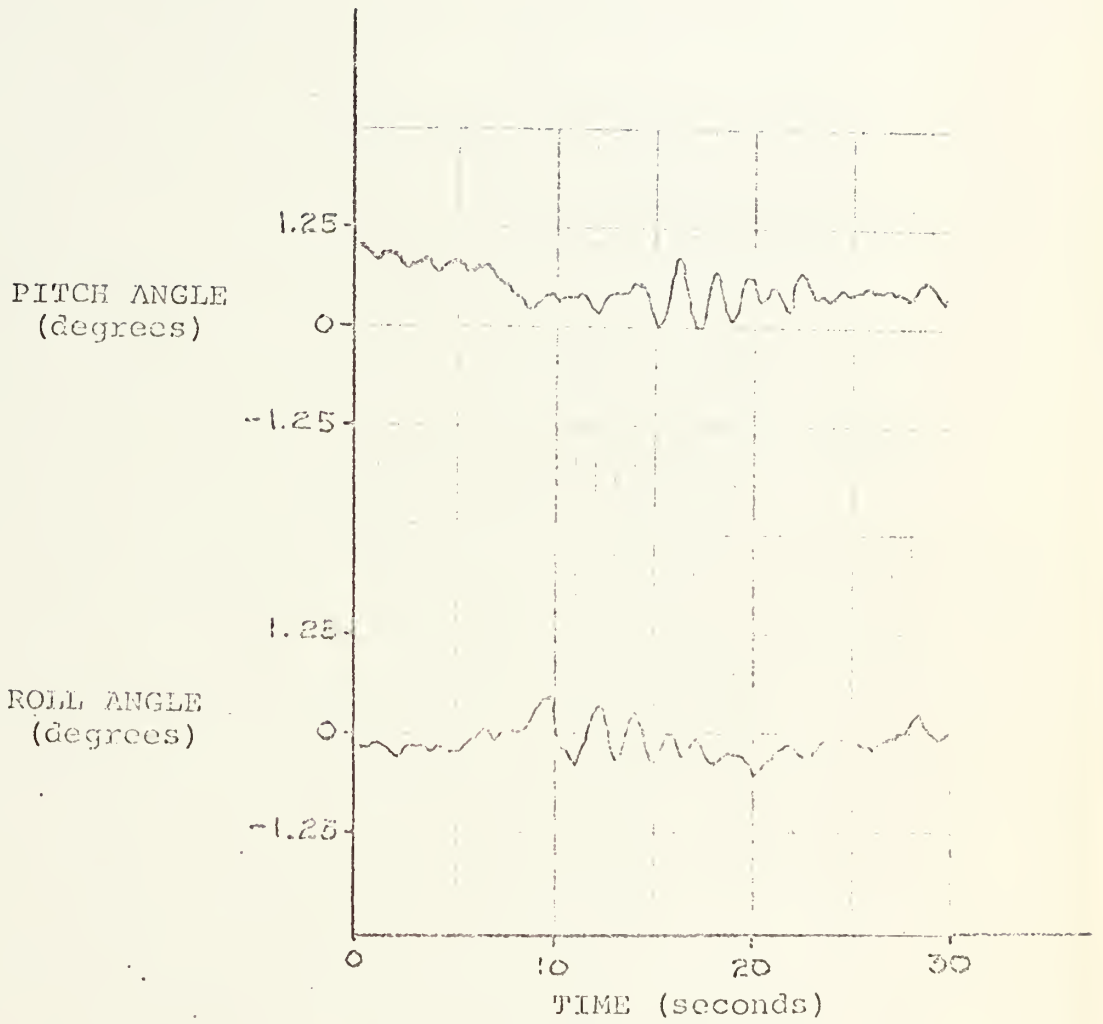
Figure 33

FIVE, FIFTEEN AND TWENTY DEGREE TURNS:  
Yaw Angle Versus Time









PITCH AND ROLL ANGLE: Measured data  
Figure 34



foot throughout all the various monitored craft motions.



## VII. CONCLUSIONS AND RECOMMENDATIONS

The conversion of the L&M program from the 100B model to the smaller XR-3 model involved considerably more time and effort than was anticipated at the onset. A great deal of time was required for familiarization with the program, for providing a more useful output format and for adding plotting routines. Considerable effort was required to obtain the straight run, calm water trim conditions for various speeds. Plenum center of pressure movement with velocity was one of the more difficult problems encountered in obtaining the proper initial trim conditions. It is recommended that future investigators write an initial condition program to assist in reducing the time and effort required to arrive at the proper trim conditions.

Good agreement between measured and computed data for calm water straight runs was possible by the adjustment of the bubble drag coefficients, draft, bubble pressure and stern seal leakage. The measurement data for turning maneuvers could not be used for a check on the simulation in the form in which it is presently recorded. It is recommended that the recorded data be processed digitally and suitably reduced to a form useful for comparison with the L&M program output. Qualitative comparison of the XR-3 turn maneuver data however, has indicated that pitch and roll motion have a lightly damped response quite similar to the L&M program output. Much work remains to be done in checking



the accuracy of the computed transient response.

Additional qualitative checks were made on the computed XR-3 turn maneuvers by comparison with the 100B model response. The results indicated similar transient characteristics in which damping decreases as pitch or roll angle increase.

The simulation study of the XR-3 has demonstrated the importance of the product moment of inertia  $I_{XZ}$  in maintaining stability in roll and pitch for rudder angles greater than 5 degrees. Future investigators should attempt to obtain an accurate value for  $I_{XZ}$ . This can be done by utilizing the discrete mass distribution option in the INCON Subroutine.





APPENDIX A

SES MOTIONS AND LOADS PROGRAM

USERS MANUAL



SES MOTIONS AND LOADS PROGRAM

USERS MANUAL

by

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Oceanics Incorporated

with modifications by

LCDR Don G. Leo and LT Richard Boncal U. S. Navy



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Discussion





## INTRODUCTION

The SES Motions and Loads Program is a Fortran IV program capable of calculating the time histories of the motions and loads of a surface effect ship operating in the on bubble mode in a seaway in six degrees of freedom. It is programmed in a "modular" fashion, i.e. each major element of the craft has its own subprogram. The input is in the form of basic data, i.e. sidewall offsets, seal geometry, fan map data points, etc. and enables the user to make a wide range of parametric changes to the particular craft being modeled by changing only the input data. The program has the capability of printing and/or plotting a wide range of variables as a function of time; such as forces and moments from each element, total craft forces, moments and accelerations, leakage gaps and flow rates, fan flow rates and power required, etc. The current program has been checked out and run on an IBM 360 computer (using version Release 20.6.) at the W. R. Church Computer Facility, NPS, Monterey, Ca.

This report is intended to be primarily a users manual for the program as it exists. The details of how one would rewrite various modules to reflect changes in the craft design are discussed extensively in Appendix A-A.



## PROGRAM ORGANIZATION

Within a given run the program proceeds as follows. First the main program calls the input and initialization subroutine INCON. The program then proceeds to calculate the motion time histories by calling the various modular subroutines and the integration routine for as many time steps as is necessary to complete the run. During the course of the calculation the various subroutines will output those variables selected by the print option switches at the appropriate input print interval. In addition, data may be written on scratch files to be used for summarizing the output and doing bending moments and shear calculations. At the present time the Shears and Moments Subroutine has been removed, however, it may be reintroduced at any time with a minimum of changes.

When the run is completed, the program, depending on the options chosen, may then print and/or plot the output summary and proceed to do the bending moment and shear calculations. After these steps are completed the main program returns to INCON to read data for the next case.

The above procedure is repeated until all cases are finished.



## PROGRAM REQUIREMENTS

As run on an IBM 360 computer under OS/360MVT version (Release 20.6), the program requirements are as follows;

	<u>TOTAL CORE</u>	<u>TIME</u>
Program length	201,456 <sub>10</sub>	NA
Core size required for execution	250,000 <sub>10</sub>	SEE BELOW

The total core required for a given step includes the program, system routines, data storage, etc. The time required to run a single case depends on the nature of the case and the length of time to be simulated. The ratio of required execution time to real time has been found to be as low as 1/3 for some calm water cases. Higher ratios occur where the transient curves are rather sharp.

The program currently uses the following FORTRAN Data Set Reference Numbers (Unit Numbers):

<u>Unit Number</u>	<u>Usage</u>
1	Scratch file for COLFIL plotting package.
2	Scratch file for lateral plane output summary
5	Input
6	Output
10-15	Sidewall Integral Table data (see Appendix A-C)



IBMF           Intermediate file containing time histories  
                  required by bending moment calculations. The  
                  unit number IBMF is read in using the 01501  
                  input card (see discussion of Input)

#### INPUT AND OUTPUT

The input for the program is handled by subroutine INCON  
and is discussed there. The output is controlled by the  
individual subprograms and is discussed separately there.





DESCRIPTION OF SUBPROGRAMS



## Main Program

Discussion - The main program contains the logic for interconnecting the various subroutines. In addition, it compares the running value of time with the finish time, calculates the next value of time for printing after each print time, does some output, etc. The main program also contains the logic for the integration of the trajectory  $(x, y, \psi)$  by the trapazoidal rule.

Input - None

Output - The output from the main program is controlled by the print option switch ITRAJ. If the value of this switch is 1, the program will print the current values of the time and the craft velocities and displacements (angular and translational) as shown in the sample output at the end of the report.



## Subroutine AEROD

Discussion - Subroutine AEROD calculates the aerodynamic forces and moments on the craft. The subroutine currently uses curve fits of the aerodynamic coefficients vs sideslip angle. Appendix A-A discusses how the program may be changed to input tabular data for the aerodynamic coefficients.

Usage - CALL AEROD

Input - The input data for AEROD is controlled by block 10 of subroutine INCON and is discussed there.

Output - The output from AEROD is controlled by print option switch IAEROD. If this switch is 1, the program will print the total forces and moments calculated as shown in the sample output at the end of the report.



## Subroutine BOWSL

Discussion - Subroutine BOWSL calculates the forces and moments due to the bow seal and the leakage flow rate associated with any gaps which open up under the various seal stations.

Usage - CALL BOWSL

Input - The input data for BOWSL is controlled by blocks 3, 6, and 17 of subroutine INCON and is discussed there.

Output - The output from BOWSL is controlled by print option switch IBOWSL. If this switch is 1, the program will print the gaps and wetted lengths at the various stations on the bowseal as well as the total forces and moments due to the bowseal. A sample print point is given in the sample output at the end of the report.





## Subroutine COLFIL

Discussion - Subroutine COLFIL is used to format the program output. It can provide up to 16 variables listed in two tabular summaries of 8 variables each. The subroutine has a plotting package that permits use of either the print plot or calcomp (continuous line) option. Multiple curves may be plotted and up to 10 graphs may be drawn on each run. Print switches control the printing by each subroutine of its forces and moments. This option is very useful in debugging the program. Normally it provides too much output and is too cumbersome.

Usage - CALL COLFIL

Input - The input is controlled by the control card with the control tag 00104 and is discussed in the description of Subroutine INCON in the block 1 control card section. Additional input required for the plotting package is contained in the Users Manual for the COLFIL routine.

Output - For output format consult the COLFIL plotting package users manual.



## Subroutine DMINV

Discussion - Subroutine DMINV is a matrix inversion package used for inverting the mass matrix. The method used is the standard Gauss-Jordan technique. The determinant of the matrix is also calculated. If the determinant is zero the matrix is singular and the program will stop (see Appendix A-B Abnormal Termination Messages).

Usage - CALL DMINV (A, N, D)

### Description of Parameters

A = The input matrix, destroyed in computation and replaced by resultant inverse

N = The order of matrix (maximum = 6)

D = The resultant determinant of the matrix

Input - None

Output - None



## Subroutine FAN

Discussion - Subroutine FAN is used to calculate the inflow to the plenum, stern seal, and bowseal from the fans for a given pressure differential across the fans. The subroutine uses tabular data and allows for changes in fan speed as well as the number of fans. Fan speed changes are currently handled by using the fan scaling laws rather than reading data as a function of fan speed.

Usage - CALL FAN

Input - The input for subroutine FAN is controlled by block 19 of subroutine INCON and is discussed there.

Output - The output from FAN is controlled by print option switch IVEL. If this switch is 1, the program will print the flow rates and pressure differentials across the bow seal, cushion and stern seal fans, as well as the total fan horsepower required as shown in the sample output at the end of the report.



## Function FGL

Discussion - The purpose of FGL is to perform the task of evaluating a tabular function  $y = f(x)$ . The procedure used is linear interpolation between data points. If the input value of the independent variable does not fall in the range of its input tabular values the appropriate table extreme is held. The function  $y$  must be single valued and the tabular values for the independent variable must be stored in ascending order i.e.  $XTAB(J)$ ,  $XTAB(J+1)$ . The increment between tabular values need not be constant.

Usage -  $Y = FGL (X, N, XTAB, YTAB, IMEM)$

### Description of Parameters

Y = The output value of the tabular function

X = The value of the independent variable to be used to evaluate the function  $y = f(x)$

N = The number of elements in the XTAB and YTAB arrays

XTAB = The name of the array that contains the values of the independent variable in ascending order

YTAB = The name of the array that contains the values of the dependent variable corresponding to the values of the independent variable stored in XTAB

IMEM = Dummy variable used to store location of last entry into table, to be used as initial point of search at next entry

Input - None

Output - None





## Subroutine FORIT

Discussion - Subroutine FORIT is used to obtain a Fourier analysis of a periodically tabulated function. It computes the coefficients of the desired number of terms of the Fourier series  $f(x) = a(0) + \sum_{k=1}^M (a(k)\cos kx + b(k)\sin kx)$ , to approximate the given set of periodically tabulated values of a function.

Usage - CALL FORIT (FNT, N, M, A, B, IER)

### Description of Parameters

FNT = Vector of tabulated function values of length  $2N+1$

N = The interval such that  $2N+1$  points are taken over the interval  $(0, 2\pi)$ . The spacing is thus  $2\pi/(2N+1)$ .

N must be greater than or equal to M

M = Maximum order of harmonics to be fitted. M must be greater than or equal to zero

A = Resultant vector of Fourier cosine coefficients

B = Resultant vector of Fourier sine coefficients

IER = Resultant error code where:

IER=0 No error

IER=1 N less than M

IER=2 M less than 0

Input - None

Output - None



## Subroutine INCON

Discussion - Subroutine INCON contains the logic for the reading of all input data, the initialization of variables and for the initiation of new cases. The subroutine is programmed so that the input data is non-structured i.e. there is no set order of input cards from one read statement to another. However, a given read statement may have more than one input card. In runs with multiple cases, only those input parameters which are to be changed for the new case need be read in.

Usage - CALL INCON

Input - The input logic is subdivided into twenty-two "blocks." Each block being for a particular subroutine or function e.g. stern seal, sidewall, etc. Switching to the proper input block is done by means of a control tag on the input cards. Once control has been transferred to a particular block additional input may be read by specific format statements if necessary, however, the card which contains the control tag may also be used to input up to seven variables for the selected block. The format of the input card used for switching is as follows:

<u>Column</u>	<u>Format</u>	<u>Entry</u>
1-3	I3	control tag
4-5	I2	option tag
6-75	7F10	input variables (if any)



The control tag used to transfer control to the appropriate block is of the form OMN where M and N are integer constants, i.e., if the control tag is 015 the program will go to statement 1500.

The option tag is loaded into a variable called IOPT and allows different branches of logic within a given input block. If no branches are used within the input block the option tag may be zero.

The input variables are stored in an array called TEMP and may be set to a given parameter by using an arithmetic replacement statement in the appropriate block (see various blocks in attached listing for examples).

Example: When read, a card of the form

Column	3	5	15	25	35	80
	↓	↓	↓	↓	↓	↓
	017	02	3.5	blank	1.0	blank

will transfer control to statement 1700. Within statement 1700 the logic might look as follows

```
1700 CONTINUE
      GO TO (1710, 1720), IOPT
1710 A = TEMP (1)
      B = TEMP (2)
      GO TO 10
1720 C = TEMP (1)
      D = TEMP (2)
      E = TEMP (3)
      GO TO 10
```



In the above example the option switch IOPT is 02 and will cause the program to go to statement 1720 which will then set  $C=3.5$ ,  $D=0.0$ ,  $E=1.0$  and then will return to statement 10 which is the read statement for the input cards.

The various input blocks as currently programmed are as follows:

<u>Block Number</u>	<u>Function</u>
1	Executive input (time steps, print switches, option switches, etc.)
2	Mass and inertial input
3	Craft geometric input
4	Sidewall input
5	Stern seal input
6	Bow seal input
7	Plenum input
8	Propulsion geometry input
9	Rudder input
10	Aerodynamic input
11	Wave input
12	Initial conditions
13	End of case indicator
14	End of run indicator
15	Not used
16	Thrust, rudder motion input
17	Bow and stern seal pressure input
18	Title card
19	Fan map input





<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00101 - control tag and option
	6-15	F	Start time (generally zero), sec.
	16-25	F	Finish time, sec.
	26-35	F	Initial integration time step, sec.
	36-45	F	Print interval, sec.
	46-55	F	Print start time, sec.

Option tag = 2      Print switches (if=1 print if=0 no print)

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00102 - control tag and option
2	5	I	IACCEL, print switch for lateral acceleration and integration time step
	10	I	IVEL, print switch for subroutine FAN
	15	I	ITRAJ, print switch for main program
	20	I	ISIDWL, print switch for subroutine SIDEWL
	25	I	IBOWSL, print switch for subroutine BOWSL
	30	I	ISTNSL, print switch for subroutine STNSL
	35	I	IWAVES, print switch for subroutine WAVES
	40	I	IRUD, print switch for subroutine RUDDER



Option tag = 2 (Continued)

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
2 (Cont.)	45	I	IPROP, print switch for sub- routine PROP
	50	I	IAEROD, print switch for sub- routine AEROD
	55	I	IRHS, print switch for subroutine RHS

Option tag = 3 Integrator Tolerances

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00103, control tag and option
2	1-2	I2	Number of integrators to be used (maximum of 15)
	3-4	I2	Control tag for integration pro- cedure
3, 4...	1-80	8F10	Integrator error tolerance, one per integrator

Note: The usual procedure for selecting integrator tolerances is to choose values on the order of  $10^{-5}$  to  $10^{-8}$ . However, for each new craft the following procedure is used; make a run with a given set of tolerances; halve the tolerances and rerun. If the results do not change drastically, try doubling the original tolerances and running. As changes are noted in the integrator outputs (i.e. craft velocities, etc.), hold the tolerances for those integrators fixed and vary the others until the largest tolerances possible are obtained. Once



chosen for a given craft the tolerances rarely have to be changed. A control tag (JQQ in the program) is used to select integration procedure. A blank provides the original R-K., procedure. A "one" provides a fixed step size runga-kutta procedure that could be useful in selecting integrator tolerances. A "two" provides runga-kutta variable step size, but does not print out the step varying procedure. Only the minimum stepsize is output.

Option tag = 4      Tabular Summary of Output

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00104, control tag and option
2	5	I	Print switch for summary one 1 = print, 0 = no print
	10	I	Print switch for summary two 1 = print, 0 = no print

Option tag = 5      Program Option Switches

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00105, control tag and option
	6-15	F	Switch for lateral plane motions 1 = only lateral plane motions 0 = six degrees of freedom
	16-25	F	Switch for constant speed 1 = surge equation not used 0 = surge velocity allowed to vary



<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
	26-35	F	Switch for trim
			1 = thrust varied to give proper speed. If this option is selected, then there must be input in Block 16 an estimate of thrust and a 0.0 for the number of data points.
			0 = thrust as input

Block 2 - Mass and Inertial Input

Option tag = 1      Summary Mass Properties Card

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00201 - control tag
	6-15	F	Total craft weight, pounds
	16-25	F	Longitudinal center of gravity, feet forward of transom
	26-35	F	Vertical center of gravity feet above baseline (keel)
	36-45	F	$I_{xx}$ , mass moment of inertia about x axis, slug - ft. <sup>2</sup>
	46-55	F	$I_{yy}$ , mass moment of inertia about y axis, slug - ft. <sup>2</sup>
	56-65	F	$I_{zz}$ , mass moment of inertia about z axis, slug - ft. <sup>2</sup>
	66-75	F	$I_{xz}$ , mass moment of inertia about xz axis, slug - ft. <sup>2</sup>





Note: If this option is used, shears and moments will not be calculated correctly.

Option tag = 2      Discrete Mass Distribution Cards

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00202 - control tag
2, 3, 4...	1 -10	F	Discrete weight, pounds
	11-20	F	Longitudinal c.g., feet forward of transom
	21-30	F	Transverse c.g., feet to starboard
	31-40	F	Vertical c.g., feet above baseline (keel)
Last card	1-10	F	-1.0 - control tag

The mass distribution is specified by discrete weights at various locations with one card used for each weight. Symmetry about the longitudinal center-plane is assumed, so that only weights on the starboard side, with a transverse location greater than zero should be specified. Thus, the total weight on the input cards is one half the total craft weight. The last card is used to signal the end of the discrete weights. The maximum number of discrete weights is 201.

Block 3      Craft Geometric Input

No option tags

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00300 - control tag
	6-15	F	Number of stations on port sidewall



<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
	16-25	F	Number of stations on starboard sidewall
	26-35	F	Number of stations on bow seal
	36-45	F	Number of stations on stern seal
	46-55	F	Total craft length, ft.

Note: The maximum number of stations is 11 for each element. The program will automatically subdivide the element into N-1 sections (N is the number of stations) and calculate the x and y coordinates of each station.

#### Block 4 Sidewall Input

Option tag = 1 Sidewall Input

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00401 - control tag and option
	6-15	F	y distance from centerline to sidewall, ft.
1	16-25	F	Average wetted length of side- wall, ft.
	26-35	F	Leakage orifice coefficient of sidewall
	36-45	F	Cross-flow drag coefficient of sidewall
	46-55	F	Average beam of sidewall, ft.



Note: Under this option tag the program will also read the sidewall integral table file stored on Unit 10.

Block 5 Stern Seal Input

No option tags

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00500 - control tag
1	6-15	F	x coordinate of seal hinge, ft. forward of transom
	16-25	F	z coordinate of seal hinge, ft. above keel
	26-35	F	Base leakage area, sq. ft.
	36-45	F	Seal leakage orifice coefficient
	46-55	F	Angle between leading edge of seal and craft vertical, deg.
	56-65	F	Pressure differential between seal bag and bubble, psf
	66-75	F	Length of leading edge of seal, ft.



Block 6 Bow Seal Input

No option tags

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-15	I	00600 - control tag
	6-15	F	x coordinate of seal hinge, ft. forward of transom
	16-25	F	Seal leakage orifice coefficient
	26-35	F	Pressure differential between seal bag and bubble, psf
	36-45	F	Z coordinate of the seal hinge above keel, feet
	46-55	F	Angle between leading edge of seal and craft vertical, deg.
	56-65	F	Length of the leading edge of the seal, feet
	66-75	F	Base leakage area, ft.

Block 7 Plenum Input

Option tag = 1 Plenum Geometry





<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00701 - control tag and option
1	6-15	F	Plenum length at water surface, ft.
	16-25	F	Plenum width at water surface, ft.
	26-35	-	Not used at present
	36-45	F	Plenum width at deck, ft.
	46-55	F	Plenum length at deck, ft.
	56-65	F	x coordinate of center of pressure, ft., forward of transom
	66-75	F	Plenum average height

Option tag = 2      Critical Froude Number

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00702 - control tag and option
	6-15	F	Froude number corresponding to hump speed

Block 8 · Propulsion Input

Option tag = 1      Basic Data

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-15	F	00801 - control tag and option
	6-15	F	x coordinate of propeller center, ft. forward of transom
	16-25	F	y distance from centerline to propeller center, ft.
	26-35	F	z coordinate of propeller, ft. above keel



Block 9 Rudder Input

Option tag = 1 Rudder Geometry

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00901 - control tag and option
	6-15	F	x coordinate of centroid of rudder, ft. forward of transom
	16-25	F	y distance from centerline to rudder centroid, ft.
	26-35	F	z coordinate of centroid of rudder, ft. above keel
	36-45	F	Rudder span, ft.
	46-55	F	Rudder aspect ratio
	56-65	F	Rudder area, sq. ft.
	66-75	F	Average Thickness ratio of rudder section

Block 10 Aerodynamic Input

No option tags

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01000 - control tag
	6-15	F	Reference length, ft.
	16-25	F	Reference width, ft.

Note: The reference length and width are those used to nondimensionalize the wind tunnel data used in the program.

Block 11 Waves Input

Option tag = 1 Amplitude vs. frequency



<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01101 - control tag and option
	6-15	F	Number of wave components, maximum of 10
	16-25	F	Initial wave heading relative to craft headings ( $180^{\circ}$ = head seas), deg.
2, 3, 4...	1-10	F	Wave frequency, rad./sec.
	11-20	F	Wave amplitude, ft.

Option tag = 2      Amplitude vs. wave length

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	00102 - control tag and option
	6-15	F	Number of wave components, maximum of 10
	16-25	F	Initial wave heading relative to craft heading ( $180^{\circ}$ = head seas), deg.
2, 3, 4...	1-10	F	Wave length, ft.
	11-20	F	Wave amplitude, ft.

Note: The program constructs irregular seas by adding together a series of regular wave components with appropriate distribution of amplitude and frequency. To run a regular sea case, the number of wave components should be equal to 1. If the number of waves is equal to zero (calm water) no additional data (cards 2, 3, 4...) should appear.

Block 12    Initial Conditions



No option tags

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01200 - control tag
	6-15	F	Initial speed, knots
	16-25	F	Initial pitch angle (positive-nose up), deg.
	26-35	F	Initial draft at the center of gravity, inches
	36-45	F	Initial bubble gage pressure, psf

Block 13 End of Case

No option tags

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01300 - control tag

Note: This card is used to signal the end of data for a given case. The program will now initialize all required variables and will start the calculation of the time history.

If the program reads two consecutive 01300 cards with no data between, the job will be stopped rather than repeat the previous case.

Block 14 End of Run

No option tags

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01400 - control tag

Note: This card is used to signal the end of the run. When encountered the program will print out the message:

COMPLETED ALL RUNS

and will then stop.





Block 16 Thrust and Rudder Input

Option tag 1 = STB Thrust input

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01601 - Control tag and option
	6-15	F10	Value of constant thrust for the starboard screw if variable thrust is not desired
	16-25	F10	Number of data points in the thrust map. Left blank if constant thrust is used.
	26-35	F10	Side thrust coefficient
2,3..	1-80	8F10	Data points for the independent variable, time in ascending order.
	1-80	8F10	Corresponding data points for the dependent variable.

Option tag 2 = Port thrust input



<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01602 - Control tag and option
	6-15	F10	As above for the port screw.
	16-25	F10	" " " " " "
	26-35	F10	" " " " " "
2,3..	1-80	8F10	" " " " " "
	1-80	8F10	" " " " " "

Option tag 3 = Rudder motion input

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01603 - Control tag and option
	6-15	F10	Value of rudder if constant rudder is desired
	16-25	F10	Number of data points of the rudder map. Left blank if constant rudder is desired.
2,3..	1-80	8F10	Values of the independent variable time in ascending order.
	1-80	8F10	Corresponding values of rudder angle in degrees. Note: Positive rudder angle is right rudder.

Block 17 Bow and Stern Seal Pressure Differences Input

Option tag 1 = Bow seal

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01701 - Control tag and option
	6-15	F	Number of data points for the bow seal



<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
2,3..	1-80	8F10	Time points in ascending order
6,7..	1-80	8F10	Corresponding differences in bow seal pressures

Block 17 shall be left blank if a constant pressure is desired. That constant shall be input in Block 5 and 6. However,, one seal may be held constant and the other varied.

Option 2 = Stern seal

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01702 - Control tag and option
	6-15	F	Number of data points for the stern seal
2,3..	1-80	8F10	As for option 1, for the stern seal
6,7..	1-80	8F10	As for option 1, for the stern seal

Block 18 Title card

No option tags

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01800 - control tag
2	1-80	20A4	Alphanumeric data to be printed as title in input summary

Block 19 Fan Maps

Option tag = 1 Bow Seal Fans



<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01901 - control tag and option
	6-15	F	Number of bow seal fans
	16-25	F	Speed of bow seal fans, rpm
	26-35	F	Number of data points (maximum of 25)
	36-45	F	If this is a 1.0 then the following data points are read. If left blank no further read takes place.
2,3..	1-80	8F10	Tabular value of fan pressure differential, psf.
After last pressure data card	1-80	8F10	Corresponding volumetric flow rate, cu.ft./sec.

Option tag = 2 Cushion Fans

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01902 - control tag and option
	6-15	F	Number of cushion fans
	16-25	F	Speed of cushion fans, rpm
	26-35	F	As option 1 above
2,3..	1-80	8F10	Tabular values of fan pressure differential, psf
After last pressure data card	1-80	8F10	Corresponding volumetric flow rate.

Option tag = 3 Stern Seal Fans





<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-5	I	01903 - control tag and option
	6-15	F	Number of stern seal fans
	16-25	F	Speed of stern seal fans, rpm
	26-35	F	Number of data points (maximum of 25)
	36-45	F	As option 1 above
2,3..	1-80	8F10	Tabular values of fan pressure differential, psf
After last pressure data card	1-80	8F10	Corresponding volumetric flow rates cu.ft./sec.

Note: The tabular pressure data for all the fans must be stored in order of increasing pressure. (See discussion in Function FG1). The data is for a single fan.

Structure of Input Deck - The input deck for a given case or series of cases may be considered as being divided into two parts, "basic" data and specific data. Basic data is defined as those inputs which are required to adequately represent the craft regardless of the type of case being considered. Data such as mass properties, craft geometry, fan maps, etc. fall into this category. Specific data is defined as those inputs which are needed to define a specific problem such as runs in waves vs. calm water, rudder motion vs. no rudder motion, etc.

The input cards which constitute the basic data are summarized below by control and option tag along with a



brief description of the input. An asterisk indicates that more than one input card is read in under the given control and option tag.



Required Input Summary (Listed in Numerical Order)

<u>Control Tag and Option</u>	<u>Description</u>
00101	Timing information
00103	Number of integrators and error tolerances
00201 or 00202*	Mass and inertias or mass distribution
00300	Craft geometric data
00401	Sidewall basic data
00500	Stern seal basic data
00600	Bow seal basic data
00701	Plenum geometry
00702	Froude number at hump speed
00801	Propulsion system basic data
00901	Rudder geometry
01000	Aerodynamic reference lengths
01200	Initial conditions
01300	End of data for one case
01400	End of all cases
01600	Thrust map input
01700	Rudder motions input
01901*	Bow seal fan maps
01902*	Cushion fan maps
01903*	Stern seal fan maps

---

\*More than one input card under this control tag and option.



Optional Input Summary (Listed in Numerical Order)

<u>Control Tag and Option</u>	<u>Description</u>	<u>Program Action if Input Card Is Not Used</u>
00102*	Subroutine print switches	No printout from individual subroutine
00104*	Tabular summary print switches	No tabular summary
00105	Option switches for lateral plane motions only, trim calculations and constant speed runs	Six Degrees of freedom, fixed thrust (unless engine out is requested, surge velocity allowed to vary
01101*	Wave input	Calm water
01800	Title card	No title printed

Multiple Case Runs - In running multiple cases it is important that the user remember that any input data that is not read in again will be repeated from the previous case. Consider the case where a run is to be made consisting of a run in waves followed by a turn in calm water at a different speed. Assume both intermediate and tabular output is desired for both cases. In terms of control tags the deck might look as follows:

00101	Required Input
00103*	
00202*	
00401	
00500	
00600	

---

\*More than one input card under this control tag and option.





00701	
00801	
00901	
01000	
01200	
01600*	
01700	
01901*	
01902*	
01903*	
00102*	Intermediate print
00104*	Tabular print
01102*	Wave input
01300	End of case 1
01200	New initial conditions
01603	Rudder motion
01102*	Wave input
01300	End of case 2
01400	End of run

The purpose of the wave input card in case 2 is to read in the number of waves as zero (calm water). Without this card case 2 would become a turn in waves. Similarly, if a run were to be made with case 1 being an engine out run and case 2 being a turn with both engines operating, case 2 would have to reset the engine out time to a time larger than the run finish time by reading a large time on an 00802 card

---

\*More than one input card under this control tag.



(if case 2 had a finish time less than the engine out time from case 1 it would not be necessary to read this card).

Output - The output from INCON is printed after an end of case card (01300) is read. It is a combination of input data and calculated results. A sample case is given in the input at the end of the report.



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## Subroutine INTGRL

Discussion - Subroutine INTGRL is used to integrate a system of first order ordinary differential equations. It uses a variable time step technique based on the Runge-Kutta-Merson algorithm. A fixed time step R-K also available - See Block 1 option tag 3 for a discussion on its use. The program will stop the calculation if the time step becomes smaller than  $10^{-6}$  sec.

Usage - CALL INTGRL (TIME)

### Descriptions of Parameters

TIME = current value of the independent variable

Input - The input to subroutine INTGRL is controlled by the 00103 control tag as discussed in block 1 of subroutine INCON.

Output - If the integration step size is halved, INTGRL will print the current value of time, the new value of the time step, the integrator number, the calculated error and the input maximum error as shown in the sample output at the end of the report. This output is useful as it tells the user which integrator is causing the step size to be reduced and may indicate an excessively tight input error tolerance (see discussion of 00103 card in discussion of subroutine INCON).





## Subroutine PROP

Discussion - Subroutine PROP is used to calculate forces and moments on the craft due to the propulsion system. The subroutine has the capability of uneven thrusting and receives this information by using the Function Program FGI to linearly interpolate a map input in block 16.

Usage - CALL PROP

Input - The input to subroutine PROP is controlled by block 8 and block 16 of subroutine INCON and is discussed there.

Output - The output from PROP is controlled by print option switch IPROP. If this switch is 1, the program will print the calculated forces and moments as shown in the sample output at the end of the report.



## Subroutine RHS

Discussion - Subroutine RHS is the subprogram containing the FORTRAN expressions for the right hand side of the system of first order differential equations. It contains the logic to calculate the bubble volume, area and pressure as a function of time as well as the logic which sums the individual forces, moments and leakages from the various craft components to get craft totals. RHS also contains the statements used for the writing of the scratch file for the tabular output.

Usage - CALL RHS (VALUE)

### Description of Parameters

VALUE = The array containing the values of the right hand side of the differential equations as calculated in RHS, i.e., for a system of equations of this form  $y_i = f_i(y_i, t)$  the VALUE array is used to store the values of  $f_i(y_i, t)$

Input - None

Output - The output from RHS is controlled by print option switch IHRS. When this switch is 1, the subroutine will print the output shown in the sample output in the back of the report.



## Subroutine RUDDER

Discussion - Subroutine RUDDER contains the logic for calculating rudder forces and moments as well as rudder motions. Rudder motions are calculated by employing the Function Program FGI to linearly interpolate a map input in block 16 of INCON.

Usage - CALL RUDDER

Input - The input to RUDDER is controlled by block 9 and 16 in Subroutine INCON and is discussed there.

Output - The output from rudder is controlled by print option switch IRUD. If this switch is 1, the program will print out the total forces and moments due to the rudder as shown in the sample output in the back of the report.



## Subroutine SIDEWL

Discussion - Subroutine SIDEWL calculates the forces and moments acting on the craft due to the sidewalls as well as the leakage flow rates associated with any gaps which open under the sidewalls due either to craft motion or waves.

Usage - CALL SIDEWL

Input - The input to subroutine SIDEWL is controlled by blocks 3 and 4 of subroutine INCON and is discussed there.

Output - The output from SIDEWL is controlled by the print option switch ISIDWL. When this switch is equal to 1, the program will print the sidewall gaps, immersion depths and total forces and moments due to the sidewall-appendage combination as shown in the output listing at the back of the report.





## Subroutine STNSL

Discussion - Subroutine STNSL calculates the forces and moments acting on the craft due to the stern seal as well as the leakage flow rates arising from any gaps which open under the seal. The craft equilibrium leakage area is assumed to be located in the stern seal.

Usage - CALL STNSL

Input - The input data for STNSL is controlled by blocks 3, 5, and 17 of subroutine INCON and is discussed there.

Output - The output from STNSL is controlled by print option switch ISTNSL. When this switch is equal to 1, the program will print the seal wetted lengths, and gaps as a function of station as well as the craft forces and moments due to the stern seal. An example is contained in the sample output at the back of the report.



## Functions T1 and T2

Discussion - Functions T1 and T2 are two small Function subprograms used to calculate various trigonometric relations used by subroutine WAVES.



## Subroutine WAVES

Discussion - Subroutine WAVES calculates the wave forces and moments acting on the craft. It also generates the wave heights at the various stations around the seals and sidewalls, as well as the bubble volume lost due to wave elevation.

The sea state for irregular seas is computed in WAVES by adding together a series of regular waves with an appropriate distribution of amplitude and frequency.

Usage - CALL WAVES

Input - The input to subroutine WAVES is controlled by block 11 of subroutine INCON and is discussed there.

Output - The output from WAVES is controlled by print option switch IWAVES. When this switch is set equal to 1, WAVES will print the wave elevation around the seals and sidewalls, the wave elevation at the center of gravity and the volume reduction of the bubble plenum due to waves as well as the total forces and moments acting on the craft due to waves.



USERS MANUAL FOR THE PLOTTING  
PACKAGE  
(INCLUDES THE MULTICURVE OPTION)

DESCRIPTION:

The plotting package of the COLFIL subroutine is a flexible routine that allows the user to:

- 1) Plot on either the CALCOMP or the printer
- 2) Plot up to 3 curves per graph on the CALCOMP
- 3) Intermix multicurve CALCOMP and single curve CALCOMP plots
- 4) Revise the variables plotted on successive runs
- 5) Choose from up to 26 different variables
- 6) Print up to 16 variables per run
- 7) Revise the variables printed on successive runs

The method of employing this routine must be adhered to or errors will result. JCL for calling this routine is found at the end of this manual.

MEANING OF THE CARD

1. Block 20

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-3	I3	020
2	This card must be used if card 1 appears. See sample input		
	1-10	I1	NCURV is the number of this curve on the corresponding graph, ie; Col. 1 pertains to graph 1, Col. 2 - graph 2, etc.





<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
			A "0" must appear in these columns if only one curve per graph is to be plotted. "1" must appear if this is the first of more than one curve per graph, a "2" if this is the intermediate curve and a "3" if this is the last curve on this graph.

2. Block 21

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-3	I3	021 - Causes the summary variables to be read
2	1-16	8I2	Punch in the numbers corresponding to the variable names desired to be printed in summary one.
3	1-16	8I2	The same as card one but, for Summary Two, these cards need not be repeated for successive runs unless changes are desired.

3. Block 22

<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1	1-3	I3	022 - Read in the number of graphs desired, whether or not Calcomp is desired. Read the X and Y axes for the graphs and read the first line



<u>Card</u>	<u>Columns</u>	<u>Format</u>	<u>Entry</u>
			of the graph title.
2	1-2	I2	The number of graphs desired right justified, up to and including 10.
	3-4	I2	A zero if print plot is desired or a 1, right justified, if CALCOMP is desired.
3	1-50	25I2	The numerical values of the X and Y axes alternating in the following manner. The X axis of the first graph then the Y axis of the first graph and continuing for all desired graphs. A table relating axis number and name is at the end of this paper.
4	1-48	6A8	The Alpha-numeric title that will appear on the first line of the CALCOMP plot. If CALCOMP is not desired, replace this card with a blank card. Your name should appear somewhere on this line for computer identification purposes.



SAMPLE INPUT DECK

020

11 ← This indicates that this is the first of multiple curves on graphs 1 and 2.

021

0115 ← Summary one will print the first two variables,  
0116 01, 15, and summary two the following two,  
01, 16.

022

0201 ← Two graphs are called for, and a CALCOMP output

01150116 Graph 1 plots 01, 15, Time and X displacement

Graph 2 plots 01, 16, Time and Y displacement

SES output for LEO

Standard input deck

013

020 )  
22 )  
021 ← As Above. These can be changed on subsequent  
1516 runs.  
0115 )

Changes desired

013  
020  
33  
021 As Above.  
1325  
0116

Changes desired

013  
014



RELATION OF VARIABLE NAME AND NUMBER

<u>NUMBER</u>	<u>NAME</u>
01	Time
02	Wave Height
03	Z Displacement
04	Pitch Angle
05	Plenum Pressure
06	Bow Acceleration
07	C. G. Acceleration
08	Fan Power
09	Roll Angle
10	Yaw Angle
11	Lateral Acceleration
12	Speed through the water
13	Turn Radius
14	Turn Rate
15	X Displacement
16	Y Displacement
17	Air Flow in
18	Air Flow out
19	Net Force X Direction
20	Wave Force X Direction
21	Net Force Y Direction
22	Net Force Z Direction





<u>NUMBER</u>	<u>NAME</u>
23	Net Torque X Axis
24	Net Torque Y Axis
25	Net Torque Z Axis
26	Rudder Angle



APPENDIX A-A

CHANGING THE MODEL



## Changing the Model

### Appendix A-A

#### Introduction

As previously stated, the program has been written in a modular form to facilitate changes to the program which reflect major design changes to the craft, i.e., a different type of seal, addition of controls, etc. Since it is obviously impossible to program all possible configurations in one program, these types of changes will require either replacing a whole module (sub-program) or altering the Fortran statements within a given sub-program. In order to achieve this, a more detailed knowledge of the structure of the program and the method of data transfer between subprograms is required. This appendix will attempt to give a brief explanation of the program structure and will then discuss the details of how one would make certain anticipated changes.

#### General Structure

The primary variables (displacements, velocities, pressure, etc.) are contained in an array of length 40 words, named VAL; which is transmitted through the various subprograms using a labelled common block called VARBLE. Within each subprogram the various elements of VAL are equivalenced to local variables, which are given mnemonic names which closely resemble the standard mathematical symbols used for the variable (e.g.  $u, v, w, p_B$  become U, V, W, PB in the



Fortran listing). The second through the sixteenth elements of VAL are reserved for the output of integrators and must be used in numerical order, i.e., when adding a new equation to be integrated, the output of the integrator must be equalized to the first unused location in VAL (VAL(12) for the current program).

The force and moment components acting on the craft are calculated for each element in the appropriate subprogram and are transmitted through various labelled common blocks. These force and moment components are then summed in subroutine RHS to get the appropriate acceleration and velocity components. The accelerations and velocities are transmitted back to subroutine INTGRL in an array called VALUE. INTGRL then integrates these first derivatives to get the new velocities and displacements.

#### Anticipated Changes

##### a. Replacing Analytic Coefficients or Curve Fits With Tabular Experimental Data

As experimental data is obtained it may be desired to replace coefficients based on analytic calculations or estimations from simple shapes by the experimental data. This data will often be tabular in nature. For functions of a single variable this is quite simple to do as the necessary table look-up routine already exists within the program (function FGL). The user would be required to make the following changes.





1. Statements to read in the tabular data must be added to subroutine INCON.
2. A common block must be provided to transfer the data to the subroutine where it is to be used.
3. A statement must be added to call FGI to do the table look-up.

A good example of the above procedure is afforded the user by the fan maps as currently programmed. This logic uses tabular data and the user should refer to input block 19 of subroutine INCON and subroutine FAN to see an example of the three steps outlined above.

b. Adding a Stern Seal Equation of Motion

The current program has a stern seal model which is based on the assumption that the seal is completely deformable (no stiffness) and as such there is no dynamic equation of motion. For seal designs where there is an appreciable degree of stiffness a seal equation of motion should be added.

Assume that the seal equation of motion to be added is a standard spring-mass-damper system and therefore may be represented by the following system of first order differential equations.

$$\dot{\alpha}_s = (-d\theta_s - k\theta_s + M_s)/m \quad (1)$$

$$\dot{\theta}_s = \alpha_s \quad (2)$$



The following program changes would have to be made in order to incorporate Equations (1) - (2) into the current program.

1. Logic must be added to block 5 of subroutine INCON to read in and store the constants  $d$ ,  $k$ , and  $m$  as well as the initial conditions for  $\theta_s$  and  $\dot{\theta}_s$ . Care should be taken in the case of the latter to save these initial conditions using Fortran variables with names other than the names which will contain the current (running) values of the seal displacement and velocity. This is due to the fact that when running multiple cases the program will use the currently stored values of  $\theta_s$  and  $\dot{\theta}_s$  from the old case as initial conditions for the new case unless the initial conditions are reset. An example of this can be seen on page 205 of the program listing after statement number 1200 where the craft initial conditions are read in. Saving the initial conditions under a different name also has the advantage of allowing the input to be in degrees rather than in radians as required by the program, as the conversion can be done in the arithmetic replacement statements added in step 2 below.



2. In block 13 of INCON, (after statement 1300 but before statement 1400) arithmetic replacement statements should be added to convert the initial conditions to radians and radians/sec. and then store these values in the running variables for  $\theta_s$  and  $\dot{\theta}_s$  (see page 205 of the program listing after statement 1302 for an example). Note that in the program the variable RAD is the number of degrees in a radian and may be used for the conversion of units (see example cited above.)
3. The variable names for the seal velocity and displacement should be equivalenced to VAL (12) and VAL (13) respectively. This automatically makes these variables the output of integrators. This equivalence statement should appear in subroutines INCON, RHS and STNSL.
4. The number of differential equations on the input card after the 00103 card should be increased from 10 to 12, indicating that two additional differential equations have been added. In addition, error tolerances for these integrators must be given (see page 154 of this report for a discussion of this point.)
5. A common block to transmit  $d$ ,  $k$ , and  $m$  must be added to subroutines INCON and RHS.



6. In subroutine RHS the Fortran equivalent of the right hand side of Equation (1) must be set equal to VALUE (11) while  $\dot{\theta}_s$  must be set equal to VALUE (12). (See examples in listing of subroutine RHS.)
7. In subroutine STNSL the expressions for  $M_s$ , the total applied moment on the stern seal about its hinge point must be added. These are placed in STNSL as this subroutine has the logic for calculating wave elevations relative to the seal, etc. In addition, the equations for the stern seal leakage gap in STNSL must be modified to take into account the seal motion.
8. A common block must be added to subroutines STNSL and RHS to transmit the value of the moment  $M_s$  to RHS.

c. Adding New Forces or Moments Acting on a Craft

If the modification of the program entails the addition of any new force or moment component acting on the craft, care must be taken to add this component to the bending moment calculations as well as the craft motion calculations. If this is not done the equilibrium check done by subroutine SAM prior to calculating the bending moments will not balance and the calculation will be terminated.

The following changes would have to be made:





1. In subroutine RHS the new force component should be added to the WRITE statement preceding statement number 111 on page 218 of the program listing as well as into the calculation of GF in RHS. If the force component has a fixed moment arm, a common block should be added to transmit its value to subroutine SAM. If the moment arm is time varying the moment arm should also be added to the WRITE statement.
2. In subroutine SAM the force and arm (if necessary) should be added to the following READ or WRITE statements; page 220 , statement numbers 42 and 44; page 220 , after statement number 6.  
The force and moment components must be added to the equilibrium check on the top of page .  
The force and moment components must be added to the calculation of the longitudinal and lateral moment and shear calculations. In these calculations the variables XMI(IX) and YMI(IY) are the distance to the current plane of interest. The user should study the current program listing (pages 183 - 233) to ascertain the procedure used to add these force and moment components.



APPENDIX A-B

ABNORMAL TERMINATION MESSAGES



<u>ABNORMAL TERMINATION MESSAGE</u>	<u>SUBPROGRAM</u>	<u>PROGRAM ACTION</u>	<u>USER ACTION</u>
CRAFT SPEED BELOW HUMP SPEED	MAIN	Go to next case	None
INPUT ERROR -- STOP -- ISYS = XXX	'INCON	Stop run	Check input data for misspunched card or card out of place. Program has read a card with an invalid program control tag (ISYS).
ERROR IN INPUT --- DELT AND/OR DELPNT EQUALS ZERO --- JOB ABORTED	INCON	Stop Run	Check 00101 input card and fix error. Program would loop indefinitely if allowed to continue.
ERROR IN INPUT --- INPUT INERTIA	INCON	Stop Run	Inertia matrix is singular. Check 00201 card or mass distribution to find error.
DELTA TIME LESS THAN 1.0E-6 -- JOB STOPS	INTGRL	Stop Run	The time step has been halved to below 10 <sup>-6</sup> sec. Check any intermediate output for unusual values. Check the derivative (K1) and the state variables (VAL) printed with this error message for any unusual numbers.



APPENDIX A-C

SIDEWALL INTEGRAL TABLE PROGRAM

DISCUSSION





## Sidewall Integral Table Program

### Appendix A-C

The sidewall Integral Table Program evaluates tables of integrals of sectional hydrostatic and hydrodynamic properties over the whole and partial lengths of a SES sidewall. These tables are calculated as a function of sidewall draft, trim and length of a regular wave. The tables are then subsequently accessed by the main SES Motions and Load Program and when combined with knowledge of both the craft and waves instantaneous position and motion produces the hydrostatic and hydrodynamic forces and moments acting on the sidewalls.

The primary input to this program is a table of waterlines and corresponding beams for each chosen station with arbitrary spacing in both waterlines and stations. The program is thus applicable to a general sidewall form. In addition to this input, the user must specify the range of drafts, trim (pitch) angles, and wavelengths (encompassing all components of a specified sea state) that the craft is expected to range thru in the subsequent simulations performed by SES Motions and Loads Program. The wavelengths are specified via the wavelengths parameter ( $2\pi/\lambda$ ). The first value of this parameter must be zero which corresponds to an infinite wavelength and is used to SIDEWL subroutine of the SES Motions and Loads Program to determine hydrostatic and hydrodynamic forces due to body motion alone.



The tables at the remaining values are used by the WAVES subroutine for wave induced forces. Since the center of gravity is not necessarily known at the time this program is executed, the user must also specify a longitudinal reference coordinate measured from the transom about which the integrals are to be evaluated (a value near mid-ships is recommended). The range of drafts and trims at the longitudinal reference point must be selected in such a manner so that the top of the plenum does not sink below the water surface.

The description and order of the cards of the input data deck is as follows:

1st Card

<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1-5	I	No. of wave parameters $\leq 20$
6-10	F	increment in wave parameters (ft. <sup>-1</sup> )
11-15	F	first value of wave parameter (ft. <sup>-1</sup> )
16-20	I	no. of drafts $\leq 5$
21-25	F	increment in draft (in.)
26-30	F	first value of draft (in.)
31-35	I	no. of trims $\leq 7$
36-40	F	increment in trim (deg.)
41-45	F	first value of trim (deg.)
46-50	I	no. of stern beams $\leq 36$
51-55	F	increment of stern beam (ft.)
56-60	F	first value of stern beam (ft.)



2nd Card

<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1-5	I	no. of stations = NSTA $\leq$ 95
6-10	I	max. no. of drafts per station $\leq$ 8

3rd Card

<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1-5	F	distance from keel to top of plenum (ft.)

4th Card

<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1-10	F	distance of reference position from transom (ft.)

5th Card

<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1-5	I	no. of integral limits in addition to the integral over the whole length $\leq$ 10
6-75	10F5	integral limits (distance from transom) (ft.)

Next NSTA Cards (one card per station)

<u>Columns</u>	<u>Format</u>	<u>Entry</u>
1-5	F5	distance of station from bow (in.)
6-10	F5	lowest waterline beam (ft.)
11-15	F5	corresponding height of beam (ft.)
16-20	F5	next waterline beam (ft.)
21-25	F5	corresponding height of beam (ft.)



<u>Columns</u>	<u>Format</u>	<u>Entry</u>
.	.	
.	.	
.	.	
66-70	F5	next waterline beam (ft.)
71-75	F5	corresponding height of beam (ft.)

This program transmits the calculated tables to the SES Motions and Loads Program by writing the tables on units which are later read by the main program. Unit number 10 contains the tables obtained by integrating over the entire length and the succeeding units contain the tables obtained by integrating over partial lengths.





APPENDIX B  
FORTRAN PROGRAM LISTING











```

GC TO 1
12 CALL COLFIL
IF (IMM.NE.1) GO TO 11
IF (FILE.IBMFIL) GO TO 605
GO TO 11
605 CALL SAV
GO TO 11
500 FCRMAT(//10X,13HTIME (SEC) = F6.2//10X,23HTRANSLATIONAL VELS (KTS)
1) / (FT/SEC) / 10X,2HU= F6.2,5X,2HP= F6.3//10X,31HRCTATI
20NAL VELOCITIES (DEG/SEC) / 10X,2HQ= F6.2,5X,2HR= F6.2
3//10X,30HDTHETA= F6.2//10X,27HTRAJECTORY (FT AND DEGREES) / 10X,
4F6.2,3X,6HTHY= F8.2,4X,2HPSI= F8.2)
52FX= F8.2,5X,2HSIDESLIP ANGLE (DEG) = F8.2,10X,21HRUDDER ANGLE
501 1 FCRMAT(//10X,23HSIDESLIP ANGLE (DEG) = F12.1)
505 FURMAT(//25X,28HCRAFT SPEED BELOW HUMP SPEED )

BLOCK DATA
COMMON /AIR/ Z1(3)
COMMON /BMC0/ Z2(25)
COMMON /COLUMN/ Z3(2)
COMMON /CONST/ Z4(3)
COMMON /CNTEL/ Z5(10)
COMMON /ENGINE/ Z6(107)
COMMON /EQNCO/ Z7(22)
COMMON /FAERO/ Z8(6)
COMMON /FAIR/ Z9(2)
COMMON /FANMAP/ Z10(262)
COMMON /FORPS/ Z11(7)
COMMON /FORSS/ Z12(8)
COMMON /FPROPL/ Z13(6)
COMMON /FPRODE/ Z14(2)
COMMON /FRUD/ Z15(6)
COMMON /GBOW/ Z16(1)
COMMON /GEOM/ Z17(138)
COMMON /GEOBMS/ Z18(62)
COMMON /GEOHSS/ Z19(62)
COMMON /GEOHSSW/ Z20(11)
COMMON /KSWTCH/ Z21(1)
COMMON /LEAKER/ Z22(4)
COMMON /MASSES/ Z23(317)
COMMON /MATRIX/ Z24(36)
COMMON /MSIDW/ Z25(55)
COMMON /MWAVE/ Z26(12)
COMMON /OPTION/ Z27(3)
COMMON /PLENUM/ Z28(4)

```

```

MN 0960
MN 0970
MN 0980
MN 0990
MN 1000
MN 1010
MN 1020
MN 1030
MN 1040
MN 1050
MN 1060
MN 1070
MN 1080
MN 1090
MN 1100
MN 1110
MN 1120
MN 1130
MN 1140
MN 1150
MN 1160
MN 1170
MN 1180
MN 1190
MN 1200
MN 1210
MN 1220
MN 1230
MN 1240
MN 1250
MN 1260
MN 1270
MN 1280
MN 1290
MN 1300
MN 1310
MN 1320
MN 1330
MN 1340
MN 1350
MN 1360
MN 1370
MN 1380
MN 1390
MN 1400
MN 1410
MN 1420
MN 1430

```









```

DATA Z32/0.0/
DATA Z33/2.0.0/
DATA Z34/62.0.0/
DATA Z35/22.0.0/
DATA Z36/19.0.0/
DATA Z37/19.0.0/
DATA Z38/5.0.0/
DATA Z39/2.0.0/
DATA Z40/20.0.0/
DATA Z41/40.0.0/
DATA Z42/80.0.0/
DATA Z43/40.0.0/
END

```

C

```

SUBROUTINE AEROD
INTEGER CN
COMMON /FAERO/ FX,FY,FZ,FK,FM,FN
COMMON /FAIR/ RHGA,XLAERO
COMMON /PRINT/ON,IACCEL,IVEL,ITRAJ,ISIDWL,IBOWSL,ISTNSL,IWAVES,
-IRUD,IPROP,IAEROD,IRHS
COMMON /VARBLE/ VAL(40)

EQUIVALENCE
1(VAL(5),P), (VAL(6),Q), (VAL(7),R), (VAL(8),PHI), (VAL(9),THETA),
2(VAL(10),Z), (VAL(11),BMASS); (VAL(21),X), (VAL(22),Y), (VAL(23),PSI),
3(VAL(24),PB)
QA=RHGA*U*U
QAL=QA*XLAERO
QALF=-V/U
BETASQ=BETA*BETA+0.131*QA
FX=-(0.09*BETASQ+0.53*BETA)*QA
FZ=-(2.06*BETASQ+0.39)*QA
FK=-(0.5*BETASQ+0.07*BETA)*QAL
FN=(0.29*BETASQ+0.12)*QAL
FN=(0.04*BETASQ+0.076*BETA)*QAL

IF (IAEROD.NE.CN) RETURN
WRITE(6,100) FX,FY,FZ,FK,FM,FN
100 FORMAT(/10X,23HAEROD FX,FY,FZ,FK,FM,FN/6E15.4)
RETURN
END

```

C

```

SUBROUTINE BOWSL
INTEGER ON
COMMON /AIR/ PINF,RHOINF,GAM

```

```

MN 1920
MN 1930
MN 1940
MN 1950
MN 1960
MN 1970
MN 1980
MN 1990
MN 2000
MN 2010
MN 2020
MN 2030
MN 2040

```

```

AER 0010
AER 0020
AER 0030
AER 0040
AER 0050
AER 0060
AER 0070
AER 0080
AER 0090
AER 0100
AER 0110
AER 0120
AER 0130
AER 0140
AER 0150
AER 0160
AER 0170
AER 0180
AER 0190
AER 0200
AER 0210
AER 0220
AER 0230
AER 0240
AER 0250
AER 0260
AER 0270
AER 0280
AER 0290

```

```

BSL 0010
BSL 0020
BSL 0030
BSL 0040

```



```

COMMON /CCNST/ PI, PAD, UO
COMMON /FORBS/ FX, FY, FZ, FK, FM, FN, QL
COMMON /GECM/ WIDTH, XL, XX(4, 11), YY(4, 11), NSTA(4), AB, VOLNOM
1, CDELS(4, 10), XCP, ZCP
COMMON /GECMBS/DETABX(11), DETABT(11), ARM1B(10), ARM2B(10)
1, DFBS(10), TSKIB(10)
COMMON /LEAKER/ALEAK, BLEAK, CFSS, CFBS
COMMON /MASSES/ AM, AIXX, AIYZ, AIZZ, AIXZ, A IMAX, G, WEIGHT, RHO, NMMASS,
IRUD, IPROP, IAEROD, IRHS
COMMON /PRINT/ON, IACCEL, IVEL, I TRAJ, ISIDLW, IBCWSL, ISTNSL, IWAVES,
COMMON /SOFTBS/XBF, PBS, SINBS, COSES, XBS, ZBS, DELYBS, DPBS, ELMAXB, YAVG
1 B(10)
COMMON /VARBLE/ VAL(40)
COMMON /WAVE/ ETA(4, 11), AM(10), CMEGA(10), DVCLW, NWAVE, BETA,
FXWAV, FYWAV, FZWAV, FKWAV, FMWAV, FNWAV
1 ZBAR, PHIBAR, THEBAR, TC, COSEET, SINBET, PBBAR
DIMENSION GAP(11), ELSKI(11)
DATA NPTS, IBS/6, 0, 75, 5, 42, 6, 67, 7, 5, 8, 42/
DATA WTAB/0, 3, 4, 0, 0, 4, 4, 2, 4, 83, 5, 25, 5, 67/
DATA ZTAB, UMSKI, CLSKI/1, 28E-05, 0, 0, 1, 5708/
EQUIVALENCE (VAL(1), TIME), (VAL(2), U), (VAL(3), V), (VAL(4), W),
1 (VAL(5), P), (VAL(6), Q), (VAL(7), R), (VAL(8), PFI), (VAL(9), THETA),
2 (VAL(10), Z), (VAL(11), BMASS), (VAL(21), X), (VAL(22), Y), (VAL(23), PSI),
3 (VAL(24), PB)
DC 5 J=1, 11
GAP(J)=0.0
ELSKI(J)=0.0
5 ALBS=0.0
FX=0.0
FZ=0.0
FK=0.0
FM=0.0
FN=0.0
DELPBG=PBS-PB
IF(DELDPBG.LT.0.0) DELPBG=0.0
PBAR=PB-PINF
DELP=PBAR
IF(DELFP.LSINBS-COSBS*THETA)
SINDIF=COSBS+SINBS*THETA
XI=XBS+ZBS*THETA-XBF*SINDIF
ZI=-Z-ZBS*XBS*THETA-XBF*COSDIF
N=NSTA(3)
DC 10 K=1, N

```

```

BSL 0050
BSL 0060
BSL 0070
BSL 0080
BSL 0090
BSL 0100
BSL 0110
BSL 0120
BSL 0130
BSL 0140
BSL 0150
BSL 0160
BSL 0170
BSL 0180
BSL 0190
BSL 0200
BSL 0210
BSL 0220
BSL 0230
BSL 0240
BSL 0250
BSL 0260
BSL 0270
BSL 0280
BSL 0290
BSL 0300
BSL 0310
BSL 0320
BSL 0330
BSL 0340
BSL 0350
BSL 0360
BSL 0370
BSL 0380
BSL 0390
BSL 0400
BSL 0410
BSL 0420
BSL 0430
BSL 0440
BSL 0450
BSL 0460
BSL 0470
BSL 0480
BSL 0490
BSL 0500
BSL 0510
BSL 0520

```



```

ELSKI(K)=(ETA(3,K)-DETABX(K))*(XX(3,K)-X1)-Z1+YY(3,K)*PHI
GAP(K)=-ELSKI(K)
IF(GAP(K).LT.0.0) GAP(K)=0.0
CONTINUE
N=NSTA(3)-1
DO 20 J=1,N
  ELSKIA=(ELSKI(J+1)+ELSKI(J))/2.0
  GO TO 15
IF(ELSKIA.GT.ELMAXB) ELSKIA=ELMAXB
  ARM1B(J)=XX(3,J)+ELSKIA/2.0
  ARM2B(J)=ZS-ELSKIA
  DFBS(J)=-DELP*ELSKIA*DELYBS
  ARG=0.5*RHOU*U*ELSKIA*DELYBS
  RESKI=U*ELSKIA/ENU
  CDTSKI=0.427/(ALOG10(RESKI)-0.407)**2.64
  TSKI8(J)=-ARG*CDTSKI
  GC TO 18
DFBS(J)=0.0
TSKIB(J)=0.0
CONTINUE
FX=FX+DFBS(J)
FK=FK+DFBS(J)*YAVGB(J)
FM=FM-DFBS(J)*ARM1B(J)+TSKIB(J)*ARM2B(J)
FN=FN+TSKIB(J)*YAVGB(J)
ALBS=ALBS+(GAP(J)+GAP(J+1))*DELYBS/2.0
CONTINUE
ALBS=ALBS+BLEAK
QL=CEBS*ALBS*SQR(2.0*ABS(PBAR)/RHCINF)*SIGN(1.0,PBAR)
IF(1BOWSL.NE.CN) RETURN
WRITE(6,100) GAP,ELSKI,FX,FY,FZ,FK,FM,FN
FORMAT(/10X,8HROW SEAL/26H GAP (FT.)/(PCRT TO STBD.)/11F10.5
100 1/28H ELSKI (FT.)/(PCRT TO STBD.)/11F10.5 /10X,23HBO*SL FX,FY,FZ,
2K,FM,FN/6E15.4)
END

```

```

C
C
C
C
SUBROUTINE COLFIL
QUESTIONS CONCERNING THE USE OF THIS SUBRCUTINE SHCULD BE REFERED
TO THE USERS' MANUAL CONTAINED IN THIS THESIS.
COMMON/AXIS/NXYS(26)
COMMON/COLUMN/IVERT,I,LATPL
COMMON/CURVE/NCURV(10)
COMMON/EQNCO/NEQS,TOL(20),JQQ
COMMON/GRAF/NGRAF,NDRW
CFL 0010
CFL 0020
CFL 0030
CFL 0040
CFL 0050
CFL 0060
CFL 0070
CFL 0080
CFL 0090
CFL 0100
CFL 0110

```









C L 0600  
 C F L 0610  
 C F L 0620  
 C F L 0630  
 C F L 0640  
 C F L 0650  
 C F L 0660  
 C F L 0670  
 C F L 0680  
 C F L 0690  
 C F L 0700  
 C F L 0710  
 C F L 0720  
 C F L 0730  
 C F L 0740  
 C F L 0750  
 C F L 0760  
 C F L 0770  
 C F L 0780  
 C F L 0790  
 C F L 0800  
 C F L 0810  
 C F L 0820  
 C F L 0830  
 C F L 0840  
 C F L 0850  
 C F L 0860  
 C F L 0870  
 C F L 0880  
 C F L 0890  
 C F L 0900  
 C F L 0910  
 C F L 0920  
 C F L 0930  
 C F L 0940  
 C F L 0950  
 C F L 0960  
 C F L 0970  
 C F L 0980  
 C F L 0990  
 C F L 1000  
 C F L 1010  
 C F L 1020  
 C F L 1030  
 C F L 1040  
 C F L 1050  
 C F L 1060  
 C F L 1070

```

IQ=IQ+1
XCUT(IQ)=PVQQ(INDX)
YOUT(IQ)=PVQQ(INDY)
GO TO 7
8 REWIND 1
  INX=INDX*2
  INY=INDY*2
  NAMEX(1)=NAMES(INX-1)
  NAMEX(2)=NAMES(INX)
  NAMEY(1)=NAMES(INY-1)
  NAMEY(2)=NAMES(INY)
  IF(NCUR.EQ.1) GO TO 20
  CALL PLOTP(XCUT,YOUT,-IQ,0)
  WRITE(6,301) NAMEX,NAMEY
301 FORMAT(' ',20X,2A8,' IS THE INDEPENDENT VARIABLE AND ',2A8,' THE DEPENDENT VARIABLE')
  GO TO 19
20 TITLE(8)=NAMEY(1)
  TITLE(9)=NAMEY(2)
  TITLE(11)=NAMEX(1)
  TITLE(12)=NAMEX(2)
  NCUR=NCUR+1
  IF(NCUR.NE.0) GO TO 25
  LABEL=LAB(1)
  CALL DXLAB(IQ,XCUT,YOUT,NCUR,0,LABEL,TITLE,C,0,0,0,8,0,8,0,LAST)
  J=J+1
  GO TO 19
25 WRITE(2)IQ,NCUR,NGF,LABEL,(TITLE(K),K=1,12),(XCUT(L),YOUT(L),L=1,10)
  NGF=NGF-1
  CONTINUE
19 IF((NGF.EQ.0).AND.(NCUR.EQ.3)) GO TO 26
  IF((IVERT.NE.1) GO TO 14
11 WRITE(6,100)
100 FORMAT('U',50X,'***SUMMARY ONE***',/, '0')
  K=0
  DO 31 I=1,8
  31 IF(I.SUM1(I).NE.0) K=K+1
  CONTINUE
  N=K*2
  IF(K.EQ.0) GO TO 14
  J=1
  DO 33 I=1,NUM1
  33 IDEX=ISUM1(I)*2
  INAME(J)=NAMES(IDEX-1)
  J=J+2
  
```







CFLL 1560  
 CFLL 1570  
 CFLL 1580  
 CFLL 1590  
 CFLL 1600  
 CFLL 1610  
 CFLL 1620  
 CFLL 1630  
 CFLL 1640

DMV 0010  
 DMV 0020  
 DMV 0030  
 DMV 0040  
 DMV 0050  
 DMV 0060  
 DMV 0070  
 DMV 0080  
 DMV 0090  
 DMV 0100  
 DMV 0110  
 DMV 0120  
 DMV 0130  
 DMV 0140  
 DMV 0150  
 DMV 0160  
 DMV 0170  
 DMV 0180  
 DMV 0190  
 DMV 0200  
 DMV 0210  
 DMV 0220  
 DMV 0230  
 DMV 0240  
 DMV 0250  
 DMV 0260  
 DMV 0270  
 DMV 0280  
 DMV 0290  
 DMV 0300  
 DMV 0310  
 DMV 0320  
 DMV 0330  
 DMV 0340  
 DMV 0350  
 DMV 0360  
 DMV 0370  
 DMV 0380

```

23 READ(1,END=16)(PVQQ(I),I=1,26)
DU 36 I=1,NUM2
J=ISUM2(I)
AFILE(I)=PVQQ(J)
WRITE(6,400)(AFILE(I),I=1,NUM2)
GC TO 23
REKIND 1
RETURN
I7 END

C
SUBROUTINE DMINV (A,N,D)
DIMENSION A(6,6),PIVOT(6)
DIMENSION IPVOT(6),INDEX(6,2)
EQUIVALENCE (IROW,JRCW),(ICOL,JCOL)
D=1.0
DO 17 J=1,N
DC PIVOT(J)=0
CONTINUE
DO 135 I=1,N
T=0.0
DO 9 J=1,N
IF(IPVOT(J)-1) 13,9,13
DO 23 K=1,N
IF(IPVOT(K)-1) 43,23,81
IF (ABS(T)-ABS(A(J,K))) 83,23,23
ICL=K
T=A(J,K)
CONTINUE
CONTINUE
IPVOT(ICOL)=IPVOT(ICOL)+1
IF(IROW-ICOL) 73,109,73
D=-D
DC 12 L=1,N
T=A(IROW,L)
A(IROW,L)=A(ICOL,L)
A(ICOL,L)=T
CONTINUE
INDEX(1,2)=IROW
INDEX(1,2)=ICOL
PIVOT(I)=A(ICOL,ICOL)
D=D*PIVOT(I)
DC 205 L=1,N
A(ICOL,L)=A(ICOL,L)/PIVOT(I)
CONTINUE
DO 134 LI=1,N

```





```

21 IF(LI-ICOL) 21,134,21
   T=A(LI,ICOL)
   A(LI,ICOL)=0.0
89 DO 89 L=1,N
134 A(LI,L)=A(LI,L)-A(ICOL,L)*T
135 CONTINUE
CONTINUE
DO 3 I=1,N
L=N-I+1
IF(INDEX(L,1)-INDEX(L,2)) 19,3,19
19 JRCW=INDEX(L,1)
   JCOL=INDEX(L,2)
DO 549 K=1,N
   T=A(K,JRCW)
   A(K,JCOL)=T
549 CONTINUE
81 RETURN
END

```

C C

```

SUBROUTINE FAN
INTEGER CN
COMMON /AIR/ PINF, RHOINF, GAM
COMMON /FANMAP/ QIN, QBFAN(25), QMFAN(25), QSFAN(25), ENBFAN, ENMFAN,
1 ENSFAN, BRPM, EMRPM, SRPM, NPTSB, NPTSM, NPTSS
2 , PBFAN(25), PMFAN(25), PSFAN(25), TMEB(25), DELB(25), NB, TMES(25),
3 DELS(25), NS
COMMON /PR/ INT/ON, IACCEL, IVEL, ITRAJ, ISIDL, IBOWSL, I STNSL, IWAVES,
- IRUD, IPROP, IAEROD, IRHS
COMMON /SOFTBS/ XBF, PBS, SINBS, COSBS, XBS, ZBS, DELYBS, DPBS, ELMAXB, YAVG
1 B(10)
COMMON /SOFTSS/ XLF, PSS, SINTH, CCSTH, XSS, ZSS, DELYSS, DPSS
1 , ELMAXS, YAVGS(10)
COMMON /VARBLE/ VAL(40)
DIMENSION QB(1), QM(1), QS(1), PBOW(1), PM(1), PS(1)
EQUIVALENCE (VAL(1), TIME), (VAL(2), U), (VAL(3), V), (VAL(4), W),
1 (VAL(5), P), (VAL(6), Q), (VAL(7), R), (VAL(8), PF1), (VAL(9), THETA),
2 (VAL(10), Z), (VAL(11), BMASS), (VAL(21), X), (VAL(22), Y), (VAL(23), PSI),
3 (VAL(24), PB)
EQUIVALENCE (VAL(18), FANPWR)
EQUIVALENCE (QB(FAN(1)), QB(1)), (QM(FAN(1)), QM(1)), (QS(FAN(1)), QS(1)),
1 ((PBFAN(1)), PBOW(1)), (PMFAN(1)), PM(1)), (PSFAN(1)), PS(1))
BRAT=3000/BRPM
EMRAT=3000/EMRPM

```



FAN 0270  
 FAN 0280  
 FAN 0290  
 FAN 0300  
 FAN 0310  
 FAN 0320  
 FAN 0330  
 FAN 0340  
 FAN 0350  
 FAN 0360  
 FAN 0370  
 FAN 0380  
 FAN 0390  
 FAN 0400  
 FAN 0410  
 FAN 0420  
 FAN 0430  
 FAN 0440  
 FAN 0450  
 FAN 0460  
 FAN 0470  
 FAN 0480  
 FAN 0490  
 FAN 0500  
 FAN 0510  
 FAN 0520  
 FAN 0530

FGI 0010  
 FGI 0020  
 FGI 0030  
 FGI 0040  
 FGI 0050  
 FGI 0060  
 FGI 0070  
 FGI 0080  
 FGI 0090  
 FGI 0100  
 FGI 0110  
 FGI 0120  
 FGI 0130  
 FGI 0140  
 FGI 0150  
 FGI 0160  
 FGI 0170  
 FRT 0010

```

SRAT=3000/SRPM
TL=VAL(1)
IF(NB.EQ.0.C) GO TO 5
DPBS=FGI(TL,NB,TMEB,DELBI,ILB)
PBS=PB+DPBS
5 IF(NS.EQ.0.C) GO TO 6
DPSS=FGI(TL,NS,TMES,DELS,ILS)
PSS=PB+DPSS
6 CONTINUE
PBI=PBSP-PINF
PB2=PBSP-PINF
PE3=PSS-PINF
PBARB=PB1*BRAT**2
PBARM=PB2*EMRAT**2
PBARS=PE3*SRAT**2

UBOW=ENBFAN*FGI(PBARB,NPTSB,PBOW,QB,IB)/BRAT
QMAIN=ENMFAN*FGI(PBARM,NPTSM,PM,QM,IM)/EMRAT
QSTN=ENSFAN*FGI(PBARS,NPTSS,PS,CS,IS)/SRAT
FANPWR=((QBOW*PB1+QMAIN*PB2+QSTN*PB3)/550.
IF(IRHS.NE.ON) RETURN
WRITE(6,100) QBOW,QMAIN,QSTN,PBARB,PBARM,PBARS
FORMAT(//4H FAN /32H Q - BOW,MAIN,STERN (CU FT /SEC) 3F12.1)
100 1 /28H DELP - BOW,MAIN,STERN (PSF) 3F11.2)
RETURN
END
C
C
FUNCTION IGN FGI(X,N,XT,YT,IX)
DIMENSION XT(1),YT(1)
IF(IX.LT.1) IX=1
IF(IX.GT.N-1) IX=N-1
I=SIGN(1.0,X-XT(IX))
IF(IX.LT.1) CR=X*GE.N) GO TO 30
IF(XT(IX)).GT.X) CR=X*GT.XT(IX+1)) GO TO 20
C=(X-XT(IX))/(XT(IX+1)-XT(IX))
GO TO 100
IX=IX+10
GO TO 10
C=IX/N
IX=IX-1
FGI=YT(IX)+C*(YT(IX+1)-YT(IX))
RETURN
END
100 C
C

```



```

SUBROUTINE FORIT(FNT,N,M,A,B,IER)
DIMENSION A(1),B(1),FNT(1)
CHECK FOR PARAMETER ERRORS
IER=0
IF(M) 30,40,40
IER=2
RETURN
IF(M-N) 60,60,50
IER=1
RETURN
C 60
COMPUTE AND PRESET CONSTANTS
CONTINUE
AN=N
COEF=2.0/(2.0*AN+1.0)
PI=4.*ATAN(1.)
CONST=PI*COEF
SI=SIN(CONST)
CI=CCS(CONST)
C=1.0
S=0.0
J=1
FNTZ=FNT(1)
U2=0.0
UI=0.0
I=2*N+1
C 70
FCRM FOURIER COEFFICIENTS RECURSIVELY
U0=FNT(I)+2.0*CU1-U2
U1=U0
I=I-1
IF(I-1) 80,80,75
A(J)=COEF*(FNTZ+ C*U1-U2)
B(J)=COEF*S*U1
IF(J-(M+1)) 90,100,100
Q=CI*C-SI*S
C=CI*S+SI*C
S=Q
J=J+1
GC TO 70
C 75
A(1)=A(1)*0.5
RETURN
END
C 80
C 90
C 100
C

```

```

T 0020
ERT 0030
ERT 0040
ERT 0050
ERT 0060
ERT 0070
ERT 0080
ERT 0090
ERT 0100
ERT 0110
ERT 0120
ERT 0130
ERT 0140
ERT 0150
ERT 0160
ERT 0170
ERT 0180
ERT 0190
ERT 0200
ERT 0210
ERT 0220
ERT 0230
ERT 0240
ERT 0250
ERT 0260
ERT 0270
ERT 0280
ERT 0290
ERT 0300
ERT 0310
ERT 0320
ERT 0330
ERT 0340
ERT 0350
ERT 0360
ERT 0370
ERT 0380
ERT 0390
ERT 0400
ERT 0410
ERT 0420
ERT 0430
ERT 0440
ERT 0450
ERT 0460
ERT 0470
ERT 0480

```



```

SUBROUTINE INCON (TIME)
REAL*8 TICRD
INTEGER ION
COMMON /AIR/ PINF,RHOINF,GAM
COMMON /AXIS/NXYS(26)
COMMON /BMCO / IMM,IMNX,IMNY,IBMFIL,BTIME,IMT,XMI(10),YMI(7),IX,IY
COMMON /COLUMN/ IVERT,ILATRL
COMMON /CONST/ PI,RAD,UO
COMMON /CNTRL/CONTW,CONTO,CONTH,QMULT,LCOVER,ACONTZ,ACONTW,ZEQUIL
COMMON /THEQL/ACBASE
COMMON /CURVE/NCURV(10)
COMMON /ENGINE/NPS,NPP,THSTS(25),THSTP(25),XP,YP,ZP,STHS,STHP,
A TIP(25),TIS(25)
COMMON /FAIK/ RHOA,XLAERD
COMMON /FANMAP/QIN,QBFAN(25),QMFBAN(25),QSFAN(25),ENBFAN,ENMFAN,
1 ENSFAN,BRPM,EMRPM,SRPM,NPTSB,NPTSM,NPTSS
2 ,PSFAN(25),PMFBAN(25),TMEB(25),DELB(25),NB,TMES(25),
3 DETS(25),NS
COMMON /FROUDE / FN,FNCRIT
COMMON /G80W/ XBOW
COMMON /GEOM/ WIDTH,XL,XX(4,11),YY(4,11),NSTA(4),AB,VCLNOM
1 ,DELS(4,10),XCP,ZCP
COMMON /GEUMSW/ XAVG(10),DS
COMMON /GRAF/NGRAF,NDRW
COMMON /HEADG/TICRD(6)
COMMON /PWAVE/ FNCNCON,PWVCON
COMMON /LEAKER/ALFAK,8LEAK,CFSS,CFBS
COMMON /MASSES/ AM,AIXX,AIYY,AIZZ,AIXZ,AIMAX,G,WEIGHT,RHC,NMASS,
- AMI(201),XI(201),YI(201),ZI(201),XS,ZS,HRHO
COMMON /MATRIX/ A(6,6)
COMMON /OPTION/ I3DOF,ISRGE,ITRIM
COMMON /PLENUM/XLBW,XBBW,ABW,BUBHGT
COMMON /PLVCOQ/NVI,NVD,NLI,NLD
COMMON /PRIME/ STIME,FTIME,DELT,DELPNT,TPRINT
COMMON /PRINT/CON,IACCEL,IVEL,ITRAJ,ISIDWL,IBGWSL,ISTNSL,IWAVES,
- IRUD,IPROP,IAEROD,IRHS
COMMON /ROLL/ PHIMAX,TRCLL
COMMON /RUDDR/ NPR,DELRRUD(25),XR,YR,ZR,IRDS,TL,RSPAN,RAREA,RASPR,
ARCLB,RTC,RUDANG,TIR(25)
COMMON /RISER/ AMPTC
COMMON /SOFTBS/XBF,PBS,SINBS,COSBS,XBS,ZBS,DELYBS,DPBS,ELMAXB,YAVG
1 B(10)
COMMON /SOFTSS/ XLF,PSS,SINTH,COSTH,XSS,ZSS,DELYSS,CPSS
1 ,ELMAXS,YAVGS(10)
COMMON /SIDE/FXSW,FYSW,FZSW,FMSW,FNSW,ALSW,YSW,XLSW,CFSW,CDSW
1 ,VAREA ,VCHORD,VSPAN,VANGLE,VCOG,VX,VY,VZ ,AVBMSW,DELX,VTC

```









```

PROGRAM CONTROL PARAMETERS
C 100 CCNTINUE
101 GC TO (101,102,103,104,105),IOPT
      STIME=TEMP(1)
      FTIME=TEMP(2)
      DELC=TEMP(3)
      DELPNT=TEMP(4)
      TPRINO=TEMP(5)
      IF (TPRINO.LT.(STIME+DELPNT) .TPRINO = STIME+DELPNT
      IF (DELO.GT.DELPNT) DELO=DELPNT
      IF (DELO.EQ.0.0) GO TO 140
      GC TO 10
200 READ(5,3003) NCURV
3003 FC RMAT(1011)
      GC TO 10
2100 READ(5,2210) ISUM1
2210 FC RMAT(812)
      GC TO 10
102 READ(5,191) IACCEL, IVEL, ITRAJ, ISIDWL, IBOWSL, ISTNSL, IWAVES, IRUD,
      1 IPROP, IAEROD, IRHS
      GC TO 10
103 READ(5,175) NEQS, JQQ, (TOL(J), J=1, NEQS)
104 READ(5,191) IVERT, ILATRL, NVI, NLD, NLI
      GC TO 10
105 CCNTINUE
      I3DDGF=TEMP(1)
      ISRGE=TEMP(2)
      ITRIM=TEMP(3)
      GC TO 10
      140 WRITE(6,195)
C 200 MASS DISTRIBUTION
      G=32.17
      RHHO=1.99
      GC TO (210,220,230), IOPT
210 IWM = 0
      WEIGHT = TEMP(1)
      AM = WEIGHT/G
      XS = TEMP(2)
      ZS = TEMP(3)
      AIYY = TEMP(4)
      AIY = TEMP(5)

```



INC 1450  
 INC 1460  
 INC 1470  
 INC 1480  
 INC 1490  
 INC 1500  
 INC 1510  
 INC 1520  
 INC 1530  
 INC 1540  
 INC 1550  
 INC 1560  
 INC 1570  
 INC 1580  
 INC 1590  
 INC 1600  
 INC 1610  
 INC 1620  
 INC 1630  
 INC 1640  
 INC 1650  
 INC 1660  
 INC 1670  
 INC 1680  
 INC 1690  
 INC 1700  
 INC 1710  
 INC 1720  
 INC 1730  
 INC 1740  
 INC 1750  
 INC 1760  
 INC 1770  
 INC 1780  
 INC 1790  
 INC 1800  
 INC 1810  
 INC 1820  
 INC 1830  
 INC 1840  
 INC 1850  
 INC 1860  
 INC 1870  
 INC 1880  
 INC 1890  
 INC 1900  
 INC 1910  
 INC 1920

```

C 212 AIZZ = TEMP(6)
      AIXZ = TEMP(7)
      INERTIA MATRIX OPERATIONS
      DO 211 I=1,6
      DO 211 N=1,6
      A(I,N) = 0.0
      DO 213 N=1,5
      A(N,N) = AM
      A(4,4) = AIXX
      A(5,5) = AIYY
      A(6,6) = AIZZ
      A(6,4) = -AIXZ
      A(6,4) = -AIXZ
      AIMAX = AMAX1(AM, AIXX, AIYY, AIZZ, ABS(AIXZ))
      DO 214 I=1,6
      A(I,J) = A(I,J)/AIMAX
      CALL DMINV(A,6,D)
      DO 215 J=1,6
      A(I,J) = A(I,J)/AIMAX
      IF (D.NE.0.0) GO TO 10
      WRITE (6,216)
      STOP
      READ X
      Y = I
      I = 1
      Z INPUT DIST. UP FROM KEEL-LINE
      220 READ (5,192) AMI(I), XI(I), YI(I), ZI(I)
      IF (AMI(I).LT.0.0) GO TO 224
      I = I+1
      IF (I.GT.201) GO TO 70
      GO TO 222
      224 NMASS = I-1
      SUM = 0.0
      SUZ = 0.0
      SUZ = 0.0
      DO 225 I=1,NMASS
      AMI(I) = AMI(I)/G
      SUM = SUM+AMI(I)
      SUZ = SUZ+AMI(I)*XI(I)
      SUZ = SUZ+AMI(I)*ZI(I)
      225 AMI(I) = SUM*2.0
      WEIGHT = AM*G
      ZS = AM*G
      XS = SUZ/SUM
      SUM = 0.0
      WEIGHT DISTRIBUTION - ASSUME TRANSVERSE (PORT/STBD) SYMMETRY
      INPUT DIST. FWD. OF (SIDEWALL) TRANSCM
      INPUT DIST. TO STARBOARD
  
```



INC 1930  
 INC 1940  
 INC 1950  
 INC 1960  
 INC 1970  
 INC 1980  
 INC 1990  
 INC 2000  
 INC 2010  
 INC 2020  
 INC 2030  
 INC 2040  
 INC 2050  
 INC 2060  
 INC 2070  
 INC 2080  
 INC 2090  
 INC 2100  
 INC 2110  
 INC 2120  
 INC 2130  
 INC 2140  
 INC 2150  
 INC 2160  
 INC 2170  
 INC 2180  
 INC 2190  
 INC 2200  
 INC 2210  
 INC 2220  
 INC 2230  
 INC 2240  
 INC 2250  
 INC 2260  
 INC 2270  
 INC 2280  
 INC 2290  
 INC 2300  
 INC 2310  
 INC 2320  
 INC 2330  
 INC 2340  
 INC 2350  
 INC 2360  
 INC 2370  
 INC 2380  
 INC 2390  
 INC 2400

```

SUX = 0.0
SUZ = 0.0
DC 226 I=1, NMASS
XI(I) = XI(I)-XS
ZI(I) = -ZI(I)+ZS
AMK(I) = AMI(I)*2.0
SUX+AMK*XI(I)*XI(I)
SUZ+AMK*YI(I)*YI(I)
SUM+AMK*ZI(I)*ZI(I)
226 AIXX = SUY+SUZ
AIYY = SUX+SUZ
AIZZ = SUM
GO TO 212
230 GO TO 10

XX AND YY TABLES
CONTINUE = TEMP(1)
NSTA(1) = TEMP(2)
NSTA(2) = TEMP(3)
NSTA(3) = TEMP(4)
XLTUT=TEMP(5)
GCTC 10

C 300

SIDEWALL ( INCLUDING APPENDAGES )
CONTINUE (401,402), IOPT
401 YSW=TEMP(1)
XLSW=TEMP(2)
CDSW=TEMP(3)
AVBMSW=TEMP(5)
REWIND 10
GOTO 10
C 402 BLOCK 4 OPTION 2 REMOVED. NO APENDAGES
CONTINUE

C 500 STERNSEAL
CONTINUE
XSSI=TEMP(1)
ZSS1=TEMP(2)
ALFAK=TEMP(3)
CFSS=TEMP(4)
  
```









C BLOCK 8 OPTION 2 REMOVED. ENGINE OUT INPUT IN BLOCK 16

INC 2890  
INC 2900  
INC 2910  
INC 2920  
INC 2930  
INC 2940  
INC 2950  
INC 2960  
INC 2970  
INC 2980  
INC 2990  
INC 3000  
INC 3010  
INC 3020  
INC 3030  
INC 3040  
INC 3050  
INC 3060  
INC 3070  
INC 3080  
INC 3090  
INC 3100  
INC 3110  
INC 3120  
INC 3130  
INC 3140  
INC 3150  
INC 3160  
INC 3170  
INC 3180  
INC 3190  
INC 3200  
INC 3210  
INC 3220  
INC 3230  
INC 3240  
INC 3250  
INC 3260  
INC 3270  
INC 3280  
INC 3290  
INC 3300  
INC 3310  
INC 3320  
INC 3330  
INC 3340  
INC 3350  
INC 3360

```

C 810 CCNTINUE
      GOTO 10

C 900 RUDDER
      CONTINUE
      GOTO (505,910,915),IOPT
      XRC = TEMP(1)
      YR = TEMP(2)
      ZR = TEMP(3)
      RSPAN = TEMP(4)
      RASPR = TEMP(5)
      RAREA = TEMP(6)
      RCLB = 2.*PI*RASPR/(RASPR+3.)
      RRC = TEMP(7)
      GOTO 10
      $10 NOT USED

C 910 CONTINUE
      GOTO 10
      GOTO 10

C 1000 AERODYNAMICS
      CONTINUE
      XLAERO = TEMP(1)
      BEAM = TEMP(2)
      PHCA = .5*RHCINF*XLAERO*BEAM
      GOTO 10

C 1100 WAVES
      CONTINUE
      IWAWSW = IOPT
      NWAVE = TEMP(1)
      IF(NWAVE .EQ. 0) GOTO 10
      IF(NWAVE .GT. 10) GOTO 70
      BETAD = TEMP(2)
      BEATA = BETAD/RAD
      CCSSBET = COS(BETA)
      SINBET = SIN(BETA)
      TC = 1.0
      GOTO (1104,1106),IWAWSW
      DO 1105 I=1,NWAVE
      READ(5,1190) OMEGA(I),AW(I)
      GOTO 10
      DO 1107 I=1,NWAVE
      READ(5,1190) WAVLEN(I),AW(I)
      GOTO 10

```



```

C 1200 INITIAL CONDITIONS
CONTINUE
UC = TEMP(1)
THE TO = TEMP(2)
DSO = TEMP(3)
DELPI = TEMP(4)
GO TO 10

C 1300
CONTINUE
INPUT COMPLETED. 1) PRINT ALL INPUT
WRITE(6,2004) TIME,FTIME,DELO,TPRINC,DELPNT
WRITE(6,2001) TACCEL,IVEL,ITRAJ,ISIDAL,IBCWSL,ISTNSL,IWAVES,IRJD,
1 IPROP,IAEROD,IRHS I3DGF,ISRGE,I TRIM
WRITE(6,2002) NEQS,(TOL(J),J=1,NEQS)
WRITE(6,2003) WEIGHT,XS,ZS,AIXX,AIYY,AIZZ,AIXZ
WRITE(6,217A) AIMAX
WRITE(6,2018) ANSTA
WRITE(6,450) YSW,XLSW,CFSW,CDSW,VANGLE,VSPAN,VCHORD,VXO,VY,VZO,
1 AVBMSW,VTC
WRITE(6,491) NAL,CAL,SAL,NDS,DDS,SDS,NTH,DTH,STH,NBB,DBB,SBB
IF(1) WRITE(6,1549) (XMC(J),J=1,IMNX)
IF(1) WRITE(6,1519) IMM,IMNX,IMNY,IBMFIL,BTIME,IMT
IF(1) WRITE(6,1559) (YMI(J),J=1,IMNY)
WRITE(6,2010) XLBW,XBBW
WRITE(6,2011) XLWIDTH,XCPO,VOLNOM,BUBHGT
WRITE(6,2020) DELPI,XLTGT
WRITE(6,2028) ENBFAN,BRPM,ENMFAN,EMRPM,ENSFAN,SRPM
WRITE(6,2013) XRG,YR,ZRO,RNO,RMAXO,RRATO,PREVO,DLRDO
1 WRITE(6,2012) XPO,YPO,ZPO
WRITE(6,2027) XLAERO,BEAM,PPBS,ELMAXB
WRITE(6,2026) XSSI,CFBS,DPBS,ELMAXB
WRITE(6,2025) XSSI,ZSSI,ALAEAK,CFSS,THSSI,CPSS,XLF
WRITE(6,2017) UO,THE TO:DSO
AND 2) INITIALIZE VARIABLES FOR CALCS.
C 1302 I=1,40
DO 1302 I=1,40
VAL(I) = 0.0
U = UC + I*.6889
XSS = -(XS-XSSI)
ZSS = ZS - ZSSI
THETA = THE TO/RAD
THE QL = THE TA
DS = ZS + DS
Z = -ZS + DS

```

```

INC 3370
INC 3380
INC 3390
INC 3400
INC 3410
INC 3420
INC 3430
INC 3440
INC 3450
INC 3460
INC 3470
INC 3480
INC 3490
INC 3500
INC 3510
INC 3520
INC 3530
INC 3540
INC 3550
INC 3560
INC 3570
INC 3580
INC 3590
INC 3600
INC 3610
INC 3620
INC 3630
INC 3640
INC 3650
INC 3660
INC 3670
INC 3680
INC 3690
INC 3700
INC 3710
INC 3720
INC 3730
INC 3740
INC 3750
INC 3760
INC 3770
INC 3780
INC 3790
INC 3800
INC 3810
INC 3820
INC 3830
INC 3840

```



INC 3850  
 INC 3860  
 INC 3870  
 INC 3880  
 INC 3890  
 INC 3900  
 INC 3910  
 INC 3920  
 INC 3930  
 INC 3940  
 INC 3950  
 INC 3960  
 INC 3970  
 INC 3980  
 INC 3990  
 INC 4000  
 INC 4010  
 INC 4020  
 INC 4030  
 INC 4040  
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 INC 4110  
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 INC 4220  
 INC 4230  
 INC 4240  
 INC 4250  
 INC 4260  
 INC 4270  
 INC 4280  
 INC 4290  
 INC 4300  
 INC 4310  
 INC 4320

```

ZEQUIL=Z
PHIMAX=0.
TRCLL=0.
IRDS=0
TL=0.0
C PARAMETERS TABLE
IF(NWAVE.EQ.0) GOTO 1321
AMPTC=1.30287
GOTO(1310,1315),I,WAVSW
DC 1311 I=1,NWAVE
WAVLEN(I)=2.*PI*G/(OMEGA(I)*OMEGA(I))
GOTO 1317
DC 1316 I=1,NWAVE
OMEGA(I)=SQRT(2.*PI*G/WAVLEN(I))
C CONTINUE

C CALCULATE INITIAL FREQUENCIES OF ENCOUNTER
DO 1318 I=1,NWAVE
WAVSLP(I)=360.0*AW(I)/WAVLEN(I)
OMEGAE(I)=2.*PI*(SQRT(G*WAVLEN(I)/(2.*PI))-U*COSBET)/WAVLEN(I)
ENCPER(I)=2.0*PI/OMEGAE(I)
C CONTINUE
WRITE (6,1191) NWAVE,BETAD,(OMEGA(I),OMEGAE(I),WAVLEN(I),AW(I),
1 WAVSLP(I),ENCPER(I),I=1,NWAVE)
GOTO 1322
WRITE (6,1192)
C CONTINUE
DC 1303 I=1,4
DC 1305 N=1,11
ETA(I,N)=0.0
DVCLW=0.0
FXWAV=0.0
FYWAV=0.0
FZWAV=0.0
FKWAV=0.0
FNWAV=0.0
ZBAP=Z
PHIBAR=PHI
THETBAR=THETA
TIME=STIME
DELT=DELLO
DPRINT=TPRINO-DELPNT
PWVCON=4.*WEIGHT/(RHO*G*XLBW)
FNCON=SQRT(XLBW*G)
VX=VX0-XS
VZ=VZ0-VZO
XP=XP0-XS
  
```

C 1310  
 1311  
 1315  
 1316  
 1317  
 C  
 1318  
 1321  
 1322  
 1303





INC 4330  
 INC 4340  
 INC 4350  
 INC 4360  
 INC 4370  
 INC 4380  
 INC 4390  
 INC 4400  
 INC 4410  
 INC 4420  
 INC 4430  
 INC 4440  
 INC 4450  
 INC 4460  
 INC 4470  
 INC 4480  
 INC 4490  
 INC 4500  
 INC 4510  
 INC 4520  
 INC 4530  
 INC 4540  
 INC 4550  
 INC 4560  
 INC 4570  
 INC 4580  
 INC 4590  
 INC 4600  
 INC 4610  
 INC 4620  
 INC 4630  
 INC 4640  
 INC 4650  
 INC 4660  
 INC 4670  
 INC 4680  
 INC 4690  
 INC 4700  
 INC 4710  
 INC 4720  
 INC 4730  
 INC 4740  
 INC 4750  
 INC 4760  
 INC 4770  
 INC 4780  
 INC 4790  
 INC 4800

```

XRC-XS
YPC=ZS-ZPC
ZP=ZS-ZRC
ZR=ZS-ZRC
IF (IMN.EQ. 0) GO TO 1305
DC 1304 J=1,IMNX
XMI(J)=XMC(J)-XS
CONTINUE
XCP=XCPD-XS
ZCP=ZS-BURHGT
XBS=XBSI-XS
N=NSTA(3)
ZBS=ZS-ZBSI
DC 1364 J=1,N
DELYBS=XBBW/(N-1)
XX(3,J)=XBS-XSSI
YY(3,J)=-0.5*XBBW+(J-1)*DELYBS
CONTINUE
N=N-1
DC 1367 J=1,N
YAVGB(J)=(YY(3,J+1)+YY(3,J))/2.
CONTINUE
N=NSTA(4)
DELYSS=XBBW/(N-1)
DC 1365 J=1,N
XX(4,J)=-XS
YY(4,J)=-.5*XBBW+(J-1)*DELYSS
CONTINUE
N=N-1
DC 1368 J=1,N
YAVGS(J)=(YY(4,J+1)+YY(4,J))/2.
CONTINUE
XBCW=XLIOT-XS
N=NSTA(1)
DELX=XBSI/(N-1)
DC 1309 J=1,2
DO 1309 I=1,N
XX(J,I)=(I-I)*DELX-XS
YY(J,I)=YSW*(2*I-J-3)
WRITE(6,1366)((XX(J,N),N=1,11),(YY(J,N),N=1,11),J=1,4)
FORMAT(17H XX AND YY ARRAYS /14H PORT SIDEWALL /2(11F10.2/),
1 15H STERN SEAL /2(11F10.2/),
2 11H STERN SEAL /2(11F10.2/))
N=NSTA(1)-1
DC 1308 I=1,N
XAVG(I)=DELX*(2*I-1)/2.-XS
CALL WAVES(TIME)
  
```











```

1910 TO 10
GCCNTINUE TEMP(1)
GCMFAN=TEMP(2)
EMRPM=TEMP(3)
NPTSM=TEMP(4)
IF (READIN.EQ.0.0) GO TO 10
READ (5,1950) (PMEAN(J),J=1,NPTSM)
READ (5,1950) (QMFAN(J),J=1,NPTSM)
GCCNTINUE
1915 GCCNTINUE TEMP(1)
ENSFAN=TEMP(2)
SRPM=TEMP(3)
NPTSS=TEMP(4)
READ (READIN.EQ.0.0) GO TO 10
READ (5,1950) (PSFAN(J),J=1,NPTSS)
READ (5,1950) (QSFAN(J),J=1,NPTSS)
GCCNTINUE
1950 GFORMAT(8F10.0)
ERRCR IN INPUT
CONTINUE
WRITE (6,79) ISYS
STOP
79 FFORMAT(24H INPUT ERROR -- STCP -- ISYS=,13)
98 FFORMAT(1H,20(/),50X,19H COMPLETED ALL RUNS )
99 FFORMAT(13,12,7F10.0)
191 FFORMAT(16I5)
195 FFORMAT(5F10.0)
1 FFORMAT(//10X,65HERROR IN INPUT --- DELT AND/CR DELPNT EQUALS ZERO)
1 FFORMAT(2I2/(8F10.0))
216 FFORMAT(//10X,82HERROR IN INPUT --- INPUT INERTIA ELEMENTS LEAD TO
ZERO DETERMINANT --- JOB ABORTED )
219 FFORMAT(22H INERTIA MATRIX, A1MAX 6E15.4/(22X,6E15.4))
305 FFORMAT(20H WEIGHT, C.G., INERTIA MOMENTS 7F12.3)
490 FFORMAT(11F7.0)
491 FFORMAT(15H SIDEWALL INPUT 12(F8.3,1X))
1190 FFORMAT(26H SIDEWALL TABLE PARAMETERS 4(I4,F7.3,F7.3))
11191 15X,16H OMEGA(SLOPE) OF WAVES I2,10H BETA(DEG)F5.0/15H OMEGA(RAD/SEC) ,
5X,16H WAVE LENGTH(FT) 5X,14H AMPLITUDE(FT)
1192 5X,16H MAX SLOPE (DEG) 5X,13H PERIOD,E(SEC)/(F8.4,12X,F8.4,4F20.3))
1519 FFORMAT(11H MOMENT CALC. CONTROL PARAMETERS 4I5, F8.3, I5 )
1522 FFORMAT(32H MOMENT CALC. AT X OF 11F10.3)
1549 FFORMAT(22H MOMENT CALC. AT Y OF 11F10.3)
1559 FFORMAT(22H MOMENT CALC. AT X OF 11F10.3)

```

```

5770 INC
5780 INC
5790 INC
5800 INC
5810 INC
5820 INC
5830 INC
5840 INC
5850 INC
5860 INC
5870 INC
5880 INC
5890 INC
5900 INC
5910 INC
5920 INC
5930 INC
5940 INC
5950 INC
5960 INC
5970 INC
5980 INC
5990 INC
6000 INC
6010 INC
6020 INC
6030 INC
6040 INC
6050 INC
6060 INC
6070 INC
6080 INC
6090 INC
6100 INC
6110 INC
6120 INC
6130 INC
6140 INC
6150 INC
6160 INC
6170 INC
6180 INC
6190 INC
6200 INC
6210 INC
6220 INC
6230 INC
6240 INC

```





```

2004 FORMAT(33H) SE MOTIONS AND LOADS PROGRAM - 20A4, /)
2001 -22H INITIAL START AND FINISH TIMES 2F10.2/
-18H START PRINTING AT F8.2, 17H TAGS IN INCREMENTS OF F8.2)
2002 FORMAT(24H) INTERMEDIATE PRINTATIONS, AND TOLERANCES I5/(10X, 10E12.2))
2003 -23H CRITICAL FROUDE NUMBER, F15.4, 5X, 19H TOTAL CRAFT LENGTH
2009 -15.4)
2010 -23H PLENUM, LENGTH AND WIDTH AT WATER 2F12.4/
2011 -34H PLENUM, LENGTH AND WIDTH AT HULL 2F12.4/
-35H PLENUM, CENTER OF PRESSURE AT FULL FLIGHT F12.4/
2012 -23H PLENUM, NOMINAL VOLUME F12.1, 10X, 6H FEIGT F12.4)
2013 -28H PROPELLER, X, Y, Z COORDINATES 3F12.4/
-41H RUDDER, X, Y, Z COORDINATES 3F12.4/
-33H RUDDER, ON, MAX RATE, REVERSE, INITIAL 5F12.4/
-33H RUDDER, SPAN, ASPECT, AREA, CL9, T/C 5F12.4)
2017 -39H INITIAL CONDITIONS, VELOCITY (KNOTS) = F7.2, 5X,
-13H PITCH (DEG) = F8.3, 5X, 12H DRAFT ((IN) = F8.2)
2018 -49H NUMBER OF STATIONS, SIDEWALLS ((P+S)), SEALS (B+S), 4I5)
2020 -38H PLENUM, INITIAL PRESSURE, GAGE (PSF) F8.2)
2021 -70H PROGRAM, INITIATION SWITCH SETTINGS (LATERAL PLANE, CONSTANT
SPEED, TRIM)
2022 -20A4)
2023 -1H1)
2025 -16H STERNSEAL INPUT 7F12.4)
2026 -16H BOWSEAL INPUT 7F12.4)
2027 -19H CAERO DYNAMICS INPUT 7F12.4)
2028 -33H FANS, NO. + RPM, BOW, MAIN, STERN 3(F10.C, F10.1))
END

```

```

SUBROUTINE INTGRL (TIME)
INTEGER ON
COMMON /BMCO / IMM, IMNX, IMNY, IBMFIL, BTIME, IMT, XMI(10), YMI(7), IX, IY
COMMON /EQNCO / NEGS, ICL(20), JQQ
COMMON /KSWTCH/ ITHRST
COMMON /MASSES/ AM, AIXX, AIYY, AIZZ, AIXZ, AIMAX, G, WEIGHT, RHO, NMAS,
COMMON /PRIME/ ATIME, ACCEL, IVEL, ITRAJ, ISIDLW, IBOWSL, ISTNSL, IWAVES,
COMMON /PRINT/ ON, IACEROD, IRHS
IRUD, IPROP, IAEROD, S(4), ISTAR
COMMON /STEP/ STEP2
COMMON /VALOLD / VAL(40)
COMMON /VARBLE/ VAL(40)
EQUIVALENCE (VAL(1), X), (VAL(2), Y(1))
DIMENSION Y(20), ERROR(20)

```

5







```

75 IF(ABS(ERROR(J)).GT.TOL(J)/16.) GC TO 9
CCNTINUE
DELT=2.*DELT
IF (DELT.GT.DELPNT) DELT=DELPNT
10 RETURN
9 STEP2=DELT
GO TO 10
8 DELT=DEL
IPASS=0
GO TO 10
11 DELT=DELT/2.
IF (DELT.LT. 1.E-6 ) GO TO 25
IF (J.WQ.EQ.2) GO TO 26
WRITE (6,666) TIME,DELT,J,ERROR(J),TOL(J)
27 IPASS=0
GC TO 15
26 STEP1=DELT/2.0
IF(STEP1.LT.STEP2)STEP2=STEP1
GC TO 27
25 WRITE ( 6,150 ) TIME,DELT,(K1(J),J=1,NEQS),VAL
STOP
100 FORMAT(/10X,23HINTGRL TIME,DELT,K1,VAL /2E15.4/2(5E15.4/),5(8E15.4
101 )
101 FORMAT(1H0,9X,33HTOTAL LATERAL ACCELERATION (G) = F12.4,
12X,5HD1 = E15.4)
150 FORMAT(1H1,10X,44HDELTA TIME LESS THAN 1.0E-6 -- JOB STOPS )
666 FORMAT(/10X,5HINT-J 2E30.5,I5,2E20.5)
END

SUBROUTINE PROP
INTEGER ON
COMMON /CONST/ PI,RAD,UO
COMMON /FPROP/ FX,FY,FZ,FK,FM,FN
COMMON /ENGINE/NPS,NPP,THSTS(25),X,YP,ZP,STHS,STHP,
ATIP(25),TIS(25)
COMMON /PRTINI/ON,IACCEL,IVEL,I TRAJ,ISIDWL,IBOWSL,ISTNSL,IWAVES,
-IRUD,IPROP,IAEROD,IRHS
COMMON/RUDDR/NPR,DELTRUD(25),XR,YR,ZR,IRCS,TL,RSPAN,RAREA,RASPR,
ARCLB,RTC,RUDANG,TIR(25)
COMMON /VARBLE/ VAL(40)
EQUIVALENCE (VAL(1),TIME),(VAL(2),U),(VAL(3),V),(VAL(4),W),
1(VAL(5),P),(VAL(6),Q),(VAL(7),R),(VAL(8),PFI),(VAL(9),THETA),
2(VAL(10),Z),(VAL(11),BMASS),(VAL(21),X),(VAL(22),Y),(VAL(23),PSI),PRP
3(VAL(24),PB)
DIMENSION THS(1),THP(1),TS(1),TP(1),RUD(1),TR(1)

```

```

INT 0670
INT 0680
INT 0690
INT 0700
INT 0710
INT 0720
INT 0730
INT 0740
INT 0750
INT 0760
INT 0770
INT 0780
INT 0790
INT 0800
INT 0810
INT 0820
INT 0830
INT 0840
INT 0850
INT 0860
INT 0870
INT 0880
INT 0890
INT 0900
INT 0910
INT 0920
INT 0930
INT 0940
INT 0950
PRP 0010
PRP 0020
PRP 0030
PRP 0040
PRP 0050
PRP 0060
PRP 0070
PRP 0080
PRP 0090
PRP 0100
PRP 0110
PRP 0120
PRP 0130
PRP 0140
PRP 0150
PRP 0160
PRP 0170
PRP 0180

```

C



```

EQUIVALENCE (THSTS(1),THS(1)),(THSTP(1),TTP(1)),(TIS(1),TS(1)),(TIPRP
AP(1),TP(1)),(TIR(1),TR(1)),(DELTRUD(1),RUD(1))
  0190 PRP
  0200 PRP
  0210 PRP
  0220 PRP
  0230 PRP
  0240 PRP
  0250 PRP
  0260 PRP
  0270 PRP
  0280 PRP
  0290 PRP
  0300 PRP
  0310 PRP
  0320 PRP
  0330 PRP
  0340 PRP
  0350 PRP
  0360 PRP
  0370 PRP
  0380 PRP
  0390 PRP
  0400 PRP
  0410 PRP
  0420 PRP
  0430 PRP
  0440 PRP
  0450 PRP
  0460 PRP
  0470 PRP
  0480 PRP
  0490 PRP
  0500 PRP
  0510 PRP
  0520 PRP
  0530 PRP
  0540 PRP
  0550 PRP
  0560 PRP
  0570 PRP
  0580 PRP
  0590 PRP
  0600 PRP
  0610 PRP
  0620 PRP
  0630 PRP
  0640 PRP
  0650 PRP
  0660 PRP

```

C                    CALCULATE THRUSTS AND MOMENTS INDIVIDUALLY  
5                    RUDANG=DELTRUD(1)  
6                    CD=COS(RUDANG)  
                    SD=SIN(RUDANG)  
                    IF(NPS.EQ.0.0) GO TO 2  
                    THSS=FGI(TL,NPS,TS,THS,IS)  
                    GO TO 4  
2                    THSS=THSTS(1)  
4                    IF(NPP.EQ.0.0) GO TO 3  
                    THSP=FGI(TL,NPP,TP,THP,IP)  
                    GO TO 1  
3                    THSP=THSTP(1)  
1                    THSTS=STHS\*THSS  
                    STHSTP=STHP\*THSP  
                    FXS=THSS\*CD+STHSTP\*SD  
                    EXP=THSP\*CD-STHSTP\*THSS  
                    FYS=-STHSTP\*CD+SD\*THSP  
                    FZS=-THSS\*THETA\*CD-STHSTS\*CD\*PHI  
                    FZSP=-THSP\*THETA\*CD+STHSTP\*CD\*PHI  
                    FY=FXP+FYS  
                    FZ=FZP+FZS  
                    FKP=-FZP\*YP-FYP\*ZP  
                    FKS=FZS\*YP-FYS\*ZP  
                    FMS=FZS\*(-XP)+FXS\*ZP  
                    FMP=FZP\*(-XP)+FXP\*ZP  
                    FNS=-FXS\*YP-FYS\*(-XP)  
                    FNP=FXP\*YP-FYP\*(-XP)  
                    FN=FNS+FNP  
                    IF (IPRUP.NE.ON) RETURN





```

WRITE(6,123)
1 FX,FY,FZ,FK,FM,FN
123 FORMAT(/10X,22HPROP F X,FY,FZ,FK,FM,FN /6E15.4)
RETURN
END

```

C C

```

SUBROUTINE RHS(VALUE)
INTEGER ON
COMMON /AIR/ PINE,RHOINF,GAM
COMMON /BMCO/ IMM,IMNX,IMNY,IBMFIL,BTIME,IMT,XMI(10),YMI(7),IX,IY
COMMON /COLUMN/ IVERT,ILATRL
COMMON /CONST/ PI,RAD,UO
COMMON /CNTRL/CONTW,CONTQ,CONTH,QMULT,LCUVER,ACONTZ,ACONTW,ZEQUIL
1,THEQL,ACBASE
COMMON /ENGINE/NPS,NPP,THSTS(25),THSTP(25),XP,YP,ZP,STHS,STHP,
ATIP(25),TIS(25)
COMMON /FANMAP/QIN,QBFAN(25),QSFAN(25),ENBFAN,ENMFAN,
1,ENSFAN,BRPM,MRPM,SRPM,NPTSB,NPTSM,NPTS
2,PBFAN(25),PMFAN(25),PSFAN(25),TMEB(25),DELB(25),NB,TMES(25),
3DETS(25),NS
COMMON /FAERD/ FXAED,FYAED,FZAED,FKAED,FMAED,FNAED
COMMON /FOBBS/FYBS,FZBS,FKBS,FMBS,FNBS,QLBS
COMMON /FORSS/FYSS,FZSS,FKSS,FMSS,FNSS,QLSS,FMS
COMMON /FPROP/ FXP,FYP,FZP,FKP,FMP,FNP
COMMON /FROUDE/ FN,FNCRIT
COMMON /FRUD/ FXRUD,FYRUD,FZRUD,FKRUD,FMRUD,FNRUD
COMMON /GBOW/ XBO
COMMON /GEOM/ WIDTH,XL,XX(4,11),YY(4,11),NSTA(4),AB,VCLNOM
1,DELS(4,10),XCPO,ZCP
COMMON /GEOMBS/DETABX(11),DETABT(11),ARM1B(10),ARM2B(10)
1,DF5S(10),TSKIB(10)
COMMON /GEOMSS/DETADX(11),DETADT(11),ARM1S(10),DFSS(10),TSKIS(10)
1,ARV2S(10)
COMMON /KSWTCH/ ITHRST
COMMON /MASSES/ AM,AIXX,AIYY,AIZZ,AIXZ,AIMAX,G,WEIGHT,RHO,NMASS,
AMI(201),XI(201),YI(201),ZI(201),XS,ZS,HRHO
COMMON /MATRIX/ A(6,6)
COMMON /MSLOW/ DF(2,10),DSWAV(2,10),FXH(2),FYH(2),FZH(2),FMH(2),
FNH(2),VEY(2),VEZ(2),FXV
1,FXW(2),FYW(2),FZW(2),FKW(2),FMW(2),FNW(2)
COMMON /MWAVE/ F3DOCF,ISRGE,ITRIM
COMMON /OPTION/ I3DOW,XBBW,ABW,BUBHGT
COMMON /PLENUM/ XLBW,XBBW,ABW,BUBHGT
COMMON /PRIME/ STIME,FIIME,DELT,DELPT,TPRINT
COMMON /PRINT/ON,IACCEL,IVEL,ITRAJ,ISIDLW,IBCWSL,ISTNSL,IWAVES,
IRUD,IPROP,IAEROD,IRHS
COMMON /PWAVE/ FNCN,PWVCON

```







```

THSTP(1)=THSTP(1)-GF(1)/2.
THST=THSTS(1)+THSTP(1)
IF(ITRIM,EQ,ON)
1WRITE(6,76) FXBS,FXSS,FXSW,FXRUD,FXP,FXWAV,FXAED,ABPB,FXPWAV,
ATHST
76FORMAT(/,10X,3HRHS
1/42H FX COMPONENTS (AS LISTED IN RHS +THRUST) /10E13.5)
GF(1)=0.0
11CONTINUE
GE(2)=-R*U*AM+FYBS+FYSS+FYRW+FYRUD+FYP+FYWAV+FYAED
+PZBS+PZSS+PZSW+PZRUD+PZRP+PZWAV+PZAED
GF(3)=WEIGHT*ABPB
GF(4)=FKBS+FKSW+FKRUD+FKP+FKWAV+FKAED +ABPB*PHI*(-Z)
C EFFECTIVE CENTER OF PRESSURE CALCULATION FOR XR-3 ONLY
XCP=-.05*U*.5925+XCP0
IF(U*.5925).GT.22.0) XCP=-.023*U*.5925+.262
C
GF(5)=FMS+FMSW+FMKUD+FMP+FMWAV+FMAED +ABPB*(XCP-THETA*Z)
+FXPWAV*ZS
FMBUB=ABPB*(XCP-THETA*Z)
FWAVZ=FXPWAV*ZS
GF(6)=FMS+FNSW+FNRUD+FNP+FNWAV+FNAED
IF(I3DOF,NE,1) GO TO 10J
GF(3)=0.0
GF(5)=0.0
CONTINUE
DO 1 I=1,6
VALUE(I)=0.0
DO 1 J=1,6
VALUE(I)=VALUE(I)+A(I,J)*GF(J)
CONTINUE
1
VALUE(7)=P
VALUE(8)=Q
VALUE(9)=W
C
IF(I3DOF,EQ,1) GO TO 325
BUBBLE PRESSURE EQUATION
QCUT=QLBS+QLSS+QLSW
CALL FAN
GCNTRL=0.0
VALUE(10)=RHOINF*(QIN-QCUT-GCNTRL)
GO TO 236
CONTINUE
325 VALUE(10)=0.0
CONTINUE
236
C WRITE DATA FILE FOR MOMENT AND SHEAR CALCS., IF REQUIRED
IF(IMT,NE,1) GO TO 111

```



```

NBS = NSTA(3)-1
NSS = NSTA(4)-1
NSSL = NSS/2+1

WRITE (IBMFIL) (VAL(I), I=1,24), ZBAR, PHIBAR, THEBAR,
FXW, FYW, FZW, FKW, FMW, FNW, (VALUE(I), I=1,10),
DF, DS*AV, FXH, FZH, FVH, FVY, VFZ, FXV,
FXRUD, FYRUD, FXP, FZP, FSS, FXS, FZBS,
FXAED, FYAED, FZAED, FMAED, FNSS)
X, FNBS, FNSS, (TSKIB(I), I=1, NSS)
Y, (TSKIB(I), DFBS(I), ARMIB(I), I=1, NBS)

111 CONTINUE

C CONSTANT LONGITUDINAL VELOCITY ( U )
IF (ISRGE.EQ.1) VALUE(1)=0.0

IF (ON.NE.1) RETURN
DO 2 I=1,3
ACCEL(I)=VALUE(I)/G
ANGACL(I)=VALUE(I+3)*RAD
CONTINUE
BCWACC=ACCEL(3)-XBC*VALUE(5)/G
STNACC=ACCEL(3)+XS*VALUE(5)/G
IF (INVERT.NE.ON) GO TO 10
ZD=Z+ZS
THETA=THETA*RAD
IF (ILATRL.NE.ON) GO TO 15
DEPSI=SI/RAD
RCG=GR*RAD
BETAS=-V/U*RAD
ACCLAT=(VALUE(2)+U*R)/G
DPHI=PHI
DRFT=12.0*ZD
VELRS=0.5925*U
DELRS=RUDANG*RAD
IF (RUS=U/R
TRADUS=U/R
GO TO 20
TRADUS=1.E8
WRITE(1) TIME, VAL(16), DRFT, THETA, PBAR, BCWACC, ACCEL(3), FANPWR, CPHI,
1 DEPSI, ACCLAT, VEL, TRADUS, RDEG, X, Y, GIN, QOUT, GF(1), FXPWAV, GF(2), GF(3)
2 GF(4), GF(5), GE(6), DELRS
IF (IRHS.NE.ON) RETURN
WRITE(6,77) FNBS, FMSS, FMRSW, FMRUD, FMP, FMWAV, FMAED, FMBUB, FMAVZ
77 FORMAT(0,6,77) X,6X,5HFMBSS=,E16.6,2X,5HFMRUD=,E16.6,2X,6HFMWAV=,E16.6,
AE16.6,/,0,6X,6HFMRSW=,E16.6,2X,6HFMWAV=,E16.6,
B/,0,6X,6HFMRSW=,E16.6,2X,6HFMWAV=,E16.6,
WRITE(6,401) FXPWAV
401 FCRMAT(0,6X,7HFXP*WAV=,E16.6)

```

```

1390 RHS
1400 RHS
1410 RHS
1420 RHS
1430 RHS
1440 RHS
1450 RHS
1460 RHS
1470 RHS
1480 RHS
1490 RHS
1500 RHS
1510 RHS
1520 RHS
1530 RHS
1540 RHS
1550 RHS
1560 RHS
1570 RHS
1580 RHS
1590 RHS
1600 RHS
1610 RHS
1620 RHS
1630 RHS
1640 RHS
1650 RHS
1660 RHS
1670 RHS
1680 RHS
1690 RHS
1700 RHS
1710 RHS
1720 RHS
1730 RHS
1740 RHS
1750 RHS
1760 RHS
1770 RHS
1780 RHS
1790 RHS
1800 RHS
1810 RHS
1820 RHS
1830 RHS
1840 RHS
1850 RHS
1860 RHS

```





```

WRITE(6,200) PBAR, FANPWR, QIN, QLBS, GLSW, QLSS
WRITE(6,215) AB, VOL
WRITE(6,150) GF, ACCCEL, ANGACL
WRITE(6,175) BC, ACC, STNACC
WRITE(6,213) VALUE, VAL
FCRMT(//10X,3)HRHS
120H GAGE PRESS. (PSF) = F7.2,5X,21HFAN POWER REQD (HP) = F8.2,
25X,27HFAN FLOW RATE (CU FT/SEC) = F9.2,
3//31H LEAKAGE FLOW RATE (CU FT/SEC) = F9.2,
411H SIDEWALL = F9.2,13H STERN SEAL = F9.2,
215 FCRMT(//13H PLENUM AREA= F9.2,10X,14HPLENUM VOLUME= F10.2)
213 FCRMT(//12H VALVE ARRAY 2(/10E13.4)/10H VAL ARRAY 4(/10E13.4))
15C FCRMT(//10X,24HTOTAL FORCES AND MCMENTS 6E12.4/10X,24HACCELERATION
-S G,DEG/SEC2 6E12.4)
175 FCRMT(//10X,16HBOB ACCEL. (G) = E12.4,21H STERN ACCEL. (G) = E12
-.4)
RETURN
END

SUBROUTINE RUDDER
INTEGER ON
COMMON /CONST/ PI,RAD,UO
COMMON /CRUD/ FX,FY,FZ,FK,FM,FN
COMMON /MASSES/ AM,AIXX,AIYY,AIZZ,AIXZ,AIMAX,G,WEIGHT,RHG,NMASS,
- AMI(201),XI(201),YI(201),ZI(201),XS,ZS,HRHC
COMMON /PRINT/ON,IACCEL,IRHS
- IRUD,IPROP,IAEROD,IRHS
COMMON/RUDDR/ NPR,DELTRJD(25),XR,YR,ZR,IRDS,TL,RSPAN,RAREA,RASPR,
ARCLB,RTC,RUDANG,TIR(25)
COMMON /VARBLE/ VAL(40)

EQUIVALENCE (VAL(1),TIME),(VAL(2),U),(VAL(3),V),(VAL(4),W),
1(VAL(5),P),(VAL(6),Q),(VAL(7),R),(VAL(8),PHI),(VAL(9),THETA),
2(VAL(10),Z),(VAL(11),EMASS),(VAL(21),X),(VAL(22),Y),(VAL(23),PSI),
3(VAL(24),PB)
EQUIVALENCE (DELTRUD(1),RUD(1)),(TIR(1),TR(1))
DIMENSION RUD(1),TR(1)
EQUIVALENCE (VAL(18),FANPWR)
DATA ENU /1.28E-5/

C
CALCULATE PROGRAMMED RUDDER DEFLECTION
TL=TIME
IF(NPR.EQ.0.0) GO TO 5
GC TO 6
RUDANG=DELTRUD(1)
5 RUDANG=RUDANG/RAD
GC TO 7

```

```

RHS 1870
RHS 1880
RHS 1890
RHS 1900
RHS 1910
RHS 1920
RHS 1930
RHS 1940
RHS 1950
RHS 1960
RHS 1970
RHS 1980
RHS 1990
RHS 2000
RHS 2010
RHS 2020
RHS 2030
RHS 2040

RUD 0010
RUD 0020
RUD 0030
RUD 0040
RUD 0050
RUD 0060
RUD 0070
RUD 0080
RUD 0090
RUD 0100
RUD 0110
RUD 0120
RUD 0130
RUD 0140
RUD 0150
RUD 0160
RUD 0170
RUD 0180
RUD 0190
RUD 0200
RUD 0210
RUD 0220
RUD 0230
RUD 0240
RUD 0250
RUD 0260
RUD 0270
RUD 0280
RUD 0290

```

C C

C



```

6 RUDANG=FG1(TL,NPR,TR,RUD,IR)
  RUDANG=RUDANG/RAD
  SIDE=FCRCE*CN*RUDDER
7 DSR=Z+ZS-XR*THETA
  ENDFACE=(1.+DSR/(DSR+RSPAN))
  VH=V+XR*Z-ZR*P
  QQ=HRHO*U*U+RAREA
  EFFANG=RUDANG-ENDFACE*VH/U
  FY=2.*QQ*ENDFACE*RCLB*EFFANG

C
DRAG FORCE CN RUDDER
REY=U*(RAREA/RSPAN)/ENU
CFR=.4277/(ALOG10(REY)+.407)*2.64
PI8=PI/8.
CC=2.*CFR+ PI8*RTC*RTC*(1.+G*RSPAN/(U*U))+RCLB*EFFANG*EFFANG
FX=-2.*CD*RAREA*HRHO*U*U

FZ=0.
FK=-ZR*FY
FN=FX*ZR
FN=XR*FY
IF(IRUD.NE.CN) RETURN
      WRITE(6,123)
123 FORMAT(/10X,24HRUDDER FX,FY,FZ,FK,FM,FN /6E15.4)
      RETURN
      END

C
SUBROUTINE SAM
WRITE(6,10)
10 FORMAT(1H1,'YOU HAVE CALLED A DUMMY SAM SUBROUTINE.'/
      RETURN
      END

C
SUBROUTINE SIDEWL
INTEGER ON
COMMON /AIR/ PINE,RHOINF,GAM
COMMON /BMCO/ IMM,IMNX,IMNY,IBMFIL,BTIME,IMT,XMI(10),YMI(7),IX,IY
COMMON /CONST/ PI,RAD,UO
COMMON /GEOM/ WIDTH,XL,XX(4,11),YY(4,11),NSTA(4),AB,VCLNCM
1,DELS(4),XCP,ZCP
COMMON /GEOMSW/ XAVG(10),DS
COMMON /KSWTCH/ ITHKST
COMMON /MASSES/ AMI(201),XI(201),YI(201),ZI(201),XS,ZS,HRHC
      AMI(201),XI(201),YI(201),ZI(201),XS,ZS,HRHC

```

```

RUD 0300
RUD 0310
RUD 0320
RUD 0330
RUD 0340
RUD 0350
RUD 0360
RUD 0370
RUD 0380
RUD 0390
RUD 0400
RUD 0410
RUD 0420
RUD 0430
RUD 0440
RUD 0450
RUD 0460
RUD 0470
RUD 0480
RUD 0490
RUD 0500
RUD 0510
RUD 0520
RUD 0530
RUD 0540
RUD 0550
RUD 0560
SAM 0010
SAM 0020
SAM 0030
SAM 0040
SAM 0050
SAM 0060
SAM 0070
SWL 0010
SWL 0020
SWL 0030
SWL 0040
SWL 0050
SWL 0060
SWL 0070
SWL 0080
SWL 0090
SWL 0100
SWL 0110
SWL 0120

```



```

CCOMON /MSIDW/ DF(2,10), DSWAV(2,10), FXH(2), FYF(2), FZH(2), FMH(2),
1 FNH(2), VFY(2), VFZ(2), FXV
CCOMON /PLENUM/ XLBWL, XBBW, ABW, BUBHGT
CCOMON /PRIME/ STIME, FTIME, DELT, DELPNT, IPRINT
CCOMON /PROP/ IAERGD, IRHS, IZBAR, PHIBAR, THEBAR, COSEET, SINBET
-IRUD, IPRD, IAERGD, IRHS, IZBAR, PHIBAR, THEBAR, COSEET, SINBET
COMMON /SIDE/ FX, FZ, FK, FM, FN, ALSW, YSW, XLSW, CFSW, CDSW
1, VAREA, VCHORD, VSPAN, VANGLE, VCO3, VX, VY, VZ, AVBMSH, DELX, VTC
CCOMON /WAVE/ ETA(4,11), AW(10), CMEGA(10), DVCLW, NWAWE, BETA,
FXWAV, FYWAV, FZWAV, FKWAV, FMWAV, FNWAV
COMMON /WAVTAB/ NAL, DAL, SAL, NDS, DDS, NTH, DTH, STH, NBB, DBB, SBB,
1 AC1(20,5,7), AC2(20,5,7), AC3(20,5,7), AC4(20,5,7),
2 AC5(20,5,7), AC6(20,5,7), AC7(20,5,7)
3 AC8(20,5,7), AC9(20,5,7), AC10(20,5,7),
4 AS1(20,5,7), AS2(20,5,7), AS3(20,5,7), AS4(20,5,7),
5 AS5(20,5,7), AS6(20,5,7), AS7(20,5,7)
6 AS8(20,5,7), AS9(20,5,7), AS10(20,5,7),
7 AS11(20,5,7), AS12(20,5,7), AS13(20,5,7),
EQUIVALENCE (VAL(2),U), (VAL(3),V), (VAL(4),W),
1 (VAL(5),P), (VAL(6),Q), (VAL(7),R), (VAL(8),PI), (VAL(9),THETA),
2 (VAL(10),Z), (VAL(11),BMASS), (VAL(21),X), (VAL(22),Y), (VAL(23),PSI),
3 (VAL(24),PB)
DIMENSION GAP(2,11), DSW(2,11)
DATA ENU /1.28E-5/
C
GAP OR WETTED DRAFT CALCULATION
DC 5 I=1,2
DC 5 J=1,11
GAP(I,J)=0.0
DSW(I,J)=0.0
CONTINUE
5 DO 10 J=1,2
DO 10 K=1,N
DC=ZS+Z+Y*(J,K)*PHI-XX(1,K)*THETA+ETA(J,K)
IF (DD.LT.BUBHGT) GC TO 101
IF (VAL(11)-TOLD.LT. DELPNT) GO TO 101
TCLD = VAL(1)
WRITE (6,100) XX(J,K), VAL(1), DD
100 FFORMAT (/10X,43H WATER CONTACT WITH TOP OF BUBBLE CHAMBER AT F7.2,
101 TIME = F7.2,19H SEC.
CONTINUE
GAP(J,K)=(SIGN(1.,DD)-1.)*DD/2.
DSW(J,K)=(SIGN(1.,DD)+1.)*DD/2.
10 CONTINUE

```



```

C      LEAKAGE AREA
      ALSW=0.0
      DC 20 J=1,2
      N=NSTA(J)-1
      DC 20 I=1,N
      ALSW=ALSW+(GAP(J,I)+GAP(J,I+1))*DELX/2.
      CONTINUE
      20
C      CRCS--FLOW DRAG ON SIDEWALLS
      FYD=0.0
      FKD=0.0
      FND=0.0
      DO 15 I=1,2
      N=NSTA(I)-1
      DC 15 J=1,N
      DSWAV(I,J)=(DSW(I,J)+DSW(I,J+1))/2.
      VREL = V+XAVG(J)*R-(ZS-DSWAV(I,J)/2.)*P
      *ABS(VREL
      *DSWAV(I,J)
      DF(I,J)=-
      HRHC#CDSW*VREL
      FYD=FYD+DF(I,J)
      FND=FND+DF(I,J)*XAVG(J)
      FKD=FKD-(ZS-DSWAV(I,J)/2.)*DF(I,J)
      15
C      SET UP STERN LIMIT OF FORCE DETERMINATION
      XSS = -XS
      GC TO 16
      ENTRY SIDWLM
      XSS = XMI(IX)
      16
      IP=1.+(THETA*RAD-STH)/DTH
      IP=MAXO(MINO(IP,NTH),1)
      IP=MINO(IP+1,NTH)
      DTHETA=(IP-1)*DTH+STH
      DIP= (THETA*RAD-DTHETA)/DTH
      C      CALC REYNOLDS NO. AND DRAG COEFF.
      REY=U*XLSW/ENU
      CDT=.427/(ALOG10(REY)-.407)**2.64
      C      SIDEWALL FORCES, P/S
      DO 40 J=1,2
      WAREA=0.0
      N=NSTA(J)-1
      NI = (XSS+XS)*N/XLSW+1.5
      DO 21 I=NI,N
      ZOR1=1.
      IF(DSWAV(J,I).EQ. 0.0) ZOR1=0.0

```









```

FNH(J) = FZH(J)*XSS-U*((V-ZS**P)**BC5+R**BC6)
IF (IMT.EQ.2) GO TO 40

C
39  CALC OF FORCE ON VENTRAL FINS REMOVED
    CCNTINUE

40  CCNTINUE
    IF (IMT.EQ.2) RETURN

C
    TCTAL SIDEWALL FORCES AMD MGMTS
    FX=FXH(1)+FXH(2)
    FY=FYH(1)+FYH(2)
    FZ=FZH(1)+FZH(2)
    FK=(FZH(2)-FZH(1))*YSW      +FKD -FY*ZS
    FY=FY+FYD
    FM=FMH(1)+FMH(2)+ZS*FX
    FN= FND +FNH(1)+FNH(2) +(FXH(1)-FXH(2))*YSW

C
    DRAG FORCE ON FINS REMOVED
    IF (ISIDWL.NE.ON) RETURN
    DC 41 I=1,2
    DO 41 J=1,11
    GAP(I,J)=12.0*D*GAP(I,J)
    DSW(I,J)=12.0*D*DSW(I,J)
    WRITE(6,123) ((GAP(I,J), J=1,11), I=1,2), ((DSW(I,J), J=1,11), I=1,2),
1  FEX,FY,FZ,FK,FM,FN
123  FORMAT(/10X,8HSIDEWALL/25H GAP (FT.) (STERN TO BOW) /14H PORT SIDE
1  EWALL /11F10.5/14H STBD SIDEWALL /11F10.5/37H IMMERSION DEPTH (FT.
2) (STERN TO BOW) /14H PORT SIDEWALL /11F10.5/14H STBD SIDEWALL /
3  11F10.5/10X,26HSIDEWALL FX,FY,FZ,FK,FM,FN /6E15.4)
    RETURN
    END

C
    SLBROUTINE STNSL
    INTEGER ON
    COMMON /AIR/ PINF,RHOINF,GAM
    COMMON /CONST/ PI,RAD,UO
    COMMON /FORSS/ FX,FY,FZ,FK,FM,FN,QL,FMS
    COMMON /GEOM/ WIDTH,XL,XX(4,11),YY(4,11),NSTA(4),AB,VCLNOM
1  DELS(4,10),XCP,ZCP
    COMMON /GEOMSS/DETADX(11),DETADT(11),ARMIS(10),DFSS(10),TSKIS(10)
1  ARM2S(10)
    COMMON /KSWTCH/ ITHRST
    COMMON /LEAKER/ ALEAK,CFSS
    COMMON /MASSES/ AM,AIXX,AIYY,AIZZ,AIMAX,G,WEIGHT,RHO,NMASS,
    AMI(201),XI(201),YI(201),ZI(201),XS,ZS,HRHC

```



```

COMMON /PRTINT/ON, IACCEL, IVEL, ITRAJ, ISIDLW, IBCWSL, ISTNSL, IWAVES,
-IRUD, IPROP, IAEROD, IRHS
C COMMON /SOFTSS/ XLF, PSS, SINTH, COSTH, XSS, ZSS, DELYSS, DPSS
1 ELMAXS, YAVGS(10)
COMMON /STSLR/ CPHI, CPHID
COMMON /VALOLD / YULD(20)
COMMON /VARBLE/ VAL(40)
COMMON /WAVE/ ETA(4,11), AW(10), OMEGA(10), DVCLW, NWAVE, BETA,
FXWAV, FYWAV, FZWAV, FMWAV, FMWAV, FMWAV
, ZBAR, PHIBAR, THERAR, TC, COSEET, SINSET, PBBAR
1 2
EQUIVALENCE (VAL(1), TIME), (VAL(2), U), (VAL(3), V), (VAL(4), W),
1 (VAL(5), P), (VAL(6), Q), (VAL(7), R), (VAL(8), PHI), (VAL(9), THETA),
2 (VAL(10), Z), (VAL(11), BMASS), (VAL(21), X), (VAL(22), Y), (VAL(23), RSI),
3 (DIMENSION GAP(11), ELSKI(11)
C DIMENSION UWSKI, CLSKI / 1.28E-5, 0.0, 1.5708/
DO 5 J=1,11
GAP(J)=0.0
ELSKI(J)=0.0
C CONTINUE
5 ALSS=0.0
FX=0.0
FZ=0.0
FK=0.0
FN=0.0
DEL P=PSS-PB
IF (DELP.LT.0.0) DELP=0.0
PBAR=PB-PINF
C CALCULATE ELSKI HERE.
SINDIF=SINTH-COSTH*THETA
COSDIF=COSTH+SINTH*THETA
XI=XSS+ZSS*THETA-XLF*SINDIF
Z1=(-Z-ZSS+XSS*THETA-XLF*COSDIF)
C CALCULATE GAP HERE.
N=NSTA(4)
DO 10 K=1,N
ELSKI(K)=(ETA(4,K)-DETADX(K)*((X(4,K)-X1)-Z1)+YY(4,K)*PHI
GAP(K)=-ELSKI(K)
IF (GAP(K).LT. 0.0) GAP(K)=0.0
C CONTINUE
10
N=NSTA(4)-1
DC 20 J=1,N

```

```

SSL 0150
SSL 0160
SSL 0170
SSL 0180
SSL 0190
SSL 0200
SSL 0210
SSL 0220
SSL 0230
SSL 0240
SSL 0250
SSL 0260
SSL 0270
SSL 0280
SSL 0290
SSL 0300
SSL 0310
SSL 0320
SSL 0330
SSL 0340
SSL 0350
SSL 0360
SSL 0370
SSL 0380
SSL 0390
SSL 0400
SSL 0410
SSL 0420
SSL 0430
SSL 0440
SSL 0450
SSL 0460
SSL 0470
SSL 0480
SSL 0490
SSL 0500
SSL 0510
SSL 0520
SSL 0530
SSL 0540
SSL 0550
SSL 0560
SSL 0570
SSL 0580
SSL 0590
SSL 0600
SSL 0610
SSL 0620

```



```

ELSKIA=(ELSKI(J+1)+ELSKI(J))/2.
IF (ELSKIA.LE.0.0) GO TO 15
IF (ELSKIA.GT.ELMAXS) ELSKIA=ELMAXS
ARMIS(J)=XX(4,J)+ELSKIA/2.
ARM2S(J)=-ZS-ELSKIA
DFSS(J)=-DELP*ELSKIA+DELYSS
ARGF=.5*RFQ*U*ELSKIA/ENU
RESKI=U*ELSKIA/ENU
CDTSKI=.427/(ALOG10(RESKI)-.407)**2.64
TCSKI(J)= - ARG*CDTSKI
GO TO 18
DFSS(J) = 0.0
TSKIS(J) = 0.0

15 CONTINUE
FX=FX+TSKIS(J)
FZ=FZ+DFSS(J)
FK=FK+DFSS(J)*YAVGS(J)+TSKIS(J)*ARM2S(J)
FM=FM-DFSS(J)*ARMIS(J)
FN=FN-TSKIS(J)*YAVGS(J)
ALSS=ALSS+(GAP(J)+GAP(J+1))*DELYSS/2.0
CONTINUE

20 ALSS=ALSS+ALEAK
QL=CFSS*ALSS*SQRT(2.*ABS(PBAR)/RHCINF)*SIGN(1.,PBAR)
IF (ISTNSL.NF.ON) RETURN
WRITE(6,100) GAP,ELSKI,FX,FY,FZ,FK,FM,FN
FORMAT(/12H STERN SEAL/26H GAP (FT.) PORT TO STBD. /11E11.3
100 1/28H ELSKI (FT.) PORT TO STBD. /11E11.3/1CX,23HSTNSL
2,FM,FN/6E15.4)
RETURN
END

C
FUNCTION T1(X)
IF(ABS(X)-.1) 10,10,20
T1=X*(1.-X*X/10.0)/3.
RETURN
T1=(SIN(X)-X*COS(X))/(X*X)
RETURN
END

C
FUNCTION T2(X)
IF(ABS(X)-.1) 10,10,20
T2=1.-X*X/6.
RETURN
END

```

```

SSJ 0630
SSL 0640
SSL 0650
SSL 0660
SSL 0670
SSL 0680
SSL 0700
SSL 0710
SSL 0720
SSL 0730
SSL 0740
SSL 0750
SSL 0760
SSL 0770
SSL 0780
SSL 0790
SSL 0800
SSL 0810
SSL 0820
SSL 0830
SSL 0840
SSL 0850
SSL 0860
SSL 0870
SSL 0880
SSL 0890
SSL 0900
SSL 0910
SSSL 0920
SSSL 0930
SSSL 0940
SSL 0950
T1 0010
T1 0020
T1 0030
T1 0040
T1 0050
T1 0060
T1 0070
T1 0080
T2 0010
T2 0020
T2 0030
T2 0040
T2 0050

```





20  
C

```

T2=SIN(X)/X
RETURN
END
SUBROUTINE WAVES(TIME)
INTEGER DIN
COMMON /BMCO / IMM, IMNX, IMNY, IBMFIL, BTIME, IMT, XMI(10), YMI(7), IX, IY
COMMON /CONST / PI, RAD, UO
COMMON /GEOM / XL, XX(4,11), YY(4,11), NSTA(4), AB, VCLNOM
1, CELS(4,10), XCPO, ZCP
COMMON /GEOMBS / DETABX(11), DETABT(11), ARMB(10), ARM2B(10)
1, DEFS(10), TSKIB(10)
COMMON /GEOMSS / DETADX(11), DETADT(11), ARMS(10), DFSS(10), TSKIS(10)
1, ARM2S(10)
COMMON /MASSES / AM, AIXX, AIYY, AIZZ, AIXZ, AIMAX, G, WEIGHT, RHO, NMASS,
ANI(201), XI(201), YI(201), ZI(201), XS, ZS, HRHO
COMMON /MWAVE / FXW(2), FYW(2), FZW(2), FKw(2), Fmw(2), FNW(2)
COMMON /PLENUM / XLBW, XBBW, ABW, BURFCT
COMMON /PRINT / ON, IACCEL, IVEL, ITRAJ, ISIDLW, IBCWSL, ISTNSL, IMAVES,
IRUD, IPROP, IAEROD, IRHS
COMMON /RISER / AMP, TC
COMMON /SIDE / FXSW, FYSW, FZSW, FKSW, FMSW, FNSW, ALSW, YSW, XLSW, CFSW, CDSW
1, VAREA, VCHORD, VSPAN, VANGLE, VCOSS, VX, VY, VZ, AVBMSW, DELX, VTC
COMMON /VARBLE / VAL(40)
COMMON /WAVE / ETA(4,11), AW(10), CMEGA(10), DVCLW, NWAWE, BETA,
FXWAV, FYWAV, FZWAV, FMKAV, ENWAV
1, ZBAR, PHIBAR, THEBAR, TC, COSBET, SINBET, PBBAR
COMMON /WAVTAB / NAL, DAL, SAL, NDS, DDS, SDS, NTH, DTH, STH, ABB, DBB, SBB,
AC1(20,5,7), AC2(20,5,7), AC3(20,5,7), AC4(20,5,7), AC5(20,5,7),
AC6(20,5,7), AC7(20,5,7), AC8(20,5,7),
AC9(20,5,7), AC00(20,5,7), AS1(20,5,7), AS2(20,5,7), AS3(20,5,7),
AS4(20,5,7), AS5(20,5,7), AS6(20,5,7), AS7(20,5,7),
AS0(20,5,7), AS00(20,5,7), AS8(20,5,7)
1, RB(36), XREF, PX
DIMENSION WCJ(2), WCOU(2), WC1(2), WC2(2), WC3(2), WC4(2), WC5(2), WC6(2)
1, WC7(2), WC8(2)
DIMENSION WSO(2), WSOO(2), WS1(2), WS2(2), WS3(2), WS4(2), WS5(2), WS6(2)
1, WS7(2), WS8(2)
EQUIVALENCE
1(VAL(5),P), (VAL(6),Q), (VAL(7),R), (VAL(8),PHI), (VAL(9),THETA),
2(VAL(10),Z), (VAL(11),BMASS), (VAL(21),X), (VAL(22),Y), (VAL(23),PSI),
3(VAL(24),PB)
EQUIVALENCE (VAL(16),ETACG)
IF (NWAWE.EQ.0) RETURN

```

T2 0060  
T2 0070  
T2 0080  
WVS 0010  
WVS 0020  
WVS 0030  
WVS 0040  
WVS 0050  
WVS 0060  
WVS 0070  
WVS 0080  
WVS 0090  
WVS 0100  
WVS 0110  
WVS 0120  
WVS 0130  
WVS 0140  
WVS 0150  
WVS 0160  
WVS 0170  
WVS 0180  
WVS 0190  
WVS 0200  
WVS 0210  
WVS 0220  
WVS 0230  
WVS 0240  
WVS 0250  
WVS 0260  
WVS 0270  
WVS 0280  
WVS 0290  
WVS 0300  
WVS 0310  
WVS 0320  
WVS 0330  
WVS 0340  
WVS 0350  
WVS 0360  
WVS 0370  
WVS 0380  
WVS 0390  
WVS 0400  
WVS 0410  
WVS 0420  
WVS 0430  
WVS 0440



```

C EFFECTIVE CENTER OF PRESSURE CALCULATION FOR XR-3 ONLY
XCP=-.05*U+.5925+XCPO
IF (U*.5925).GT.22.0) XCP=-.023*U+.5925+.262

C
GAMMA=BETA-PSI
SIGAM=SIGN(GAMMA)
COGAM=CCS(GAMMA)
FO=-X+COBET -Y+SINBET

DVOLK=0.0
ETACG=0.0
N=NSTA(3)
DO 1 J=1,N
DETABX(J)=0.0
CONTINUE
N=NSTA(4)
DC 2 J=1,N
DETADX(J)=0.0
CONTINUE
DC 10 J=1,4
N=NSTA(J)
DO 10 K=1,N
ETA(J,K)=0.0
DC 15 J=1,2
FXW(J)=0.0
FYW(J)=0.0
FZW(J)=0.0
FKW(J)=0.0
FNW(J)=0.0
FNW(J)=0.0
15 CCNTINUE

XSS=-XS
IF (IMT.EQ.2) XSS=XMI(IX)
IP=1+(THEBAR*RAD-STH)/DTH
IP=MAXO(MINO(IP,NTH),1)
IP1=MINO(IP+1,NTH)
DTHETA=(IP-1)*DTH+STH
DIP=(THETA*KAD-OTHETA)/DTH

C TIME RISE FACTOR FOR WAVE AMPLITUDE
AMPFAC=1.-EXP(-TIME/AMPTC)
DO 100 I=1,NWAVE
CM1=OMEGA(I)
CM2=OMI*CM1
XWK=OM2/G

```

```

WVS 0450
WVS 0460
WVS 0470
WVS 0480
WVS 0490
WVS 0500
WVS 0510
WVS 0520
WVS 0530
WVS 0540
WVS 0550
WVS 0560
WVS 0570
WVS 0580
WVS 0590
WVS 0600
WVS 0610
WVS 0620
WVS 0630
WVS 0640
WVS 0650
WVS 0660
WVS 0670
WVS 0680
WVS 0690
WVS 0700
WVS 0710
WVS 0720
WVS 0730
WVS 0740
WVS 0750
WVS 0760
WVS 0770
WVS 0780
WVS 0790
WVS 0800
WVS 0810
WVS 0820
WVS 0830
WVS 0840
WVS 0850
WVS 0860
WVS 0870
WVS 0880
WVS 0890
WVS 0900
WVS 0910
WVS 0920

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WVS 0930  
 WVS 0940  
 WVS 0950  
 WVS 0960  
 WVS 0970  
 WVS 0980  
 WVS 0990  
 WVS 1000  
 WVS 1010  
 WVS 1020  
 WVS 1030  
 WVS 1040  
 WVS 1050  
 WVS 1060  
 WVS 1070  
 WVS 1080  
 WVS 1090  
 WVS 1100  
 WVS 1110  
 WVS 1120  
 WVS 1130  
 WVS 1140  
 WVS 1150  
 WVS 1160  
 WVS 1170  
 WVS 1180  
 WVS 1190  
 WVS 1200  
 WVS 1210  
 WVS 1220  
 WVS 1230  
 WVS 1240  
 WVS 1250  
 WVS 1260  
 WVS 1270  
 WVS 1280  
 WVS 1290  
 WVS 1300  
 WVS 1310  
 WVS 1320  
 WVS 1330  
 WVS 1340  
 WVS 1350  
 WVS 1360  
 WVS 1370  
 WVS 1380  
 WVS 1390  
 WVS 1400

AA=AV(I)\*AMPFAC  
 FI=OMI\*TIME+XWK\*FO  
 AL=XWK\*COGAM

IAA=1+(ABS(AL)-SAL)/DAL  
 IAAO=MAXO(MINO(IAA,NAL):1)  
 IAAI=MINO(IAA+1,NAL)  
 ICAA=(IAA-1)\*DAL+SAL  
 DIA=(ABS(AL)-DAA)/DAL  
 SALP=SIGN(1.,AL)

C WAVE FORCES AND MOMENTS ON THE SIDEWALLS

DO 40 J=1,2  
 YLSW=(2\*J-3)\*YSW  
 WE=FI+XWK\*SIGAM\*YLSW  
 ST=SIN(WE)  
 CT=COS(WE)  
 DS=ZBAR+ZS+YLSW\*PHIBAR  
 DSR=DS-(XREF-XS)\*THEBAR  
 ID=1+(DSP+I2.-SDS)/DDS  
 ID=MAXO(MINO(ID,NDS):1)  
 DCSR=(IC-1)\*DDS+SDS  
 DID=(DSR+I2.-DDSR)/DDS  
 IDI=MINO(ID+1,NDS)  
 DSS=DS-XSS\*THEBAR  
 ZORI=(SIGN(1.,DSS)+1.)/2.  
 DSS=DS+ZORI  
 IDSS=1.5+(DSS-SBB)/DBB  
 IDS=MINO(NBB,IDSS)  
 ES=BB\*(ICSS)  
 CK=COS(XWK\*COGAM\*XSS)  
 A33S=(RHO\*PI\*BS\*Y2)/8.  
 SK=SIN(XWK\*COGAM\*XSS)  
 A22S=(RHO\*.4\*PI\*DDS\*Y2)/2.  
 A42S=0.0

C INTERPOLATION OF WAVE TABLES

K=1  
 L=IAA  
 CCNTINUE  
 BCO=ACO(L, ID, IP)  
 BC1=AC1(L, ID, IP)  
 BC2=AC2(L, ID, IP)  
 BC3=AC3(L, ID, IP)  
 BC4=AC4(L, ID, IP)  
 BC5=AC5(L, ID, IP)  
 BC6=AC6(L, ID, IP)

41













WVS 2370  
WVS 2380  
WVS 2390  
WVS 2400  
WVS 2410  
WVS 2420  
WVS 2430  
WVS 2440  
WVS 2450  
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WVS 2500  
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WVS 2690  
WVS 2700  
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WVS 2770  
WVS 2780  
WVS 2790  
WVS 2800  
WVS 2810  
WVS 2820  
WVS 2830  
WVS 2840

```

FKC=XWK*G*(BC7-BC8)+U*CM1*(-A42S*SK+AL*BC8)
FKS=-XWK*G*(BS7-BS8)+U*CM1*(-A42S*CK-AL*BS8)
FZW(J)=FZW(J)-AA*(FZC*CI+FZS*ST)
FYM(J)=FYM(J)+AA*(FMC*CI+FM*ST)*SIGAM
FYZ(J)=FYZ(J)-AA*(FYC*CI+FYS*ST)*SIGAM
FNW(J)=FNW(J)-AA*(FNC*CI+FNS*ST)*SIGAM
FKW(J)=FKW(J)-AA*(FKC*CI+FKS*ST)*SIGAM
FXW(J)=FXW(J)-2.*AA*RHC*G*BS*DSS*SK*CT
CONTINUE
IF (IMT.EQ.2) GO TO 100

C
WAVE ELEVATION AROUND THE SIDEWALLS AND SEALS
DC 20 J=1,4
N=NSTA(J)
DO 20 K=1,N
ETA(J,K)=ETA(J,K)+SIN(XWK*(-XX(J,K)*COGAM-YY(J,K)*SIGAM)+FT)*AA
CONTINUE
ETACG=ETACG+AA*SIN(FT)
N=NSTA(3)
DC 25 J=1,N
ARG=AA*COS(XWK*(-XX(3,J)*COGAM)+FT)
DETABX(J)=DETABX(J)-XWK*COGAM*ARG
CONTINUE
N=NSTA(4)
DC 30 J=1,N
ARG=AA*COS(XWK*(-XX(4,J)*COGAM)+FT)
DETADX(J)=DETADX(J)-XWK*COGAM*ARG
CONTINUE

C
WAVE PUMPING
X1=XWK*XLBW*COGAM/2.
X2=XWK*X8BW*SIGAM/2.
FTT=FT-XWK*XCP*COGAM
DVOLW=DVOLW+AA*ABW*T2(X1)*T2(X2)*SIN(FTT)
CONTINUE
IF (IMT.EQ.2) RETURN

C
TCTAL WAVE FORCES AND MOMENTS
FXWAV=FXW(1)+FXW(2)
FYWAV=FYW(1)+FYW(2)
FZWAV=FZW(1)+FZW(2)
FKWAV=FKW(1)+FKW(2)+(FZW(2)-FZW(1))*YSW
FMWAV=FMW(1)+FMW(2)-FXWAV*ZBAR
FNWAV=FNW(1)+FNW(2)+(FXW(1)-FXW(2))*YSW
+FYWAV*ZBAR
IF (IWAVES.NE.CN) RETURN
WRITE(6,200) ((ETA(I,J),J=1,11),I=1,4),ETACG,DVOLW

```







APPENDIX C  
SAMPLE OUTPUT













TIME (SEC) = 18.00

TRANSITIONAL VELs (KTS)/(FT/SEC)  
U= 25.02 V= 0.0 W= 0.0

ROTATIONAL VELOCITIES (DEG/SEC)  
P= 0.0 Q= 0.0 R= 0.0

DISPLACEMENTS (FT AND DEGREES)  
Z= -2.032 PHI= 0.0 THETA= 0.03

TRAJECTORY (FT AND DEGREES) PSI= 0.0  
X= 0.0 Y= 0.0

SIDESLIP ANGLE (DEG) = 0.0 RUDDER ANGLE (DEG) = 0.0 THRUST (LBS) = 0.0

GAP (FT.) (STERN TO BOW)

PORT SIDEWALL	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0
STBD SIDEWALL	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0
IMMERSION DEPTH (FT.) (STERN TO BOW)	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0
PORT SIDEWALL	5.50614	5.50614	5.51595	5.5123	5.48650	5.47177	5.45704	5.44232	5.42759	5.41286	5.41286
STBD SIDEWALL	5.50614	5.50614	5.51595	5.5123	5.48650	5.47177	5.45704	5.44232	5.42759	5.41286	5.41286

PROPR FX,FY,FZ,FX,FY,FN -0.2691E 00 0.0 0.0 0.1613E 04 0.0

RUDDER FX,FY,FZ,FX,FY,FN 0.0 0.0 0.0 -0.1201E 03 0.0

AFRCD FX,FY,FZ,FX,FY,FN -0.1653E 03 0.0 0.0 0.1017E 04 0.0

GAP (FT.) (PORT TO STBD)

ELSKI (FT.) (PORT TO STBD)	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0
PORT SIDEWALL	0.39589	0.39589	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568
STBD SIDEWALL	0.39589	0.39589	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568

PROPR FX,FY,FZ,FX,FY,FN -0.1653E 03 0.0 0.0 0.1017E 04 0.0

RUDDER FX,FY,FZ,FX,FY,FN 0.0 0.0 0.0 -0.1201E 03 0.0

AFRCD FX,FY,FZ,FX,FY,FN -0.1653E 03 0.0 0.0 0.1017E 04 0.0

GAP (FT.) (PORT TO STBD)

ELSKI (FT.) (PORT TO STBD)	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0
PORT SIDEWALL	0.39589	0.39589	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568
STBD SIDEWALL	0.39589	0.39589	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568	0.39568

PROPR FX,FY,FZ,FX,FY,FN -0.1653E 03 0.0 0.0 0.1017E 04 0.0

RUDDER FX,FY,FZ,FX,FY,FN 0.0 0.0 0.0 -0.1201E 03 0.0

AFRCD FX,FY,FZ,FX,FY,FN -0.1653E 03 0.0 0.0 0.1017E 04 0.0

THRUST (LBS) = 0.1526E-04

RUDDER ANGLE (DEG) = 0.0

SIDESLIP ANGLE (DEG) = 0.0

THRUST (LBS) = 0.0









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data from XR-3 test runs are used to verify the model for steady-state operating conditions in calm water. Computer output for turn maneuvers in calm waters and for regular sea conditions are included.



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