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(54) Title: A ROTARY STEERABLE DRILLING ASSEMBLY WITH A ROTATING STEERING DEVICE FOR DRILLING DEVIATED WELLBORES

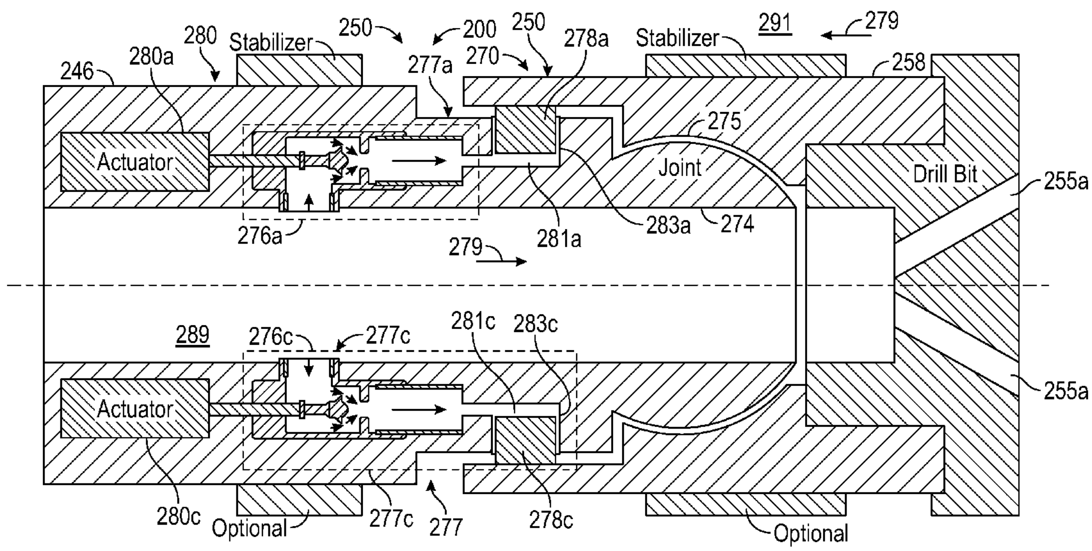

FIG. 6

(57) Abstract: A drilling assembly for drilling deviated wellbores is disclosed that in one embodiment includes a steering unit having an upper section coupled to a lower section through a tilt device, wherein an electro-mechanical actuation device tilts the tilt device about a selected location in the drilling assembly to cause the lower section to tilt relative to the upper section along a selected direction while the drill string is rotating.

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[Continued on next page]

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A ROTARY STEERABLE DRILLING ASSEMBLY WITH A ROTATING STEERING DEVICE FOR DRILLING DEVIATED WELLBORES

CROSS REFERENCE TO RELATED APPLICATIONS

[0001] This application claims the benefit of U.S. Application No. 15/210669, filed on July 14, 2016, which is incorporated herein by reference in its entirety.

BACKGROUND

1. Field of the Disclosure

[0002] The disclosure relates generally to rotary drilling systems for drilling of deviated wellbores and particularly to a drilling assembly that utilizes a rotating steering device for drilling deviated wellbores.

2. Background Art

[0003] Wells or wellbores are formed for the production of hydrocarbons (oil and gas) from subsurface formation zones where such hydrocarbons are trapped. To drill a deviated wellbore, a drilling assembly (also referred to as a bottomhole assembly or "BHA") that includes a steering device coupled to the drill bit is used. The steering device tilts a lower portion of the drilling assembly by a selected amount and along a selected direction to form the deviated portions of the wellbore. Various types of steering devices have been proposed and used for drilling deviated wellbores. The drilling assembly also includes a variety of sensors and tools that provide a variety of information relating to the earth formation and drilling parameters.

[0004] In one such steering device, an actuator mechanism is used in which a rotary valve diverts the mud flow towards a piston actuator, while the entire tool body, together with the valve, is rotating inside the wellbore. In such a mechanism, the valve actuation is controlled with respect to the momentary angular position inside the wellbore (up, down, left, right). A control unit maintains a rotary stationary position (also referred to as geostationary) with respect to the wellbore. As an example, if, during drilling, the drill string and thus the drilling assembly rotates at 60 rpm clockwise, the control unit rotates at 60 rpm counterclockwise, driven by, for example, an electric motor. To maintain a rotary stationary position, the control unit may contain navigational devices, such as accelerometer and a magnetometer. In such systems, the actuation force relies on the pressure drop between the pressure inside the tool and the annular pressure outside the tool. This pressure drop is highly dependent on operating parameters and varies over a wide range. The actuation stroke is a reaction based upon the pressure force exerted onto the actuation pistons. Neither force nor stroke is precisely controllable.

[0005] The disclosure herein provides a drilling system that utilizes a steering device that utilizes actuators that rotate along with the drilling assembly to drill deviated wellbores.

SUMMARY

[0006] In one aspect, a drilling assembly for use in drilling of a wellbore is disclosed that in one non-limiting embodiment includes a steering device that includes a tilt device and an actuation device, wherein a first section and a second section of the drilling assembly are coupled through the tilt device, and wherein the actuation device tilts the tilt device to cause the first section to tilt relative to the second section along a selected direction while the steering device is rotating.

[0007] In another aspect, a method of forming a wellbore is disclosed that in one embodiment includes: conveying a drilling assembly in the wellbore, wherein the drilling assembly includes a disintegration device at an end thereof, a steering device that includes a tilt device and an actuation device, wherein a first section and a second section of the drilling assembly are coupled through the tilt device, and wherein the actuation device tilts the tilt device to cause the first section to tilt relative to the second section about the tilt device along a selected direction while the steering unit is rotating; drilling the wellbore using the disintegration device; and actuating the actuation device to tilt the tilt device to cause the first section to tilt relative to the upper section and to maintain the tilt substantially geostationary while the steering device is rotating to form a deviated section of the wellbore.

[0008] Examples of the certain features of an apparatus and methods have been summarized rather broadly in order that the detailed description thereof that follows may be better understood, and in order that the contributions to the art may be appreciated. There are, of course, additional features that will be described hereinafter and which will form the subject of the claims.

DRAWINGS

[0009]For a detailed understanding of the apparatus and methods disclosed herein, reference should be made to the accompanying drawings and the detailed description thereof, wherein like elements are generally given same numerals and wherein:

FIG. 1 shows a schematic diagram of an exemplary drilling system that may utilize a steering unit for drilling deviated wellbores, according to one non-limiting embodiment of the disclosure;

FIG. 2 shows an isometric view of certain elements of an elctro-mechanical steering device coupled to a drill bit for drilling deviated wellbores, according to a non-limiting embodiment of the disclosure;

FIG. 3 shows an isometric view of a non-limiting embodiment of an adjuster for use in the steering unit of **FIG. 2**;

FIG. 4 shows certain elements of a modular electro-mechanical actuator for use in the steering unit of **FIG. 2**, according to a non-limiting embodiment of the disclosure;

FIG. 5 shows an isometric view of components of the steering unit laid out for assembling the steering unit of **FIG. 2**; and

FIG. 6 is a block diagram of a drilling assembly that utilizes a steering device having an actuation de vice and a hydraulic force application device, according to a non-limiting embodiment of the disclosure.

DETAILED DESCRIPTION

[0010] FIG. 1 is a schematic diagram of an exemplary rotary steerable drilling system **100** that utilizes a steering device (also referred to as steering unit or steering assembly) in a drilling assembly for drilling vertical and deviated wellbores and maintain the steering device geostationary or substantially geostationary while the steering device is rotating. A deviated wellbore is any wellbore that is non-vertical. The drilling system **100** is shown to include a wellbore **110** (also referred to as a “borehole” or “well”) being formed in a formation **119** that includes an upper wellbore section **111** with a casing **112** installed therein and a lower wellbore section **114** being drilled with a drill string **120.** The drill string **120** includes a tubular member **116** that carries a drilling assembly **130** (also referred to as the “bottomhole assembly” or “BHA”) at its bottom end. The drilling tubular **116** may be a drill pipe made up by joining pipe sections. The drilling assembly **130** is coupled to a disintegrating device **155**, such as a drill bit) or another suitable cutting device, attached to its bottom end. The drilling assembly **130** also includes a number of devices, tools and sensors, as described below. The drilling assembly **130** further includes a steering device **150** to steer a section of the drilling assembly **130** along any desired direction, a methodology often referred to as geosteering. The steering device **150**, in one non-limiting embodiment, includes a tilt device **161** and an actuation device oe unit or assembly 160 (for example, an electro-mechanical device or a hydraulic device) that tilts one section, such as the lower section **165** of the drilling assembly **130**, relative to another section, such as the upper section **166** of the drilling assembly **130**. The section **165** is coupled to the drill bit **155**. In general, the actuation device tilts the tilt device **161**, which in turn causes the lower section **165** and thus the drill bit **155** to tilt or point a selected extent along a desired or selected direction, as described in more detail in reference to **FIGS. 2-6**.

[0011] Still referring to **FIG. 1**, the drill string **120** is shown conveyed into the wellbore **110** from an exemplary rig **180** at the surface **167**. The exemplary rig **180** in **FIG. 1** is shown as a land rig for ease of explanation. The apparatus and methods disclosed herein may also be utilized with offshore rigs. A rotary table **169** or a top drive **169a** coupled to the drill pipe **116** may be utilized to rotate the drill string **120** and the drilling assembly **130**. A control unit (also referred to as a "controller" or "surface controller") **190**, which may be a computer-based system, at the surface **167** may be utilized for receiving and processing data transmitted by various sensors and tools (described later) in the drilling assembly **130** and for controlling selected operations of the various devices and sensors in the drilling assembly **130**, including the steering device **150**. The surface controller **190** may include a processor **192**, a data storage device (or a computer-readable medium) **194** for storing data and computer programs **196** accessible to the processor **192** for determining various parameters of interest during drilling of the wellbore **110** and for controlling selected operations of the various tools in the drilling assembly **130** and those of drilling of the wellbore **110**. The data storage device **194** may be any suitable device, including, but not limited to, a read-only memory (ROM), a random-access memory (RAM), a flash memory, a magnetic tape, a hard disc and an optical disk. To drill wellbore **110**, a drilling fluid **179** is pumped under pressure into the tubular member **116**, which fluid passes through the drilling assembly **130** and discharges at the bottom **110a** of the drill bit **155.** The drill bit **155** disintegrates the formation rock into cuttings **151**. The drilling fluid **179** returns to the surface **167** along with the cuttings **151** via annular space **127** (also referred as the "annulus") between the drill string **120** and the wellbore **110**.

[0012] Still referring to **FIG**. **1**, the drilling assembly **130** may further include one or more downhole sensors (also referred to as the measurement-while-drilling (MWD) sensors and logging-while-drilling (LWD) sensors or tools, collectively referred to as downhole devices and designated by numeral **175**, and at least one control unit or controller **170** for processing data received from the sensors **175**. The downhole devices **175** may include sensors for providing measurements relating to various drilling parameters, including, but not limited to, vibration, whirl, stick-slip, flow rate, pressure, temperature, and weight-on-bit. The drilling assembly **130** further may include tools, including, but not limited to, a resistivity tool, an acoustic tool, a gamma ray tool, a nuclear tool and a nuclear magnetic resonance tool. Such devices are known in the art and are thus not described herein in detail. The drilling assembly **130** also includes a power generation device **186** and a suitable telemetry unit **188**, which may utilize any suitable telemetry technique, including, but not limited to, mud pulse telemetry, electromagnetic telemetry, acoustic telemetry and wired pipe. Such telemetry techniques are known in the art and are thus not described herein in detail. Drilling assembly **130**, as mentioned above, includes the steering device **150** that enables an operator to steer the drill bit **155** in desired directions to drill deviated wellbores when the drilling assembly is rotating and to maintain the steering device geostationary or substantially geostationary. Stabilizers, such as stabilizers **162** and **164** are provided along the lower section **165** and the upper section **166** to stabilize the steering section **150** and the drill bit **155**. Additional stabilizers may be used to stabilize the drilling assembly **130**. The controller **170** may include a processor **172**, such as a microprocessor, a data storage device **174**, such as a solid state memory, and a program **176** accessible to the processor **172**. The controller **170** communicates with the controller **190** to control various functions and operations of the tools and devices in the drilling assembly. During drilling, the steering unit **150** controls the tilt and direction of the drill bit **155**, as described in more detail in reference to **FIGS. 2-6**.

[0013] **FIG. 2** shows an isometric view of certain elements or components of the steering device **150** for use in a drilling assembly, such as drilling assembly **130** of **FIG**. **1**, to steer or tilt the drill bit **155** for drilling deviated wellbores, according to one non-limiting embodiment of the disclosure. The drilling assembly **130** includes a housing or collar **210** for housing the various elements or components of the steering device **150**. The steering device **150** includes a tilt device **161** and an actuation device **160** for tilting the lower section **165** with respect the upper section **166**. In one non-limiting embodiment, the tilt device **161** includes an adjuster **242** and a joint **244**. The upper section **166** and the lower section **165** are coupled by the joint **244**. The adjuster **242** is coupled to the joint **244** in a manner such that when the adjuster **242** is moved a certain amount along a certain direction, it causes the joint **244** to tilt accordingly. The tilt device **161** can be tilted by the actuation device **160** along any direction and by any desired amount to cause the lower section **165** and thus the drill bit **155** to point in any desired direction about a selected point or location in the drilling assembly **130**. The adjuster **242** may be a swivel or another suitable device. The joint **244** may be one of a cardan joint, homokinetic joint, constant velocity joint, universal joint, knuckle joint, Hooke's joint, u-joint or another suitable device. The joint **244** transfers axial and torsional loads between the upper section **166** and the lower section **165**, while maintaining angular flexibility between the two sections. Stabilizers **162** and **164** are disposed at suitable locations around the steering assembly **150**, such as one around the lower section **165** and the other around the upper section **166**, to provide stability to the steering unit **150** and the drill bit **155** during drilling operations. In one non-limiting embodiment, the actuation device **160** further includes a suitable number, such as three or more, of electro-mechanical actuators, such as actuators **222a**, **222b** and **222c**, radially arranged spaced apart in the actuation device **160**. Each such actuator is connected to a corresponding end **242a-242c** of the adjuster **242**. In one embodiment, each actuator is a longitudinal device having a lower end that can be extended and retracted to apply a desired force on the adjuster substantially parallel to the axis **230** to cause the adjuster **160** to move about a longitudinal axis **230** of the steering unit **150**. In **FIG. 2**, end **224a-224c** of actuators **222a-222c** are shown directly connected respectively to the ends or abutting elements **242a-242c** of the adjuster **242**. As described in reference to **FIG. 1**, the steering unit **150** is part of the drilling assembly **130**. During drilling, as the drilling assembly 130 rotates, the steering unit **150** and thus each actuator rotates therewith. Each actuator **222a-222c** is configured to apply force on the adjuster **242**, as described later, and depending upon the forces applied, the movement of the adjuster **242** causes the lower section **165** and thus the drill bit **155** to tilt along a desired direction. In the embodiment shown in **FIG. 2**, since the actuators **222a-222c** are mechanically connected to their corresponding adjuster ends **242a-242c**, the forces applied by such actuators and their respective strokes may be synchronized to create any desired steering direction. Although, the actuators **222a-222c** shown apply axial forces on the adjuster **242**, any other suitable device, including, but not limited to a rotary oscillating device, may be utilized to apply forces on the adjuster **242**. In aspects, movement of at least a part the electro-mechanical actuation unit **220** may be selectively adjusted or limited (mechanically, such as by providing a stop in the steering device or electronically by a controller) to cause the lower section **165** to tilt with a selected tilt relative to the upper section **166**. Also, the tilt of the joint **244** may be selectively adjusted or limited to cause the lower section **165** to tilt with a selected tilt relative to the upper section **166**.

[0014] **FIG. 3** shows an isometric view of non-limiting embodiment of an adjuster **242** for use in the steering unit **150** of **FIG. 2**. Referring to **FIGS. 2** and **3**, the adjuster **242** includes a cylindrical body **342** and a number of spaced apart abutting elements or members, such as connectors **322a**, **322b** and **322c**, with connector **322a** having one end **320a** connected to the adjuster end **342a** and the other end **324a** for a direct connection to the actuator **222a**, connector **322b** having one end **320b** connected to the adjuster end **32a** and the other **324b** for direct connection to the actuator **222b** and connector **322c** having one end **320c** connected to an end of **32a** of the adjuster **242** and the other end **324c** for direct connection to the actuator **222c**. The abutting elements may include elements such as a cam, a crank shaft; an eccentric member; a valve; a ramp element; and a lever. In this configuration, when forces are applied onto the adjuster **242** by the actuators, the adjuster **242** may create an eccentric offset in real time in any desired direction by any desired amount about the tool axis **230**, which provides 360 degrees of drill bit maneuvering ability during drilling. The forces on the abutting elements **322a-322c** create a substantially geostationary tilt of the tilt **161** device. In an alternative embodiment, the adjuster **242** may be a hydraulic device that causes the joint **244** to tilt the lower section **165** relative to the upper section **166**., as described in more detail in reference to **FIG. 6**.

[0015] FIG. 4 shows certain elements or components of an individual actuator **400** for use as any of the actuators **222a-222c** in the steering unit **150** of **FIG. 2**. In one aspect, the actuator **400** is a unitary device that includes a movable end **420** that may be extended and retracted. The actuator **400** further includes an electric motor **430** that may be rotated in clockwise and anticlockwise directions. The motor **430** drives a gear box **440** (clockwise or anti-clockwise) that in turn rotates a drive screw **450** and thus the end **420** axially in either direction. The actuator **400** further includes a control circuit **460** that controls the operation of the motor **430**. The controller **460** includes electrical circuits **462** and may include a microprocessor **464** and memory device **466** that houses instructions or programs for controlling the operation of the motor **430**. The control circuit **460** is coupled to the motor **430** via conductors through a bus connector **470**. In aspects, the actuator **400** may also include a compression piston device or another suitable device **480** for providing pressure compensation to the actuator **400**. Each such actuator may be a unitary device that is inserted into a protective housing disposed in the actuator unit **150** (**FIG. 1**), as described in reference to **FIG. 5**. During drilling, each such actuator is controlled by its control circuit, which circuit may communicate with the controller **270** (**FIG. 1**) and/or controller **190** (**FIG. 1**) to exert force on the adjuster **242** (**FIG. 2**).

[0016] FIG. 5 shows an isometric view **500** of components of the steering unit **150** of **FIG. 2** laid out for assembling the steering unit **150**. As described earlier, the actuator unit **150** includes an upper section **166**, a lower section **165**, an adjuster **242** and a joint **244**

between the upper section **166** and the lower section **165**. The upper section **166** includes bores or pockets **520a**, **520b** and **520c**, corresponding to each of the individual actuators, such as actuators **222a-222c**. The actuator **222a** is inserted into the bore or pocket **520a**, actuator **222b** into bore or pocket **520b** and actuator **222c** into bore or pocket **520c**. The actuators **222a-222c** are connected to the upper end **242a** of the adjuster **242** as described above in reference to **FIGS. 2** and **3**. The adjuster **242** is connected to the lower section **165** by means of the joint **244** to complete the actuator unit assembly. The steering unit **150** is connected to the drill bit **155**.

[0017] **FIG. 6** is a block diagram of a drilling assembly **200** that utilizes a steering device **250** that includes an actuation device **280** and a tilt device **270**. The actuation device **280** shown is the same as shown in **FIG. 2** and includes three or more actuators **280a-280c** disposed in a housing **210**. The tilt device **270** includes an adjuster **277** and a joint **274**. In one non-limiting embodiment, the adjuster **277** includes a separate hydraulic force application device corresponding to each of the actuators **280a-280c**. In **FIG. 2**, force applications devices **277a-277c** respectively correspond to and are connected to actuators **282a-282c**. The actuators **280a-280c** selectively operate their corresponding force application devices **277a-277c** to tilt the lower section **258** relative to the upper section **246** about the joint **274** when the drilling assembly **200** and thus the steering device **250** is rotating. In one non-limiting embodiment, each of the force application devices **277a-277c** includes a valve in fluid communication with pressurized fluid **279** flowing through channel **289** in the drilling assembly **200** and a chamber that houses a piston. In the embodiment of **FIG. 2B**, force application devices **277a-277c** respectively include valves **276a-276c** and pistons **278a-278c** respectively disposed in chambers **281a-281c**. During drilling, the steering device **250** rotates while the pressurized drilling fluid **279** flows through channel **289** and exits through the passages or nozzles **255a** in the drill bit **255**. The exiting fluid **279a** returns to the surface via annulus **291**, which creates a pressure drop between the channel **289** and the annulus **291**. In aspects, the disclosure herein utilizes such a pressure drop to activate the hydraulic force application devices **277a-277c** to create a desired tilt of the lower section **246** relative to the upper section **246** about the joint **274** and to maintain such tilt geostationary or substantially geostationary while the steering assembly **250** is rotating. To tilt the drill bit **255** via the sections **258** and **246**, the actuators **280a-280c** selectively open and close their corresponding valves **276a-276c**, allowing the pressurized fluid **279** from channel **289** to flow to the cylinders **281a-281c** to extend pistons **278a-278c** radially outward, which apply desired forces on the adjuster **277** to tilt the lower section **258** and thus the drill bit **255** along a desired direction. Each piston and cylinder combination may include a gap, such as gap **283a** between piston **278a** and cylinder **281a** and gap **283c** between piston **278c** and chamber **281c**. Such a gap allows the fluid entering a chamber to escape from that chamber into the annulus **291** when the valve is open and the piston is forced back into its cylinder. Alternatively, one or more nozzles or bleed holes (not shown) connected between the cylinder and the annulus **291** may be provided to allow the fluid to flow from the chamber into the annulus **291**. To actively control the tilt of the lower section **258** while the rotary steerable drilling assembly **200** is rotating, the three or more valves **276a-276c** may be activated sequentially and preferably with the same frequency as the rotary speed (frequency) of the drilling assembly **200**, to create a geostationary tilt between the upper section **246** and the lower section **258**. For instance, referring to **FIG. 6**, if an upward drilling direction is desired, the actuator **280c** is momentarily opened, forcing the piston **278c** to extend outward. At the same moment, actuator **280a** would close valve **276a**, blocking pressure from the channel **289** to the piston **278a**. Since all pistons **276a-276c** are mechanically coupled through the joint **274**, piston **278a** would return or retract upon the outboard stroke of piston **278c**. When the drilling assembly **200** rotates, e. g. by 180° and for the case of four actuators distributed equi-spaced around the circumference of the drilling assembly **200**, the activation would reverse, actuator **280a** opening valve **276a** and actuator **280c** closing valve **276c**, thus maintaining a geostationary tilt direction. Similar methods may be utilized to tilt and maintain the tilt geostationary for the embodiment shown in **FIG. 2**.

[0018] Referring to **FIGS. 1-6**, the steering unit **150** described herein is in the lower portion of a drilling assembly **130** (**FIG. 1**) of a rotary drilling system **100**. The steering unit **150** includes an adjuster and a joint connected to an actuation device that maneuvers or tilts the adjuster about a drilling assembly axis, which in turn tilts the joint. The joint tilts a lower section containing the drill bit relative to an upper section of the drilling assembly. The system transmit torque from a collar to the drill bit. In one non-limiting embodiment, the adjuster is actively tilted by a selected number of intermittently activated electro-mechanical actuators. The actuators rotate with the drilling assembly and are controlled by signal inputs from one or more position sensors in the drilling assembly **130**. Any suitable directional sensors, including, but not limited to magnetometers, accelerometer and gyroscopes may be utilized. Such sensors provide real time position information relating to the wellbore orientation while drilling. Depending on the type and the design of the adjuster the actuators may perform reciprocating or rotary oscillating movement, e. g., actuators coupled to a cam or crank system further enabling the eccentric offset in any desired direction from the drilling assembly axis during each revolution of the drilling assembly, creating a geostationary force and offset of the adjuster axis.

[0019] The system **100** disclosed herein does not require a control unit to counter-rotate the tool body rotation. The modular activators positioned in the outer diameter of the actuation assembly receive command signals from a controller located in another section of the tool or higher up in the drilling assembly that may also include navigational sensors. These navigational sensors rotate with the drilling assembly. Such a mechanism can resolve and process the rotary motion of the drilling assembly to calculate momentary angular position (while rotating) and generate commands to the individual actuators substantially instantaneously. As an example, assume the drilling assembly rotates at 1/3 revolutions per second (20 rpm). The current steering vector is intended to point upwards. Assuming the side force element increases eccentricity with positive displacement of the actuation units, the navigational package electronics determine the momentary angular position of the drilling assembly or the steering unit with respect to the earthen formation and sends commands to all of the actuators (stroke and force). At time zero second, one of the actuators (for example the lowermost) receives a command to stroke outward a certain distance. At time 1 second, the steering unit has rotated 120 degrees and the same actuator receives the command to decrease the stroke to approximately to the middle position. At time 1.5 seconds, this actuator is at the uppermost position and the navigational package electronics sends a command to further decrease the stroke of a similar value as sent at zero second, but negative from a middle position. The commands are constantly sent to each actuator with their respective stroke requirements. With the changes for the stroke of the actuators, the angular tilt can be controlled and adjusted in real time. In such a configuration, each actuator performs one stroke per tool revolution (positive and negative from the middle position). To drill a straight wellbore section, all actuators are maintained stationary at their respective middle positions, thus requiring only minimum energy supply to hold the centralized position. The amount of the tilt angle and the momentary direction of the tilt angle controls the drilling direction of the wellbore.

[0020] The foregoing disclosure is directed to the certain exemplary non-limiting embodiments. Various modifications will be apparent to those skilled in the art. It is intended that all such modifications within the scope of the appended claims be embraced by the foregoing disclosure. The words "comprising" and "comprises" as used in the claims are to be interpreted to mean "including but not limited to". Also, the abstract is not to be used to limit the scope of the claims.

CLAIMS

1. A drilling assembly for use in drilling of a wellbore, comprising:

a steering unit having a tilt device and an actuation device, wherein a first section and a second section of the drilling assembly are coupled through the tilt device, and

wherein the actuation device causes a tilt of the tilt device to cause the first section to tilt relative to the second section along a selected direction while the steering device is rotating.

2. The drilling assembly of claim 1, wherein the actuation device applies forces on the tilt device to maintain the tilt device geostationary or substantially geostationary when the steering assembly is rotating.

3. The drilling assembly of claim 1 or 2, wherein the tilt device includes an adjuster and wherein the actuation device applies forces onto the adjuster to move the adjuster along a selected direction.

4. The drilling assembly of any of the claims 1-3, wherein movement of at least a part the actuation device is selectively adjustable to cause the first section to tilt with a selected tilt relative to the second section.

5. The drilling assembly of any of claims 1-4, wherein the tilt device includes a joint whose tilt is selectively adjustable to cause the first section to tilt with a selected tilt relative to the second section.

6. The apparatus of claim 1 or 2, wherein the tilt device is a hydraulic device and wherein the actuation device drives the hydraulic device to tilt the first section relative to the second section.

7. The apparatus of claim 6, wherein the actuation device selectively operates a valve of the hydraulic device to divert fluid flowing through the drilling assembly to tilt the first section relative to the second section.

8. The drilling assembly of claim 1 or 2, wherein the actuation device includes one or more spaced apart actuators, and wherein each such actuator applies force on a corresponding abutting element of the tilt device.

9. The drilling assembly of claim 8 further including a controller that controls the movement of at least one actuator of one or more actuators.

10. The drilling assembly of claim 9, wherein at least one of the abutting elements is selected from a group consisting of: a cam; a crank shaft; an eccentric member; a valve; a ramp element; and a lever.

11. The drilling assembly of claim 9, wherein the controller the tilt of the tilt device in response to a parameter of interest obtained from response of a sensor selected from a group consisting of: an accelerator; a gyroscope; a magnetometer, a formation evaluation sensor.

12. A method of drilling a wellbore, comprising:

conveying a drilling assembly in the wellbore, wherein the drilling assembly includes a disintegration device at an end thereof, a steering device that includes a tilt device and an actuation device, wherein a first section and a second section of the drilling assembly are coupled through the tilt device, and wherein the actuation device tilts the tilt device to cause the first section to tilt relative to the second section about the tilt device along a selected direction while the steering unit is rotating;

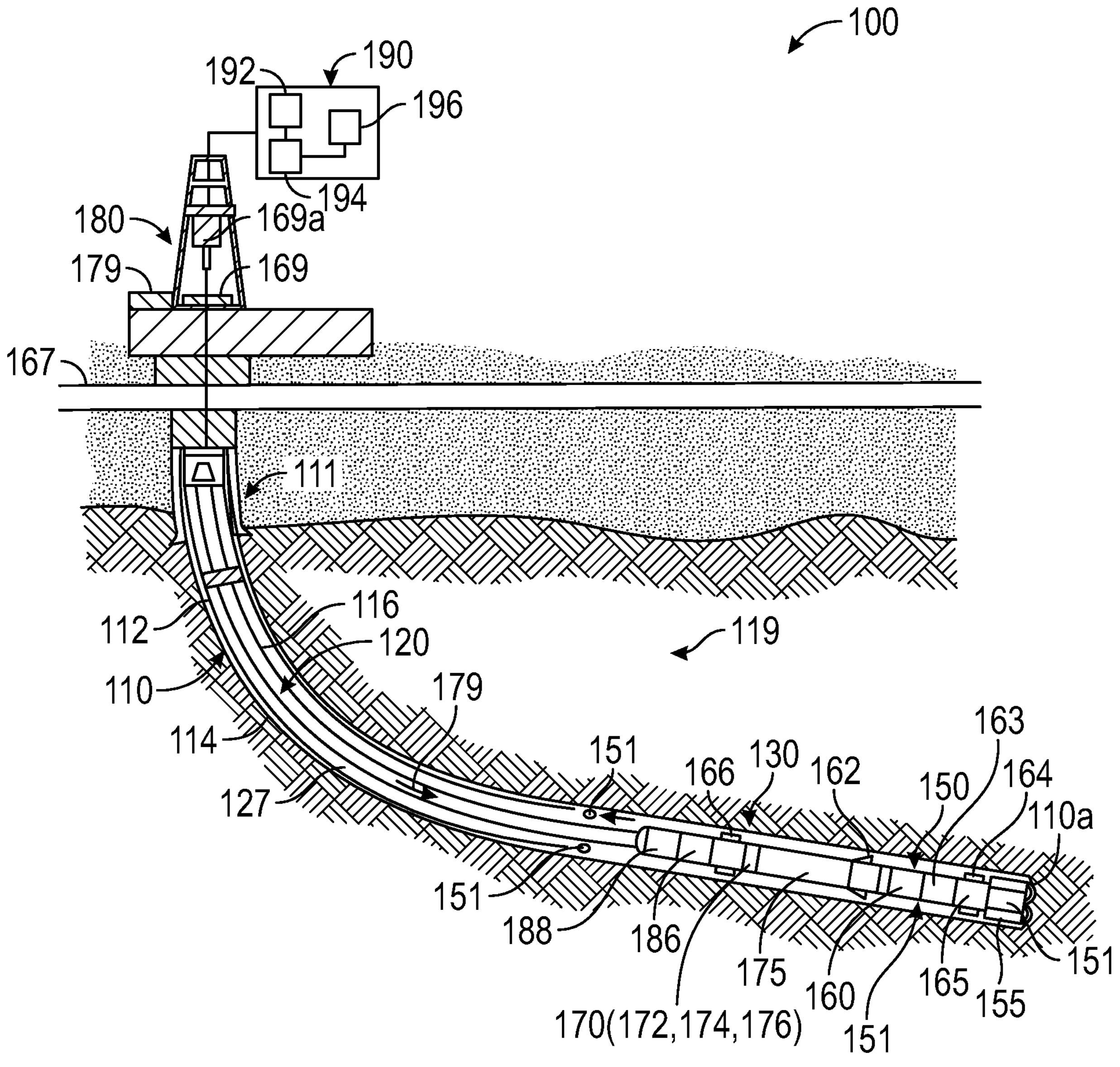
drilling the wellbore using the disintegration device; and

actuating the actuation device to tilt the tilt device to cause the first section to tilt relative to the upper section and to maintain the tilt geostationary while the drilling assembly is rotating to form a deviated section of the wellbore.

13. The method of claim 12, wherein the tilt device includes an adjuster and a joint and wherein the method further comprises applying forces on the adjuster to tilt the joint to cause the first section to tilt relative to the second section along the selected direction.

14. The method of claim 12 or 13, wherein the actuation device includes a plurality of spaced apart actuators, wherein each such actuator is configured to apply force on an abutting element of the tilt device.

15. The method of claim any of the claims 11-14, wherein the actuation device includes a plurality of actuators, wherein the method further comprises causing each such actuator to perform one stroke from a middle position thereof per revolution of the drilling assembly to drill the deviated section of the wellbore.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170(172,174,176)
151

FIG. 1

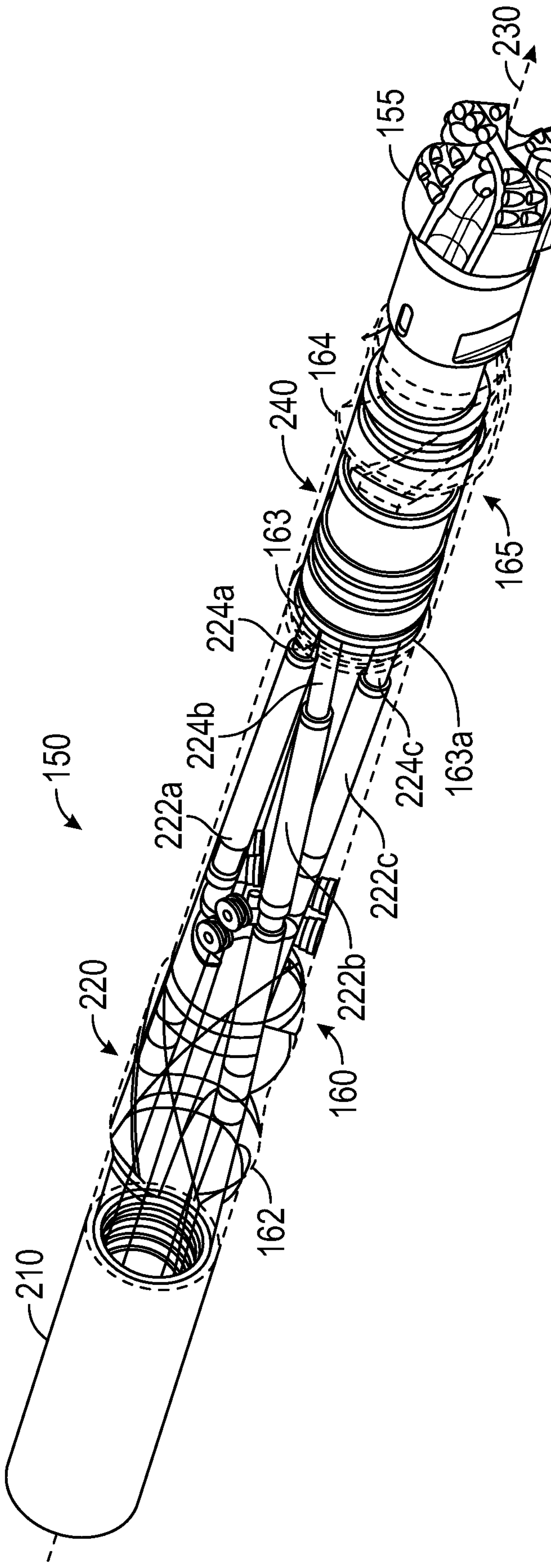
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FIG. 2

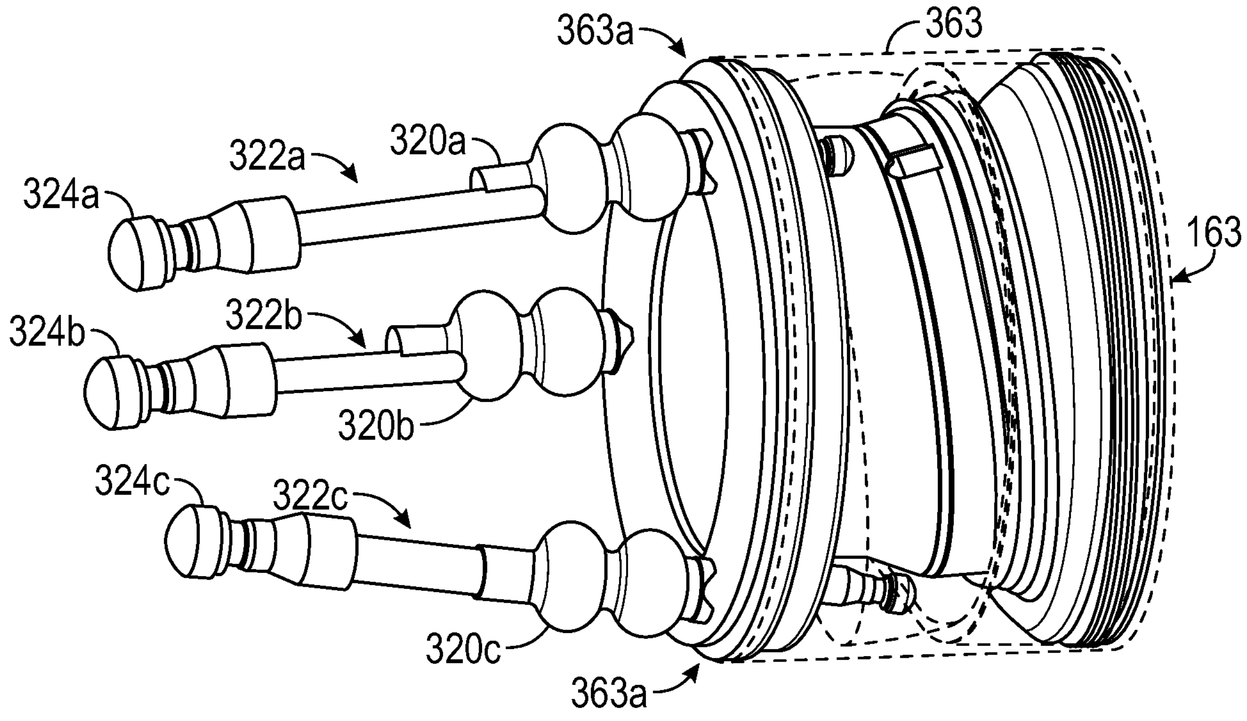
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FIG. 3

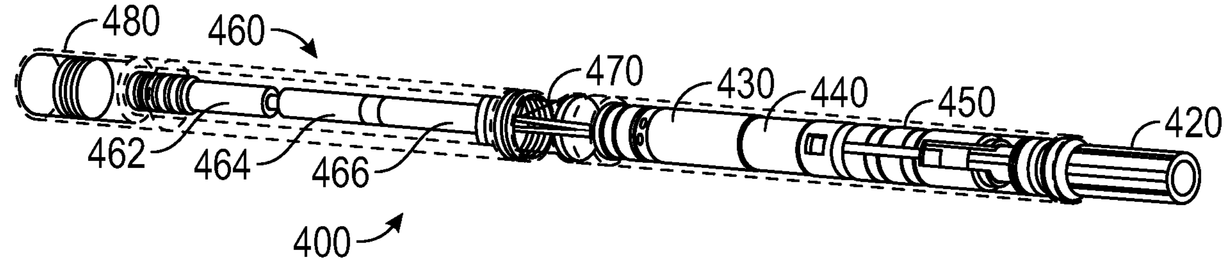
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FIG. 4

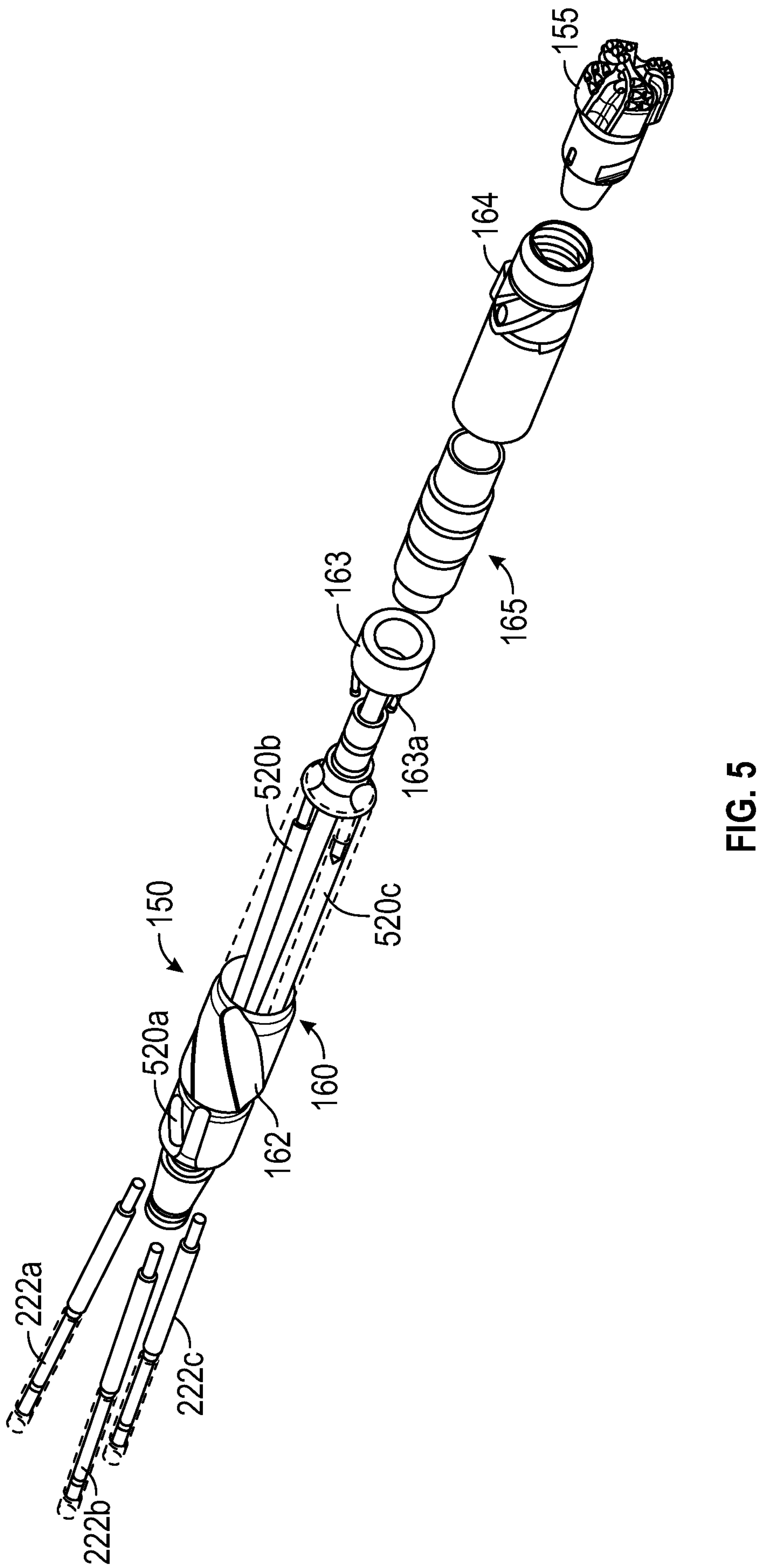
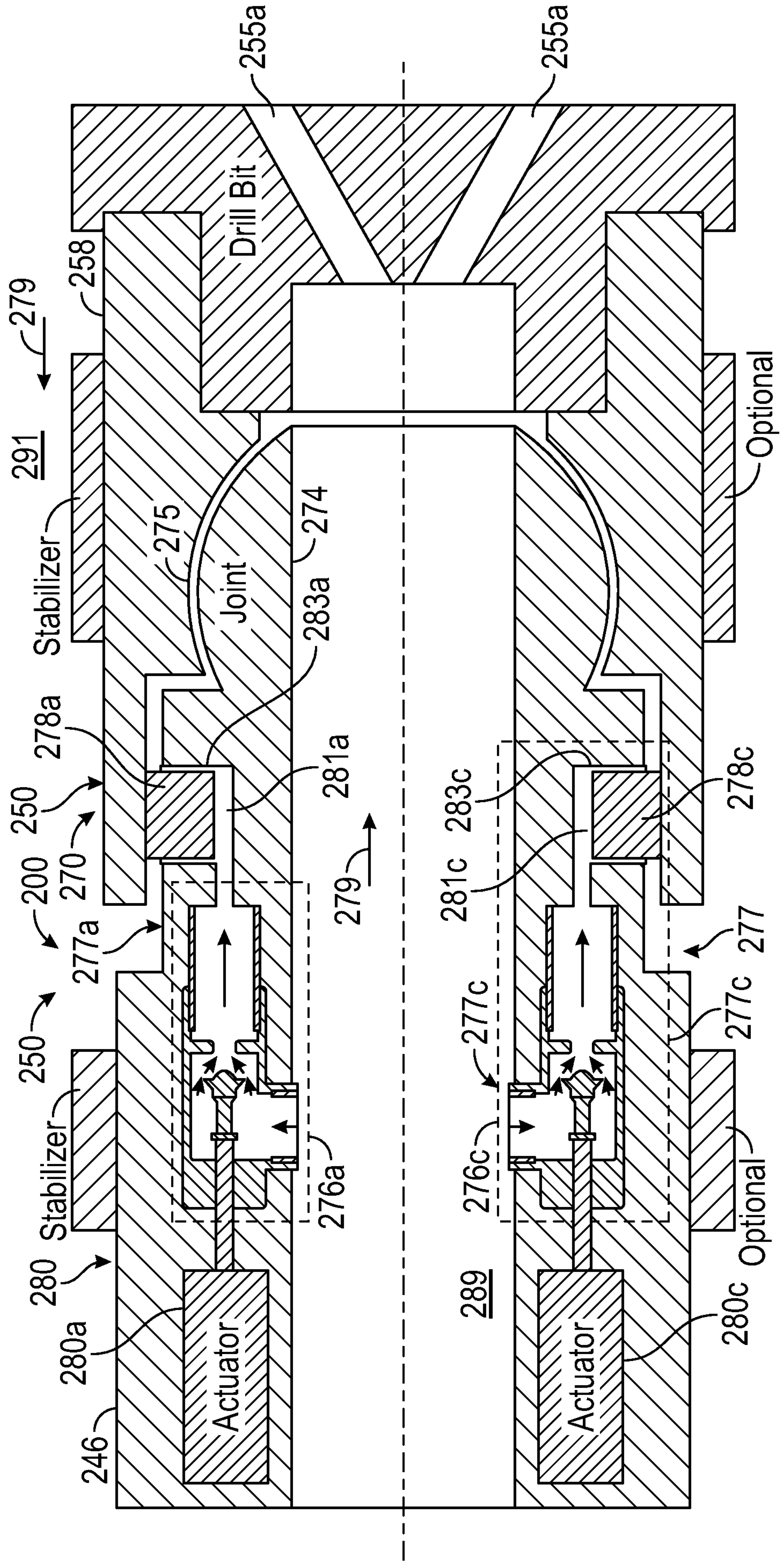


FIG. 5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Joint
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283c
278c
281c
277a
277
250
277c
277c
276a
276c
Stabilizer
Optional
280
289
280a
280c
Actuator
Actuator
246

FIG. 6

INTERNATIONAL SEARCH REPORT

International application No.
PCT/US2017/041634

A. CLASSIFICATION OF SUBJECT MATTER

E21B 7/06(2006.01)i, E21B 23/12(2006.01)i

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)
E21B 7/06; E21B 17/20; E21B 44/06; E21B 7/04; E21B 23/12

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched
Korean utility models and applications for utility models
Japanese utility models and applications for utility models

Electronic data base consulted during the international search (name of data base and, where practicable, search terms used)
eKOMPASS(KIPO internal) & Keywords: steering device, tilt, actuation device, adjuster, joint, valve, controller, disintegration device

C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
Y	US 2016-0108679 A1 (SCHLUMBERGER TECHNOLOGY CORPORATION) 21 April 2016 See paragraphs [0017], [0020], [0022], [0024], claim 1, and figure 3.	1-15
Y	US 2012-0018225 A1 (PETER et al.) 26 January 2012 See paragraphs [0017]-[0022], [0034] and figures 2, 4.	1-15
A	US 2009-0272579 A1 (SIHLER et al.) 05 November 2009 See paragraphs [0022]-[0025] and figures 2-5.	1-15
A	US 2014-0209389 A1 (SCHLUMBERGER TECHNOLOGY CORPORATION) 31 July 2014 See paragraphs [0020]-[0026] and figure 1.	1-15
A	US 6158529 A (DOREL, ALAIN P.) 12 December 2000 See column 9, line 12 - column 10, line 9 and figures 3-4.	1-15

☐ Further documents are listed in the continuation of Box C. ☒ See patent family annex.

* Special categories of cited documents:
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"T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention
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"Y" document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents,such combination being obvious to a person skilled in the art
"&" document member of the same patent family

Date of the actual completion of the international search	Date of mailing of the international search report
26 September 2017 (26.09.2017)	**26 September 2017 (26.09.2017)**

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