

**For Using Data**

Data Policy	JAMSTEC
Principal Investigator	Data Management Office
Use Constraints	See Terms and Conditions about constrain of use.
Data Citation	See Terms and Conditions about data citation.

**Quality**

DMO-Processed

**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-2015
Measurement range :	$\pm 100,000$ nT
Accuracy :	less than $\pm 200$ 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
	Gyro : 0.01 degree *Secant (Lat.)
Location :	Gravity meter room

**Duration of the Figure of 8 turn**

In KM23-06 cruise

Date (UTC)

2023/05/10 15:05:00 - 2023/05/10 15:39:00

2023/05/18 02:18:00 - 2023/05/18 02:50:00

2023/05/20 17:16:00 - 2023/05/20 17:41:00

**Data processing**

The following corrections and calculations were performed.

1) Ship magnetization correction

$$Hob = ARPYF + Hp \cdots (i)$$

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.

$$RPYF = BHob + Hpb \cdots (ii)$$

B : coefficient of Figure of 8 turn

Hpb : 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 13th 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 3 knot or exceeding 20 knot
- X, Y, or Z component of geomagnetic field anomaly exceeding  $\pm 4000$  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

B			Hpb
1.0660	0.0025	-0.0924	4666.1951
-0.0165	1.0597	-0.0840	12425.9695
-0.0060	0.1190	0.8548	2862.5882

**Note**

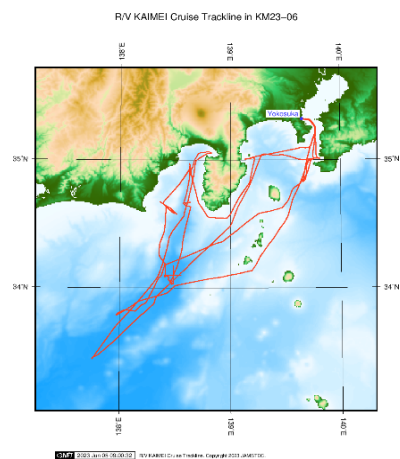
1) File naming rule : Cruise ID\_corr.stcm

2) Data interval : 10 seconds

3) Geodetic system : WGS84

4) If you would like the raw data set, please contact DMO at "dmo@jamstec.go.jp".

Related Information



KM23-06

Ship Name:	KAIMEI
Period:	2023/05/10 - 2023/05/23
Chief Scientist:	Kyoma Takahashi (JAMSTEC)
Proposal:	R/V Kaimei & KM-ROV & Jinbei Engineering cruise

## Format Description for 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	