

MIRAI MR03-K03 Leg1 Shipboard Three Component Magnetometer (STCM)

Last Modified: 2019-08-26

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Cruise ID: [MR03-K03 Leg1](#)

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

Data Policy: [JAMSTEC](#)

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

Science Keywords:

OCEANS > MARINE GEOPHYSICS > MARINE MAGNETICS
SOLID EARTH > GEOMAGNETISM

Cruise Report

http://www.godac.jamstec.go.jp/catalog/data/doc_catalog/media/MR03-K03_leg1-2_all.pdf

For Using Data

Principal Investigator

Data Management Office

JAMSTEC / BPPT joint cruise in the Indonesian waters.

Use Constraints

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

Data Citation

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

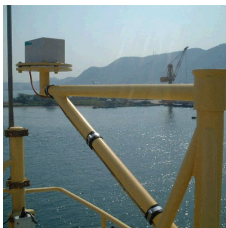
Period (UTC)

2003-06-07 09:02 – 2003-06-29 00:46

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 : Honeywell
Type : DRUH
Accuracy(Roll, Pitch) : less than ± 0.03 degree
Accuracy(Gyro) : less than ± 0.06 degree
Location : In the doppler radar dome

Duration of the Figure of 8 turn

In MR03-ENG and MR03-K03_leg1 cruise

Date (UTC)

2003/05/05 08:59:00 - 2003/05/05 09:36:00

2003/06/16 08:59:00 - 2003/06/16 09:17:00

Data processing

The following corrections and calculations were performed.

(1) Ship magnetization correction

$$\text{Hob} = \text{ARPYF} + \text{Hp} \quad \text{---(i)}$$

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.

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

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

$$\text{An} = \text{F} - \text{Figrf}$$

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 $\pm 4000\text{nT}$

(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

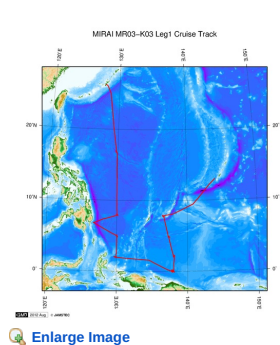
This coefficient was calculated from the above-mentioned Figure of 8 turn

| | | | | | |
|-----|---------|--------|---------|-------|-----------|
| | 0.9942 | 0.0337 | 0.0325 | | 2215.4165 |
| B = | -0.0372 | 1.0587 | -0.0038 | Hbp = | -57.6138 |
| | 0.0399 | 0.0050 | 0.9515 | | 1318.5834 |

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



MR03-K03 Leg1

Ship Name: MIRAI

Period: 2003-06-07 - 2003-06-29

Chief Scientist: Hideaki Hase (JAMSTEC)

Project Name: [Tropical Ocean Climate Study (TOCS)]

Update History

| | |
|------------|------------------------------------|
| 2019-08-26 | An observation data was registerd. |
| 2019-06-25 | An observation data was registerd. |
| 2018-12-29 | An observation data was registerd. |
| 2018-05-18 | An observation data was registerd. |
| 2016-04-07 | An observation data was registerd. |
| 2012-12-25 | An observation data was registerd. |

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KM-ROV
POWER GRAB SAMPLER
(SHELL)
POWER GRAB SAMPLER
(CLOW)
BMS

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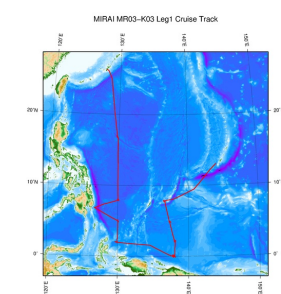
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STCM Corrected

| 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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MR03-K03 Leg1

Ship Name: MIRAI

Period: 2003-06-07 - 2003-06-29

Chief Scientist: Hideaki Hase (JAMSTEC)

Project Name: [Tropical Ocean Climate Study (TOCS)]

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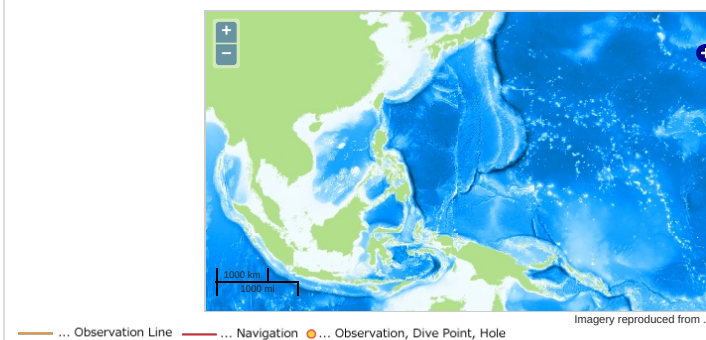
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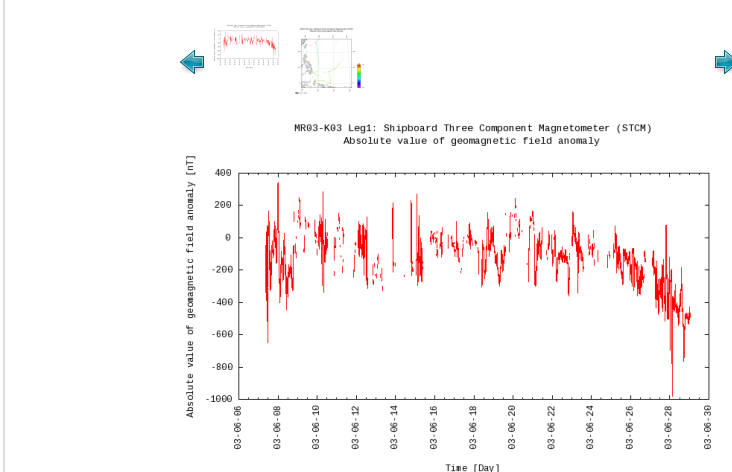
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Observation Map



Figures



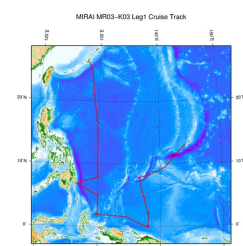
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File names

☐ MR03-K03_leg1_corr.stcm

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Period: 2003-06-07 - 2003-06-29

Chief Scientist: Hideaki Hase (JAMSTEC)

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