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**NATIONAL STANDARD OF THE
PEOPLE'S REPUBLIC OF CHINA**

GB/T 46413-2025

Code of practice for ROV operations

遥控潜水器作业规程

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Foreword

This document complies with the provisions of GB/T 1.1-2020 "Standardization Work Guidelines Part

1. Structure and Drafting Rules of Standardization Documents". Drafting. Please note that some content in this document may involve patents. The issuing organization of this document assumes no responsibility for identifying patents. This document was proposed and is under the jurisdiction of the National Technical Committee on Standardization of Submersibles (SAC/TC306). This document was drafted by: CNOOC Shenzhen Marine Engineering Technology Service Co., Ltd., and CRRC Shanghai Aisendi Marine Equipment Co., Ltd. Offshore Oil Engineering Co., Ltd., and the Rescue and Salvage Bureau of the Ministry of Transport. The main drafters of this document are. Wang Huifeng, Chen Yong, Ding Donghua, Cui Ning, Chen Xiaoming, Wang Jiewen, Zhang Dinghua, Li Aihua, Jiang Kaixian, and Shan Qin. Li Tao, Zhang Xiao, Zeng Yajun, Gao Lei, Fang Zeyan, Han Chao, Xiao Gang, Zhang Fei, Zhu Jiaolin, Li Huailiang, He Ning, Zhang Niantao, Song Junhui, Zheng Yunliang Zhang Hui, Hu Bo, and Cuoxiangma. Remotely operated vehicle operation

procedures

1 Scope

GB/T 46413-2025 is the Chinese national standard covering operating a remotely operated vehicle - the pre-dive checks and the launch and recovery through the splash zone, the tether management and the umbilical, the pilot's watch, the emergency recovery of a snagged vehicle, and the records of each dive. First edition, in force from 1 May 2026. Issued on 5 October 2025, it has been in force since 1 May 2026.

This document specifies the pre-operation preparation, operation procedures, and emergency procedures for remotely operated vehicles (ROVs). This document applies to underwater operations of remotely operated vehicles (ROVs) in marine fields such as offshore oil and gas, offshore wind power, and rescue and salvage. Other ROV applications... The underwater operation of the watercraft should be carried out in accordance with the guidelines.

2 Normative references

The contents of the following documents, through normative references within the text, constitute essential provisions of this document. Dated citations are not included. For references to documents, only the version corresponding to that date applies to this document; for undated references, the latest version (including all amendments) applies. This document.

GB/T 21412.8 Design and operation of subsea production systems for the oil and gas industry - Part

3 Terms and Definitions

The following terms and definitions apply to this document.

3.1 Signal and power are transmitted via a load-bearing umbilical cable. Underwater, it can automatically orient, maintain depth, levitate, or navigate. It is remotely controlled via a surface control unit. Unmanned underwater vehicles that control their forward and backward movement, lateral movement, turning or heave, and conduct underwater observation, inspection and/or operations.

3.2 A complete set of equipment for the lowering and recovery of ROVs.

3.3 repeater The device controls the deployment and retrieval of the ROV relay cable via an equipped underwater winch.

3.4 umbilical cable Composite cables used for power supply, communication, deployment, and recovery between surface control systems and TMS/ROVs.

3.5 ROV wet test Before the official launch operation, the operators conducted watertightness and functional tests on the ROV system and its specialized tools at a certain water depth. The act of trying.

8 Subsea production systems Robot (ROV) Interface

GB 27881 Safety requirements for underwater high-voltage equipment operation JT/T 746
Requirements for Collaborative Diving Operations of Remotely Operated Unmanned
Submersibles