

SHINSEI MARU KS-17-J09C Shipboard Three Component Magnetometer (STCM)

Last Modified: 2019-08-26

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Cruise ID: [KS-17-J09C](#)

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/KS-17-J09C_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)

2017-07-08 01:15 – 2017-07-26 04:28

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 : SFG-2009
Measurement range : $\pm 100,000$ nT
Accuracy : less than ± 200 nT
Resolution : 0.01 nT
Location : No.1 Laboratory

(2) Magnetic Sensor

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

(3) Attitude sensor and Gyro compass

Manufacturer : IXBLUE
Type : PHINS
Accuracy(Roll, Pitch) : 0.01 degree
Accuracy(Gyro) : 0.01 degree *Secant(Lat.)
Location : Gravity meter room

Duration of the Figure of 8 turn

In KS-16-J03 cruise

Date (UTC)

2016/03/09 21:27:00 - 2016/03/09 21:47:00

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

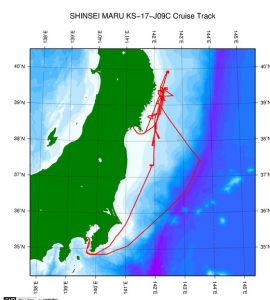
	1.0702	-0.0031	-0.0468		-799.1404
B=	-0.0005	1.1352	0.0030	Hbp=	-1027.6242
	0.0230	-0.0284	0.9123		-7909.6254

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

☒ Cruise Data ☐ Dive Data



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KS-17-J09C

Ship Name: SHINSEI MARU

Period: 2017-07-08 - 2017-07-26

Chief Scientist: Shinji Tsuchida (JAMSTEC)

Project Name: [Tohoku Ecosystem-Associated Marine Sciences (TEAMS)]

Proposal Researches on marine ecosystem dynamics in the Tsunami affected area off Sanriku

Title:

Update History

2019-08-26	An observation data was registered.
2019-06-12	An observation data was registered.
2018-06-29	An observation data was registered.

2018-05-26	An observation data was registerd.
2018-03-21	An observation data was registerd.
2017-12-13	An observation data was registerd.

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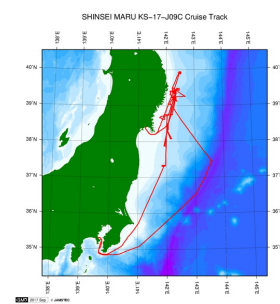
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STCM Corrected

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

[Cruise Data](#) [Dive Data](#)



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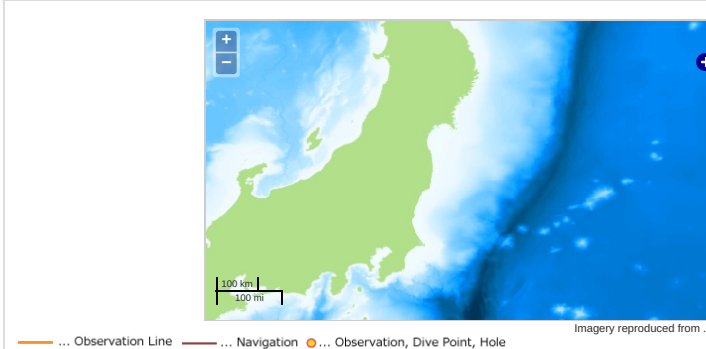
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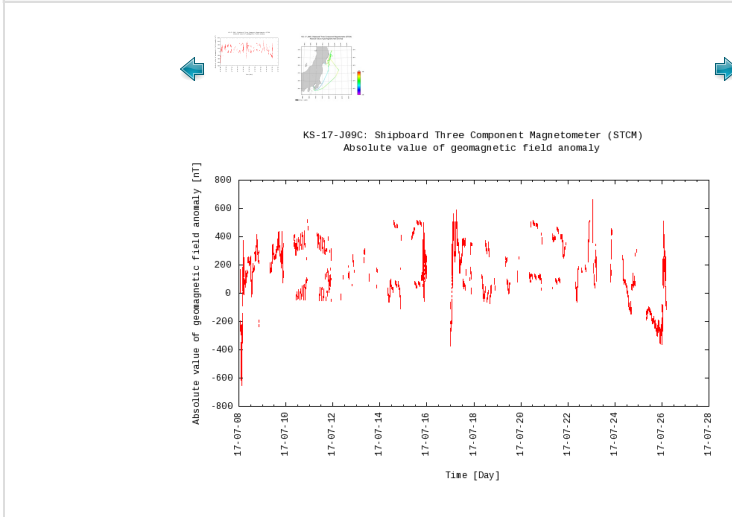
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Observation Map



Figures



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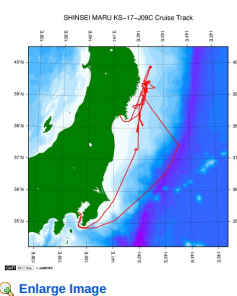
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File names

☐ KS-17-J09C_corr.stcm

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