

## KAIREI KR01-12 Leg1 Gravity

Last Modified: 2019-07-10

[ReadMe](#) [Observation Data](#) [Data Format](#)

Cruise ID: [KR01-12 Leg1](#)

Gravity: Processed (DMO)-Basic

Data Policy: [JAMSTEC](#)

Observation Items: Absolute gravity

Science Keywords:

OCEANS > MARINE GEOPHYSICS > MARINE GRAVITY FIELD  
SOLID EARTH > GEODETICS/GRAVITY > GRAVITY

Cruise Report

<http://pubs.usgs.gov/ds/2006/171/site/cruise-reports.html>

### 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)

2001-08-16 18:02 – 2001-08-31 17:40

### Instrument

Instrument:

Shipboard gravimeter ( - KR16-07)



Instrument:

Microgravimeter ( - KR07-18)



### Overview

The data provided here are absolute gravity data. The absolute gravity data are a combination of relative gravity data measured by the shipboard gravity meter and the absolute gravity data of the ports in departure and arrival. Drift corrections were done before converting into absolute gravity. The absolute gravity values of the ports are referenced to those of the Japan Gravity Standardization Net of the Geographical Survey Institute of Japan.

### Measurement System

#### (1) Shipboard gravity meter

The system consists of two main assemblies; the gyro-stabilized platform including the gravity sensor and the data handling & control system.

Manufacturer : BODENSEEWERK  
Model : KSS 31  
Measuring range : 10,000 mGal  
Accuracy : 1.0 mGal  
Drift rate : < 3.0 mGal/month  
Installation : Gravity meter room

Reference: "INSTRUCTION MANUAL for MARINE/AIR GRAVITYMETER SYSTEM KSS 31", Bodenseewerk 1996

#### (2) Portable gravity meter

The portable gravity meter consists of two modules; the data acquisition/control module and the gravity sensor module. The gravity sensor is enclosed in a thermostatically controlled vacuum chamber. The portable gravity meter is used to calculate the absolute gravity of the port with reference to the gravity station of the Japan Gravity Standardization Net of the Geographical Survey Institute of Japan.

Manufacturer : SCINTREX  
Model : CG-3M  
Measurement range : 7,000 mGal  
Standard deviation : 0.01 mGal  
Drift rate : < 0.02 mGal/day

Reference: "CG-3M AUTOGRAV AUTOMATED GRAVITY METER OPERATOR MANUAL", SCINTREX

### Absolute gravity in Ports

Date (UTC)	Port	Absolute gravity (mGal)	Sea level (cm)	Draft shipboard (cm)	Absolute gravity at sensor position (mGal)	Reading of shipboard gravity meter (mGal)
2001/07/23 23:47:10	YOKOSUKA/JAMSTEC	979758.3	230	460	979758.86	-1447.27
2001/11/05 23:19:00	YOKOSUKA/JAMSTEC	979758.3	180	470	979758.73	-1448.48

\* see [Term description](#)

### Data processing

According to the filter process of the gravity meter system, the gravity data has a time lag of 103 seconds between the measurement and its output. After adjustment of this lag time, the following corrections and calculations were performed.

#### (1) Drift correction

$$D = ((Vge - Vgs) - (Age - Ags)) / (Te - Ts)$$

D: Drift value (mGal/day)  
 Vgs: The shipboard gravity at the start of the cruise (mGal)  
 Vge: The shipboard gravity at the end of the cruise (mGal)  
 Ags: The absolute gravity at the shipboard sensor position at the start of the cruise (mGal)  
 Age: The absolute gravity at the shipboard sensor position at the end of the cruise (mGal)  
 Ts: The start time of the cruise (day)  
 Te: The end time of the cruise (day)

(2) Calculation of the absolute gravity

$$G = Ags + (Vg - Vgs) - D \cdot (T - Ts) + E + H \cdot \beta$$

G: The absolute gravity at sea surface (mGal)  
 Ags: The absolute gravity at the shipboard sensor position at the start of the cruise (mGal)  
 Vgs: The shipboard gravity at the start of the cruise (mGal)  
 Vg: The shipboard gravity at the measurement time (mGal)  
 D: Drift value (mGal/day)  
 Ts: The start time of the cruise (day)  
 T: The measurement time (day)  
 E: Eotvos correction (mGal)  
 H: Height from sea surface of the shipboard sensor position (m)  
 $\beta$ : Free-air gradient 0.3086 (mGal/m)

(3) Output of the data

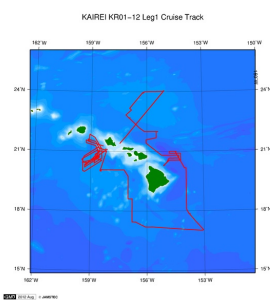
Time (UTC)  
 Latitude (degree)  
 Longitude (degree)  
 Processed absolute gravity (mGal)  
 Depth (m)

**Note**

- (1) File naming rule: Cruise ID\_p.grv
- (2) Sampling rate: 1 minute
- (3) 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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**KR01-12 Leg1**

Ship Name: KAIKEI  
 Period: 2001-08-16 - 2001-08-31  
 Chief Scientist: Eiichi Takahashi (Tokyo Institute of Technology)

**Update History**

2019-07-10	An observation data was registered.
2012-12-25	An observation data was registered.

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NATSUSHIMA

KAIYO

YOKOSUKA

MIRAI

KAIKEI

CHIKYU

KAIKEI

SHINSEI MARU

HAKUHO MARU

**Information of the Submersibles**

KAIKO

SHINKAI 2000

SHINKAI 6500

DEEP TOW

HYPER-DOLPHIN

URASHIMA

YOKOSUKA DEEP TOW

6K Camera DEEP TOW

6K Sonar DEEP TOW

KM-ROV

POWER GRAB SAMPLER (SHELL)

POWER GRAB SAMPLER (CLOW)

BMS

**Go to a Cruise Information**

Cruise ID:

**Go to a Dive Information**

Dive ID:

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Cruise ID: [KR01-12 Leg1](#)

Gravity: Processed (DMO)-Basic

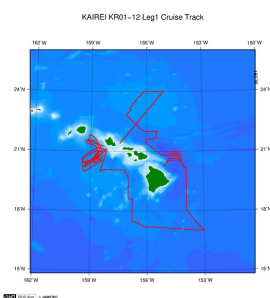
Data Policy: [JAMSTEC](#)

### Gravity Processed

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	Latitude (degree) ; positive in north, negative in south
4	27 -36	Longitude	f10.5	degree	Longitude (degree) ; positive in east, negative in west
5	39 -46	Gravity	f8.1	mGal	
6	48 -52	Depth	i5	m	

### Related Information

☒ Cruise Data ☐ Dive Data



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[6K Camera DEEP TOW](#)  
[6K Sonar DEEP TOW](#)  
[KM-ROV](#)  
[POWER GRAB SAMPLER \(SHELL\)](#)  
[POWER GRAB SAMPLER \(CLOW\)](#)  
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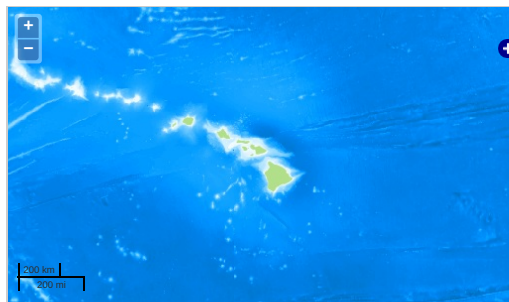
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Observation Items: Absolute gravity

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### Observation Map



— ... Observation Line — ... Navigation ● ... Observation, Dive Point, Hole

Imagery reproduced from ...

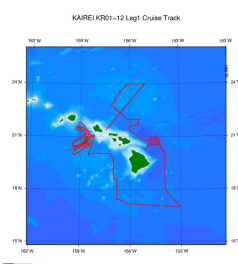
### Data List

File names

☐ KR01-12\_leg1\_p.grv

### Related Information

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



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