

## MIRAI MR15-03 Leg1 Shipboard Three Component Magnetometer (STCM)

Last Modified: 2019-06-21

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Cruise ID: [MR15-03 Leg1](#)

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/MR15-03\\_leg1\\_all.pdf](http://www.godac.jamstec.go.jp/catalog/data/doc_catalog/media/MR15-03_leg1_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)

2015-08-23 23:11 – 2015-10-06 18:38

### 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 MR15-03\_leg1 cruise

Date (UTC)

2015-09-01 03:22:00 - 2015-09-01 03:46:00

2015-09-17 04:15:00 - 2015-09-17 04:36:00

### 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

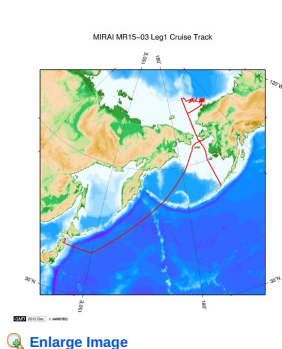
This coefficient was calculated from the above-mentioned Figure of 8 turn

	0.9956	0.0361	0.0317		2154.7152
B=	-0.0401	1.0596	-0.0020	Hbp=	-289.1176
	0.0376	0.0047	0.9485		1643.7156

#### 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



#### MR15-03 Leg1

Ship Name: MIRAI  
Period: 2015-08-23 - 2015-10-06  
Chief Scientist: Shigeto Nishino (JAMSTEC)  
Project Name: [Arctic Ocean Climate System Reaserch]  
Proposal ▶ Observational studies on the Arctic Ocean climate and ecosystem variability  
Title:

#### Update History

2019-06-21	An observation data was registerd.
2018-04-14	An observation data was registerd.
2017-08-24	An observation data was registerd.
2016-04-06	An observation data was registerd.

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HAKUHO MARU

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6K Camera DEEP TOW  
6K Sonar DEEP TOW  
KM-ROV  
POWER GRAB SAMPLER  
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POWER GRAB SAMPLER  
(CLOW)  
BMS

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**JAMSTEC**  
JAPAN AGENCY FOR MARINE-EARTH SCIENCE AND TECHNOLOGY

国立研究開発法人  
海洋研究開発機構

## MIRAI MR15-03 Leg1 Shipboard Three Component Magnetometer (STCM)

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Cruise ID: [MR15-03 Leg1](#)

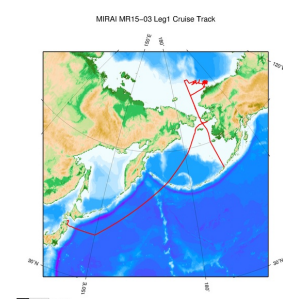
Shipboard Three Component Magnetometer (STCM): Processed (DMO)-Corrected

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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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#### MR15-03 Leg1

Ship Name: MIRAI

Period: 2015-08-23 - 2015-10-06

Chief Scientist: Shigeto Nishino (JAMSTEC)

Project Name: [Arctic Ocean Climate System Reaserch]

Proposal ▶ Observational studies on the Arctic Ocean climate and ecosystem variability

Title:

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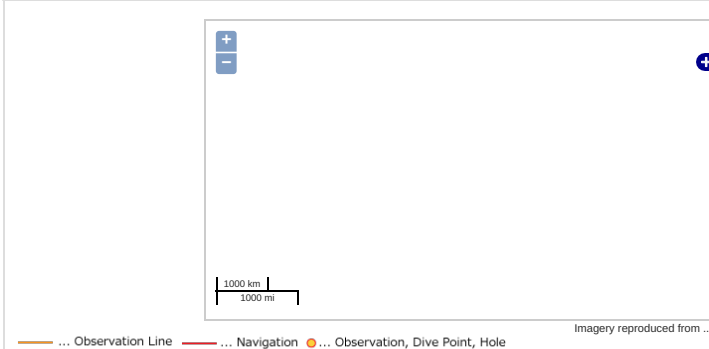
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Science Keywords:

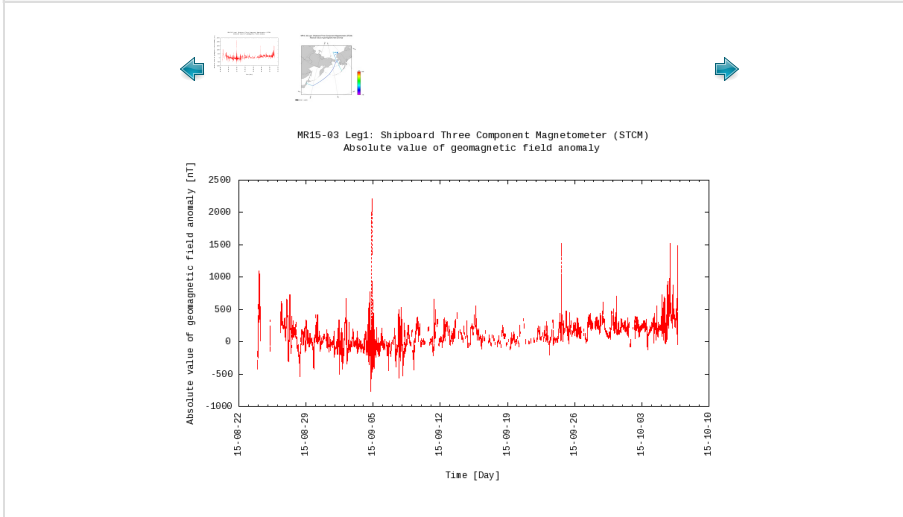
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SOLID EARTH > GEOMAGNETISM

### Observation Map



### Figures



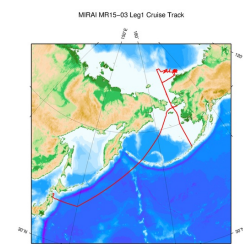
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File names

☐ MR15-03\_leg1.stcm

### Related Information



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Ship Name: MIRAI

Period: 2015-08-23 - 2015-10-06

Chief Scientist: Shigeto Nishino (JAMSTEC)

Project Name: [Arctic Ocean Climate System Research]

Proposal ▶ Observational studies on the Arctic Ocean climate and ecosystem variability

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