

MIRAI MR11-08 Leg2 Shipboard Three Component Magnetometer (STCM)

Last Modified: 2019-06-22

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Cruise ID: [MR11-08 Leg2](#)

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/MR11-08_leg1-3_all.pdf

For Using Data

Principal Investigator

Data Management Office

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

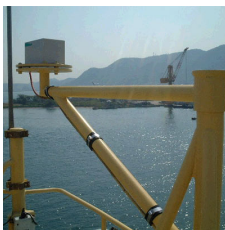
Period (UTC)

2011-12-23 19:35 – 2012-01-10 13:59
2011-12-21 22:16 – 2011-12-22 00:00

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 (see section 4.). As a quality control, data of low reliability was removed (see section 5. 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 Mr11-06 cruise

Date (UTC)

2011/08/23 06:54:00 - 2011/08/23 07:20:00
2011/09/02 12:58:00 - 2011/09/02 13:29:00

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 11th 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

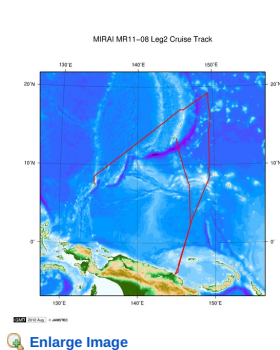
This coefficient was calculated from the Figure of 8 turn (see section 4.)

		0.9880	0.0585	0.0295		2211.5916
B=		-0.0633	1.0528	-0.0034	Hbp=	232.7431
		0.0389	0.0068	0.9395		777.9997

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



MR11-08 Leg2
Ship Name: MIRAI
Period: 2011-12-20 - 2012-01-12
Chief Scientist: Akihiko Murata (JAMSTEC)
Project Name: [POST-WOCE Hydrography]

Update History

2019-06-22	An observation data was registerd.
2018-04-18	An observation data was registerd.
2014-08-09	An observation data was registerd.
2012-09-28	An observation data was registerd.

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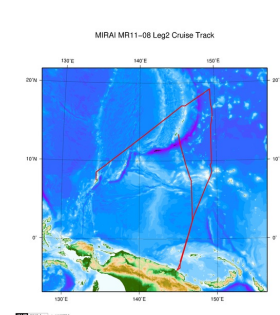
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STCM Corrected

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



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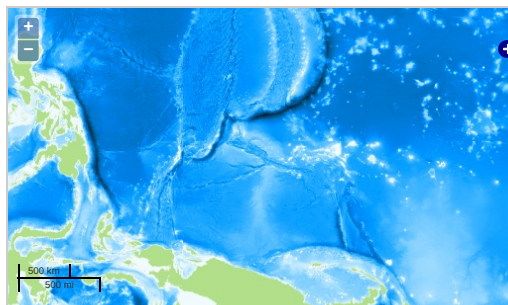
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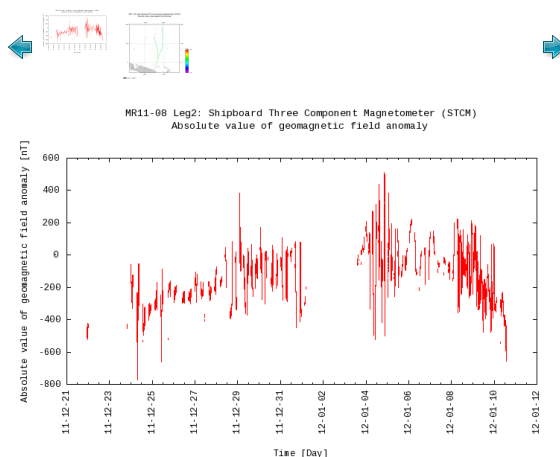
Observation Map



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

Imagery reproduced from ...

Figures



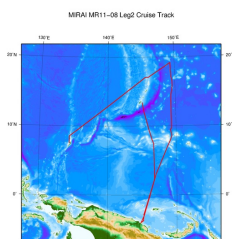
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File names

☐ MR11-08_leg2_corr.stcm

Related Information



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