

MIRAI MR10-03 Leg1 Shipboard Three Component Magnetometer (STCM)

Last Modified: 2019-06-22

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Cruise ID: [MR10-03 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/MR10-03_leg1-2_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)

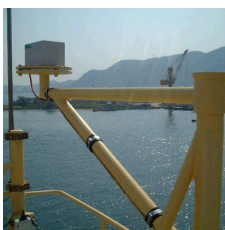
2010-05-09 05:19 – 2010-05-11 22:57

2010-05-05 06:47 – 2010-05-08 12:20

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 MR10-02 cruise

Date (UTC)

2010-04-20 09:02:00 - 2010-04-20 09:26:00

Data processing

The following corrections and calculations were performed.

(1) Ship magnetization correction
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 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 ±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

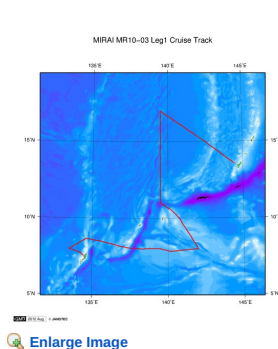
This coefficient was calculated from the Figure of 8 turn (see section 4.)

	0.9959	0.0415	0.0150		1932.1618
B=	-0.0440	1.0617	0.0047	Hbp=	-10.2992
	0.0326	0.0044	0.7709		-709.3906

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



MR10-03 Leg1
Ship Name: MIRAI
Period: 2010-05-05 - 2010-05-12
Chief Scientist: Hiroyuki Yamada (JAMSTEC)
Project Name: [MJO Research]
Proposal ▶ Observational Study on Air-Sea Interaction in the Tropical Western Pacific Ocean
Title:

Update History

2019-06-22	An observation data was registerd.
2018-04-18	An observation data was registerd.
2014-08-07	An observation data was registerd.
2012-09-28	An observation data was registerd.

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6K Camera DEEP TOW
6K Sonar DEEP TOW
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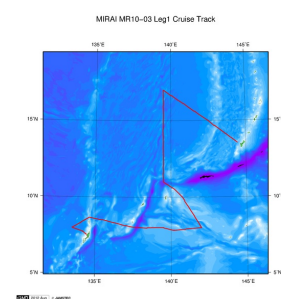
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STCM Corrected

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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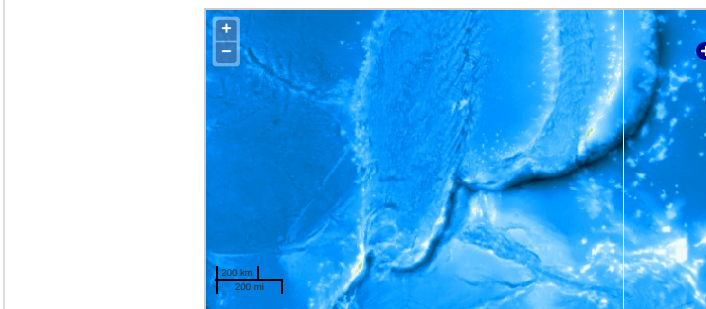
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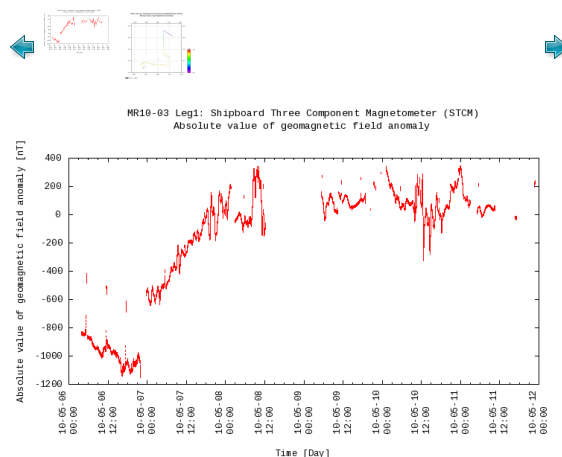
SOLID EARTH > GEOMAGNETISM

Observation Map



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

Figures



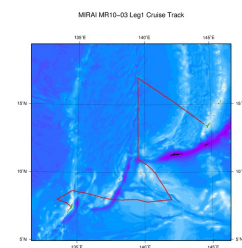
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File names

☐ MR10-03_leg1_corr.stcm

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