## MGL-dgsraw.*

The DGS gravimeter raw data are also output as a serial stream captured by LDS. They are recorded mostly for backup purposes without any correction to files MGL-dgsraw.y*YYYY*d*jjj* in the following format. See the description of the MGL-dgsdata format

| $AT1M_*a.aaa*_nnn,n,n,n,n,n,n,n,n,n,n,n,n,n,x.x,x.x,x.x,x.x,n | | |
|---|---|---|
| **Item** | **Definition** | **Units / Options** |
| *a.aaa* | Harware version | m |
| nnn | Number of lines/seconds since last reset | n/a |
| n,n,n,n | dgravity, dlong, dcross, dbeam from 24-bit AD converter | n/a |
| n,n | dpressure, dtemp unfiltered from 10-bit AD converter | n/a (hexadecimal) |
| n,n,n,n | rvcc, rve, ral, rax monitors | n/a |
| n | status | n/a |
| n | checksum | n/a |
| x.x,x.x,x.x,x.x | Latitude, Longitude, speed, course – 0 in raw data | n/a |
| s | UTC time | s |

## MGL-gy01.*

The Simrad GC80 Dual Gyro Compass output to files *MGL-gy01.yYYYYdjjj*. The following sentence types were recorded:
- HEHDT: True Heading
- HEROT: Rate of Turn
- PTKM: Alarm

### $HEHDT Sentence

| $HEHDT,x.x,T*hh | | |
|---|---|---|
| **Item** | **Definition** | **Units / Options** |
| x.x | Heading | Degrees |
| T | T = Preceding value is True heading | n/a |
| *hh | Checksum | n/a (hexadecimal) |

### $HEROT Sentence

| $HEROT,x.x,T*hh | | |
|---|---|---|
| **Item** | **Definition** | **Units / Options** |
| x.x | Rate of turn | Degrees per minute; "-" = bow turns to port |
| *a* | Status | n/a; A: Valid data |
| *hh | Checksum | n/a (hexadecimal) |

### $PTKM Sentence

| $PTKM,*aaaa*,nnnn,n,*a*\*hh | | |
|---|---|---|
| **Item** | **Definition** | **Units / Options** |
| HEALM | Almanac code | n/a |
| nnnn | unspecified | n/a |
| n | unspecified | n/a |
| *hh | Checksum | n/a (hexadecimal) |