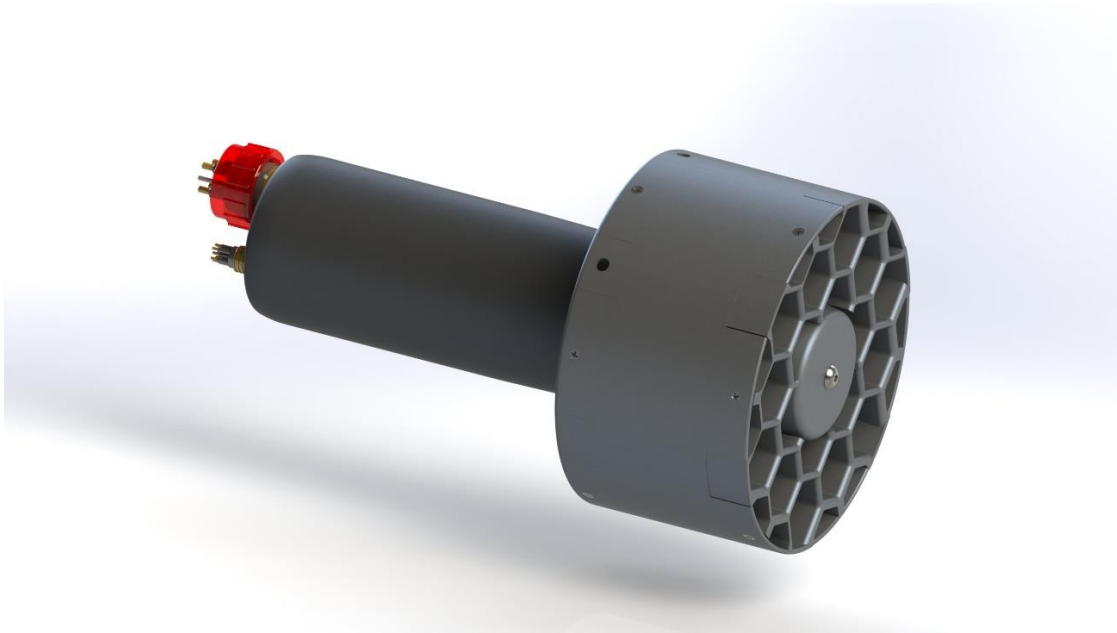




## H106-12600RH10-SMC HEXSCREEN ELECTRIC THRUSTER



- No maintenance for 5 years or 5,000 hours other than oil changes.
- No disassembly required for fresh water rinsing.
- Streamlined Brushless DC, oil filled and pressure balanced motors.
- True direct drive electric motors. No gearbox, no magnetic coupling, nor any other device to transmit power, simplifying the design and increasing reliability.
- Proven 3 tier seal system that includes Silicone Carbide Face Shaft Seals.
- 90% Reverse Thrust
- High Efficiency and Much Faster Response Time. Thrusters that will make a difference to any ROV's / Submarines performance
- All USA made materials, manufacturing and assembly.
- Independently Tested Off-The-Shelf Units that have a proven track record.

### *PRECISION DESIGNED AND BUILT - COMPARE EFFICIENCIES & PROP TIP CLEARANCES.*

- Optional Hexscreens of Hydrodynamic Design Protects Divers & the Propeller.
- The Hexscreens Cancels 80% of the Propeller Torque While Reclaiming Thrust by Reducing the Jet Whirl. Makes for a more energy efficient & Steadier Vehicle.

Customized Solutions/Systems for R & D Programs or Prototype Vehicles, small or large. These thrusters can be precision matched to each application.



## PERFORMANCE DATA & THRUSTER DIMENSIONS

H106-12600RH10-SMC Motor Specifications				
Input Voltage	Max Thrust	RPM	Input Power	Shaft Power
600 VDC	205 lbf (93 kgf)	1,500	3.2 HP (2.4 kW)	2.2 HP (1.7 kW)
Reverse Thrust				
600 VDC	180 lbf (82 kgf)	1,500	3.2 HP (2.4 kW)	2.2 HP (1.7 kW)

### H106 Hexscreen Electric Thruster with 12600RH10 Motor Performance Table

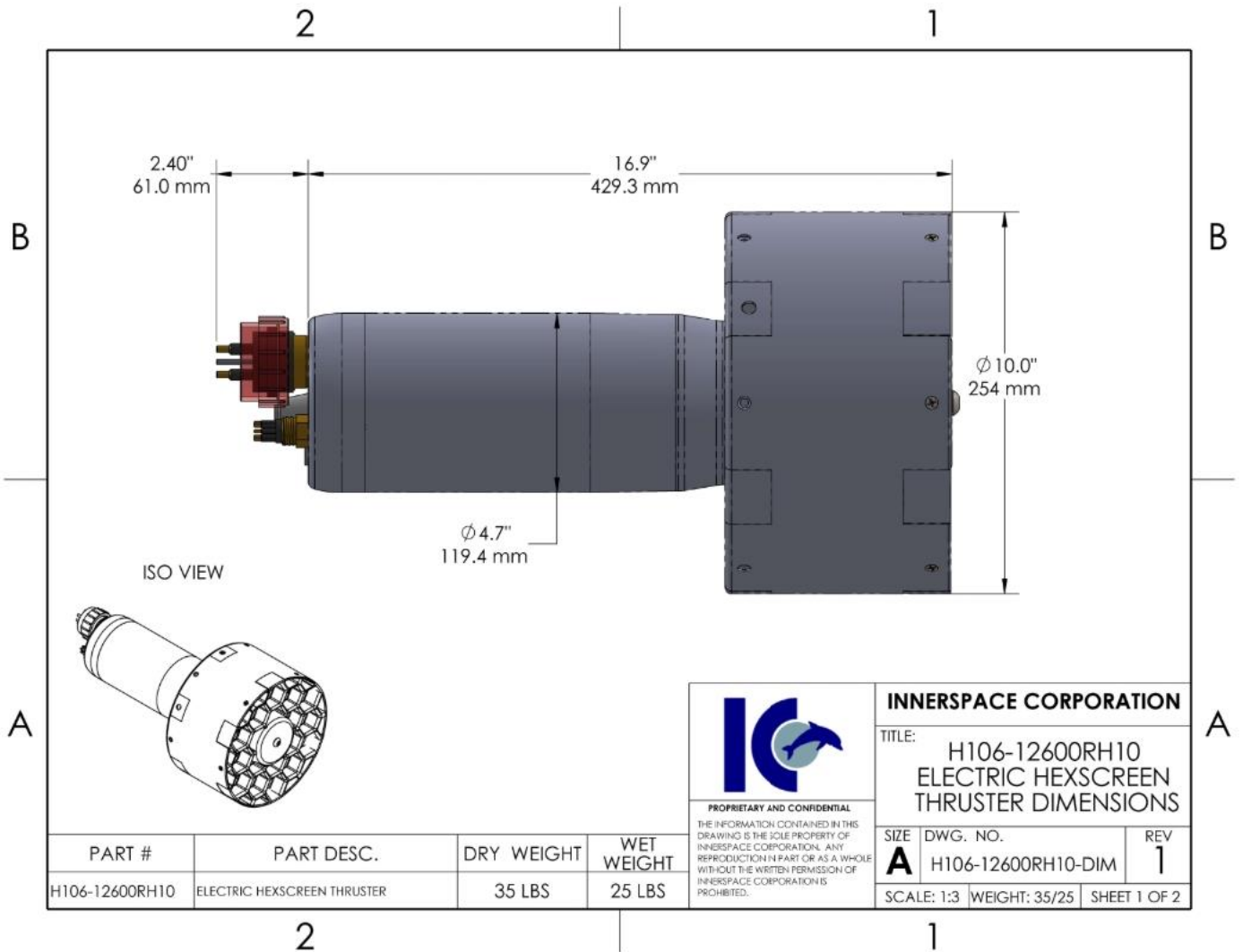
Speed (RPM)	System Voltage (VDC)	Min Voltage (VDC)	Current (A rms)	Bollard Thrust		Reverse Thrust		Power Shaft		Power In		Efficiency (Pout/Pin)
				0 (Lbf)	0 (Kgf)	(Lbf)	(Kgf)	(HP)	(Watts)	(Watts)	(HP)	
100	600	17.2	0.6	1	0.4	1	0.3	0.00	0	1	0.0	43.1%
200	600	33.7	0.9	3	1.5	3	1.3	0.00	4	5	0.0	74.1%
400	600	67.9	2.0	13	6.1	12	5.3	0.04	29	35	0.0	81.9%
600	600	103.9	3.8	31	14.0	27	12.3	0.13	99	123	0.2	80.7%
800	600	141.5	6.4	56	25.3	49	22.3	0.32	240	307	0.4	78.3%
1000	600	180.8	9.7	88	40.0	78	35.2	0.64	474	628	0.8	75.6%
1100	600	201.1	11.6	108	48.9	95	43.0	0.86	638	858	1.2	74.3%
1150	600	211.5	12.6	118	53.4	104	47.0	0.98	729	990	1.3	73.6%
1200	600	221.9	13.7	129	58.5	113	51.5	1.12	832	1140	1.5	73.0%
1250	600	232.4	14.8	141	63.8	124	56.1	1.27	946	1306	1.8	72.4%
1300	600	243.0	16.0	152	69.0	134	60.7	1.43	1064	1483	2.0	71.7%
1350	600	253.8	17.2	166	75.1	146	66.1	1.61	1203	1689	2.3	71.2%
1400	600	264.6	18.4	178	80.8	157	71.1	1.80	1342	1902	2.5	70.6%
1450	600	275.6	19.7	191	86.7	168	76.3	2.00	1491	2132	2.9	69.9%
1500	600	286.6	21.1	205	92.8	180	81.6	2.21	1651	2383	3.2	69.3%

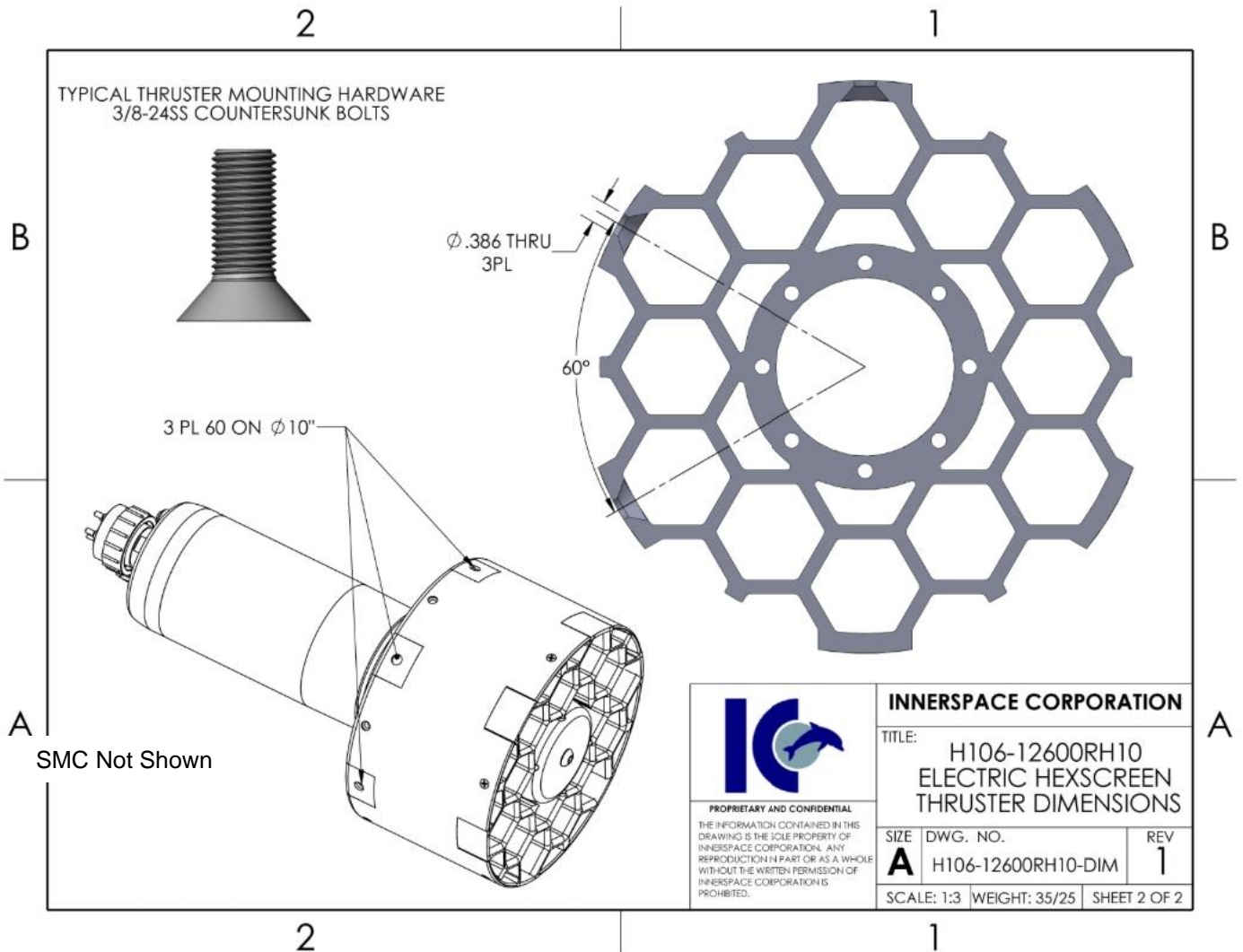
**Table Information:**

- 1) The Minimum Voltage column in the above table shows the minimum Voltage needed to achieve the performance at that corresponding propeller RPM/Thrust.
- 2) The Current shown represents the continues RMS Current to the motor to achieve the Thrust at the corresponding propeller RPM.
- 3) The Shaft HP developed is a function of the propeller and increases with propeller RPM.
- 4) The maximum performance achieved will depend on the limitations of customers system Voltage and driver Current capacity.
- 5) For Thrust at Forward Vehicle Speed (Kts), anything lower than 500 RPM varies greatly with vehicle design.
- 6) The Current/RPM might need to be limited depending on customer connector spec and or system Current limitations.
- 7) Minimum Voltage to achieve full Thrust is 600 VDC.
- 8) Max Voltage should not exceed 10% of rated Voltage.



H106-12600RH10 Dimensions





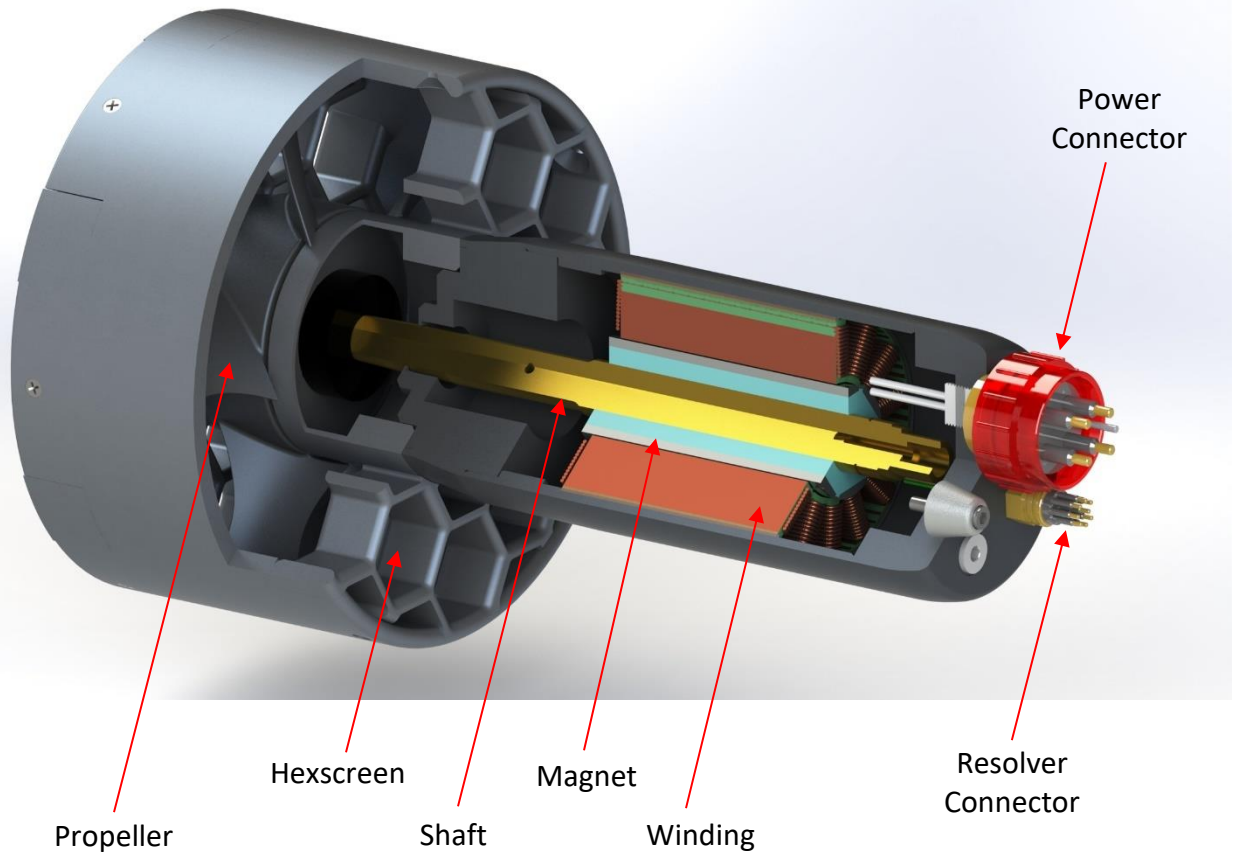
The Electric Thrusters can be ordered with almost any customer preferred connectors if Current ratings are taken into consideration.

The above Drawing shows the H106-12600RH10 Thruster Dimensions with Vertical Fittings/Bulkheads (1) and Axial fittings/Bulkheads (2).



## GENERAL ARRANGEMENT

12600RH10 BDC MOTOR  
DIRECT DRIVE – Propeller Attached on the same shaft  
that the Magnets are on without any other device to  
transmit power to the Propeller.





## **STATE-OF-THE-ART AMBIENT PRESSURE MOTOR CONTROLLER FROM 50 – 780 VDC**

The H106 Series Electric Thrusters are offered with a matching SMC (Stand-alone Motor Controller) housed in a separate one atmosphere bottle. Specially designed to match the H106 Series Electric Thruster range from Innerspace, the SMC controller operates in torque or velocity mode. Torque mode is particularly useful when integration to a vehicle stability control system is anticipated, allowing percentage torque thrust forward and reverse to the RPM limit of the motor. Feedback from the motor to the system controller receipt of the digital commands sent and provides real time RPM and motor Current, along with system health and performance monitoring data. Motor acceleration rates and other parameters can be set to suit the motor and application.

Recording of lifetime performance data including total shaft revolutions, hours since overhaul and power cycles provide data points for operation and maintenance purposes are standard.



Stand-alone Motor Controller (SMC)  
Sizes will vary depending on depth.



## INNERSPACE CORPORATION

1138 E. EDNA PLACE, COVINA, CA 91724

TEL: (626) 331-0921 FAX: (626) 966-6391

www.innerspacethrusters.com

### SPECIFICATIONS

#### SMC (Stand-alone Motor Controller):

**Type:** Atmospheric Pressure Housed Three Phase BLDC motor controller.

#### Available Configurations:

**Stand Alone (SMC):** Independent control unit with cable connections to motor - phase (power) and sensing (resolver) Communication (Network).

**Motor Power Rating:** 1hp (750W) to 25hp (18kW) with options to 55hp (41kW)

#### General Characteristics:

**Voltage:** DC, 50VDC to 780VDC, Positive, Negative, Isolated from Frame Ground.

**Current:** Maximum Continuous 50A (in water)

**Motor Type:** Suitable for Three Phase water cooled BLDC Permanent Magnet motors

**Operating Parameters:** Stand Alone Controller: Sine/CoSine resolver and direct commutation  
Controller parameter matched to associated motor.

#### Connections

**Power:** Subconn HPBH4M - Positive, Negative and Frame Safety Ground

**Data:** SubConn DBH13M – 1. 24V+, 2. SHD, 3. 0V-, 4-7 RESERVED, 8. ECAT TX+, 9. ECAT TX-, 10. ECAT RX+, 11. ECAT RX-, 12 & 13 RESERVED

**Motor Phase:** Subconn HPBH4F - Phase A, B, C, Frame Ground/Shield

**Motor Sensor:** Subconn DBH8F Sensor SIN+/-, COS+/-, EXC+/- Frame Ground/Shield

#### Control

**Electrical:** Ethercat point to point connection.

A separate 24VDC LV supply used with the Ethercat connection. This enables the condition of the controller to be known without the HV being present. Communication of all the motor parameters is possible.

**Command:** Over 300 commands available please contact for requirements

Ethercat SDO and PDO:

**Action Commands:** RPM setting (velocity mode) - Forward and Reverse, to rated motor RPM

Power setting (torque mode)- Forward and Reverse, 0% to 100% of maximum rated/programmed torque

Safety Lockout (Manual)

Status query

**Status Messages:**

Shaft RPM

Motor Current

Throttle/Thrust setting

Temperature

**Safety State Action:** Condition warnings (Temperature, Voltage, Current)

Control System Connectivity Failure - Automatic shutdown

#### Notes:

- Optional External Control Interfaces: Test interface and development code
- DC supply cables must meet minimum length/inductance requirements to eliminate requirement for an external HVDC soft start switch.
- Adequate DC bus capacitance and reverse EMF/Overvoltage protection must be used.
- All Data cable must be shielded for noise prevention
- Data cable should not exceed 6 meters between SMC and electric motors.