

MIRAI MR05-05 Leg1 Shipboard Three Component Magnetometer (STCM)

Last Modified: 2019-08-26

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Cruise ID: [MR05-05 Leg1](#)

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

Data Policy: [JAMSTEC](#)

Observation Items: X, Y and Z component of geomagnetic field

Science Keywords:

OCEANS > MARINE GEOPHYSICS > MARINE MAGNETICS
SOLID EARTH > GEOMAGNETISM

Cruise Report

http://www.godac.jamstec.go.jp/catalog/data/doc_catalog/media/MR05-05_leg1-3_all.pdf

For Using Data

Principal Investigator

Data Management Office

Use Constraints

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Data Citation

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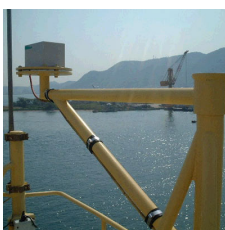
Period (UTC)

2005-10-31 17:04 – 2005-11-23 23:07

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 : Honeywell
Type : DRUH
Accuracy(Roll, Pitch) : less than ± 0.03 degree
Accuracy(Gyro) : less than ± 0.06 degree
Location : In the doppler radar dome

Duration of the Figure of 8 turn

In MR05-05_leg1 cruise

Date (UTC)

2005/11/10 23:59:00 - 2005/11/11 00:24:00

Data processing

The following corrections and calculations were performed.

- (1) Ship magnetization correction

Calculation of the geomagnetic field vector

$Hob = ARPYF + Hp$ ---(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.

$$RPYF = BHob + Hbp$$
 ---(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

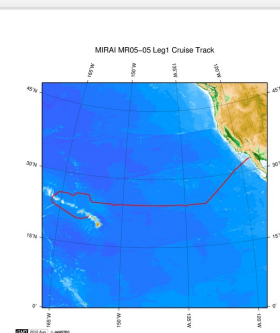
This coefficient was calculated from the above-mentioned Figure of 8 turn

	0.9878	0.0317	0.0026		2883.2768
B =	-0.0386	1.0591	-0.0519	Hbp =	1089.2024
	0.0350	0.0038	0.8490		4335.4107

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



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MR05-05 Leg1

Ship Name: MIRAI

Period: 2005-10-31 - 2005-11-24

Chief Scientist: Takeshi Kawano (JAMSTEC)

Project Name: [POST-WOCE Hydrography]

Update History

2019-08-26	An observation data was registered.
2019-06-25	An observation data was registered.
2018-08-28	An observation data was registered.
2018-05-18	An observation data was registered.
2012-11-25	An observation data was registered.

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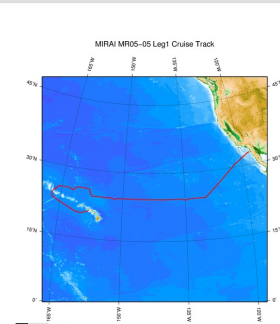
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STCM Corrected

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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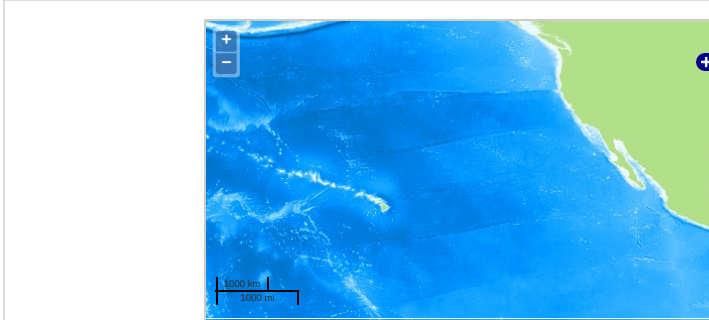
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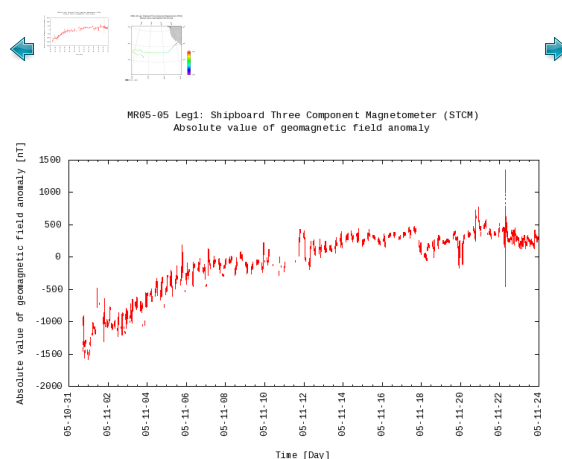
Observation Map



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

Imagery reproduced from ...

Figures



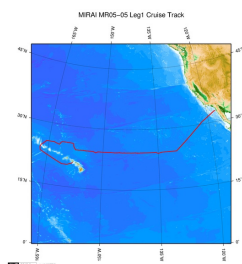
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File names

☐ MR05-05_leg1_corr.stcm

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