

## MIRAI MR16-06 Shipboard Three Component Magnetometer (STCM)

Last Modified: 2018-04-14

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Cruise ID: [MR16-06](#)

Shipboard Three Component Magnetometer (STCM): Processed (DMO)-Corrected

Data Policy: [JAMSTEC](#)

Observation Items: X, Y and Z component of geomagnetic field anomaly, Absolute value of geomagnetic field anomaly

Science Keywords:

OCEANS > MARINE GEOPHYSICS > MARINE MAGNETICS  
SOLID EARTH > GEOMAGNETISM

Cruise Report

[http://www.godac.jamstec.go.jp/catalog/data/doc\\_catalog/media/MR16-06\\_all.pdf](http://www.godac.jamstec.go.jp/catalog/data/doc_catalog/media/MR16-06_all.pdf)

### For Using Data

#### Principal Investigator

Data Management Office

#### Use Constraints

See [Terms and Conditions](#) about constrain of use.

#### Data Citation

See [Terms and Conditions](#) about data citation.

### Period (UTC)

2016-08-22 00:09 – 2016-10-04 23:38

### Instrument

Instrument:

Three component magnetometer



### Overview

The data provided is for corrected three component geomagnetic field anomalies. Three-axes flux-gate sensors with ring-cored coils were fixed on the roof of the bridge.

They measure the following items :

- h-component : along track line component, positive for the bow direction pitch.
- s-component : across track line component, positive for the starboard side roll.
- v-component : vertical component, positive for the downward direction.

The effect of ship motion was eliminated by roll and pitch data which was provided by a tilt sensor. The apparent magnetic influence can be detected through a "Figure of 8 turn"(a pair of clockwise and anti-clockwise turns) on each cruise. If no Figure of 8 turn on the cruise was completed, the latest Figure of 8 turn from the previous cruise was applied. As a quality control, data of low reliability was removed (see Data processing for quality control criteria). Synthetic geomagnetic field values were calculated from IGRF models.

### Measurement System

#### (1) Magnetometer

Manufacturer : Tierra Technica Ltd.  
Type : SFG1214  
Measurement range :  $\pm 100,000$  nT  
Accuracy : less than 100 nT  
Resolution : 1 nT  
Location : Dry Laboratory

#### (2) Magnetic Sensor

Manufacturer : Tierra Technica Ltd.  
Form : flux-gate sensors with ring-cored coils  
Location : Foremast

#### (3) Attitude sensor and Gyro compass

Manufacturer : IXBLUE  
Type : PHINS  
Accuracy(Roll, Pitch) : 0.01 degree  
Accuracy(Gyro) : 0.01 degree \*Secant(Lat.)  
Location : In the doppler radar dome

### Duration of the Figure of 8 turn

In MR16-06 cruise

Date (UTC)

2016-09-08 16:50:00 - 2016-09-08 17:10:00

2016-10-03 02:41:00 - 2016-10-03 03:03:00

### Data processing

The following corrections and calculations were performed.

- (1) Ship magnetization correction  
 $Hob = ARPYF + Hp \text{ ---(i)}$   
 Hob: Observed magnetic field vector (Ship coordinates)  
 A: Effect of induced magnetization of the ship  
 R: Matrix of rotation due to the roll  
 P: Matrix of rotation due to the pitch  
 Y: Matrix of rotation due to the heading  
 F: Geomagnetic field vector  
 Hp: Ship's permanent magnetic moment

Following the equation(i), we calculate the geomagnetic field F.

$$RPYF = BHob + Hbp \text{ ---(ii)}$$

B: coefficient of Figure of 8 turn

Hbp: Permanent magnetic field vector of the ship

Reference: Isezaki,N., A new shipboard three-component magnetometer, GEOPHYSICS. VOL.51,NO10(1986);P1992-1998

- (2) International Geomagnetic Reference Field (IGRF)

Synthetic geomagnetic field values are calculated from IGRF 12th Generation models by using navigation data ; latitude, longitude and date.

Reference: IAGA Division V-MOD Geomagnetic Field Modeling[<http://www.ngdc.noaa.gov/IAGA/vmod/igrf.html>]

- (3) Calculation of the geomagnetic field anomaly

$$An = F - Figrf$$

An: Geomagnetic field anomaly vector

F: Geomagnetic field vector

Figrf: Synthetic geomagnetic field vector from IGRF

- (4) Quality control of data

Following criteria were used for removal of data of low reliability:

- Time error (inversion of time, continuation of same timestamps)
- Summation of the difference of heading by one second exceeding 20 degree per 5 minutes
- Ground speed of the ship below 3knot or exceeding 20knot
- X, Y, or Z component of geomagnetic field anomaly exceeding  $\pm 4000nT$

- (5) Filtering of the geomagnetic field anomaly

Due to the residual undulation of the ship, a 120 second length Gaussian filter was applied for each component of the geomagnetic field anomaly data.

- (6) Output of the data

Time (UTC)

Latitude (degree)

Longitude (degree)

X: Northward (positive on the north) component of geomagnetic field anomaly (nT)

Y: Eastward (positive on the east) component of geomagnetic field anomaly (nT)

Z: Vertical (positive for downward) component of geomagnetic field anomaly (nT)

T: Absolute value of geomagnetic field anomaly (nT)

#### Coefficient of the Figure of 8 turn and Permanent magnetic field vector of the ship

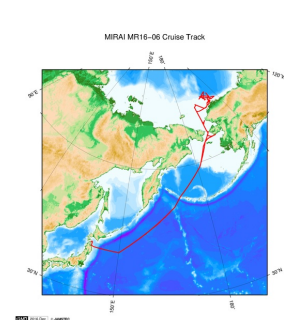
This coefficient was calculated from the above-mentioned Figure of 8 turn

	1.0017	0.0309	0.0327		2192.1398
B=	-0.0341	1.0652	-0.0093	Hbp=	236.8409
	0.0374	0.0046	0.9648		578.6310

#### Note

- (1) File naming rule: Cruise\_ID\_corr.stcm
- (2) Sampling rate: 10 seconds
- (3) Geodetic system: WGS84
- (4) If you would like the raw data set, please contact us from "Contact Us" above.

#### Related Information



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#### MR16-06

Ship Name: MIRAI

Period: 2016-08-22 - 2016-10-05

Chief Scientist: Shigeto Nishino (JAMSTEC)

Project Name: [Arctic Ocean Climate System Reaserch]

Proposal ▶ Predictability study on weather and sea-ice forecasts linked with user engagement

Title:

#### Update History

2018-04-14	An observation data was registerd.
2017-04-21	An observation data was registerd.

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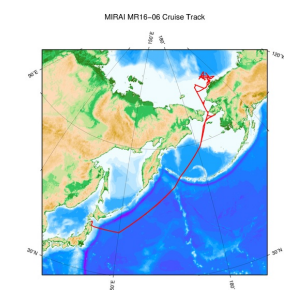
Shipboard Three Component Magnetometer (STCM): Processed (DMO)-Corrected

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### STCM Corrected

No.	Column	Content	Format	Unit	Remarks
1	1 - 8	Date	i4,i2,i2		YYYYMMDD (UTC)
2	10 -15	Time	i2,i2,i2		hhmmss (UTC)
3	17 -25	Latitude	f9.5	degree	No sign for the northern hemisphere. Negative for the southern hemisphere.
4	27 -36	Longitude	f10.5	degree	No sign for eastern hemisphere. Negative for the western hemisphere.
5	38 -43	X component of geomagnetic field anomaly	f6.0	nT	Positive on the north
6	45 -50	Y component of geomagnetic field anomaly	f6.0	nT	Positive on the east
7	52 -57	Z component of geomagnetic field anomaly	f6.0	nT	Positive for downward
8	59 -64	Absolute value of geomagnetic field anomaly	f6.0	nT	

### Related Information



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#### MR16-06

Ship Name: MIRAI

Period: 2016-08-22 - 2016-10-05

Chief Scientist: Shigeto Nishino (JAMSTEC)

Project Name: [Arctic Ocean Climate System Reaserch]

Proposal ▶ Predictability study on weather and sea-ice forecasts linked with user engagement

Title:

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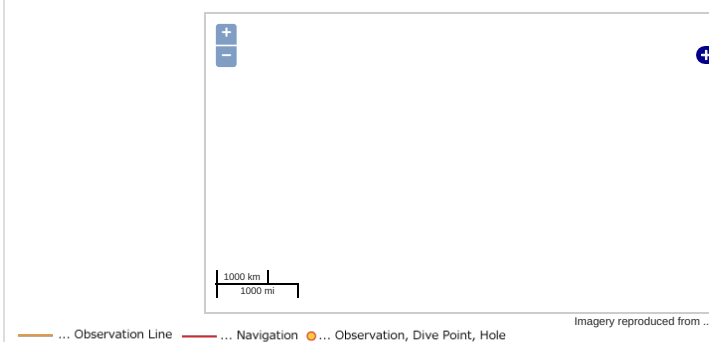
Observation Items: X, Y and Z component of geomagnetic field anomaly, Absolute value of geomagnetic field anomaly

Science Keywords:

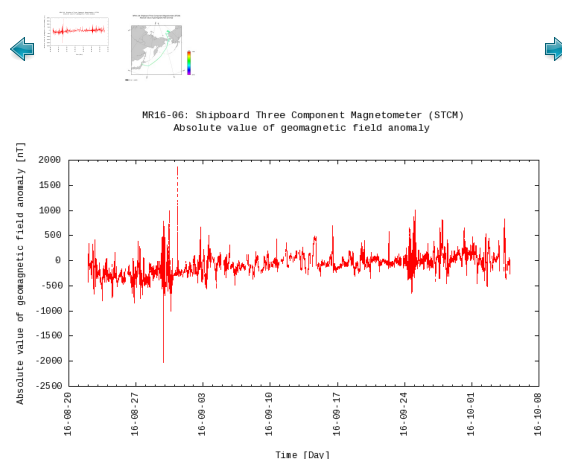
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### Observation Map



### Figures



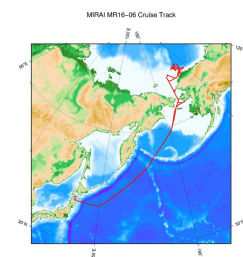
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File names

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### Related Information



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Ship Name: MIRAI

Period: 2016-08-22 - 2016-10-05

Chief Scientist: Shigeto Nishino (JAMSTEC)

Project Name: [Arctic Ocean Climate System Research]

Proposal ▶ Predictability study on weather and sea-ice forecasts linked with user engagement

Title:

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