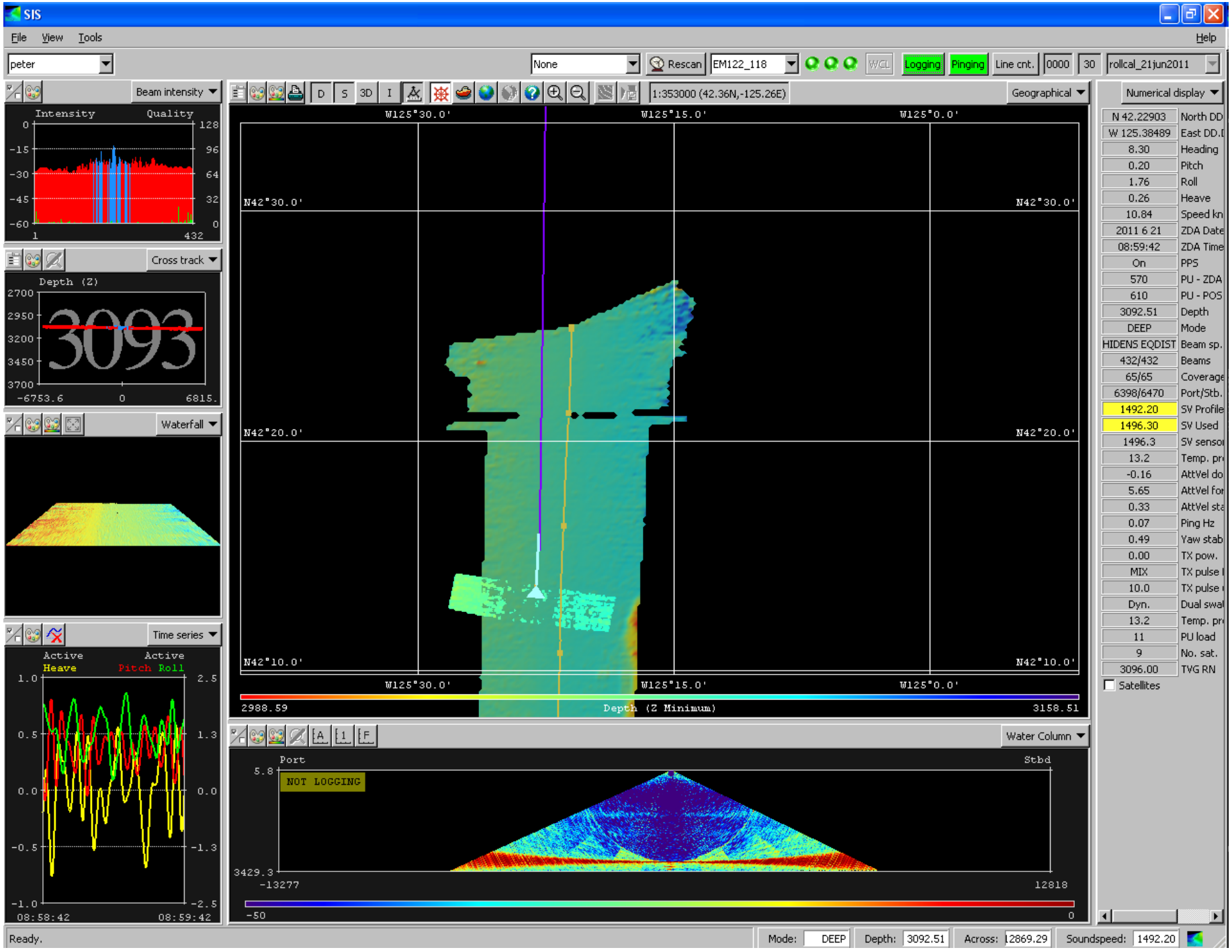
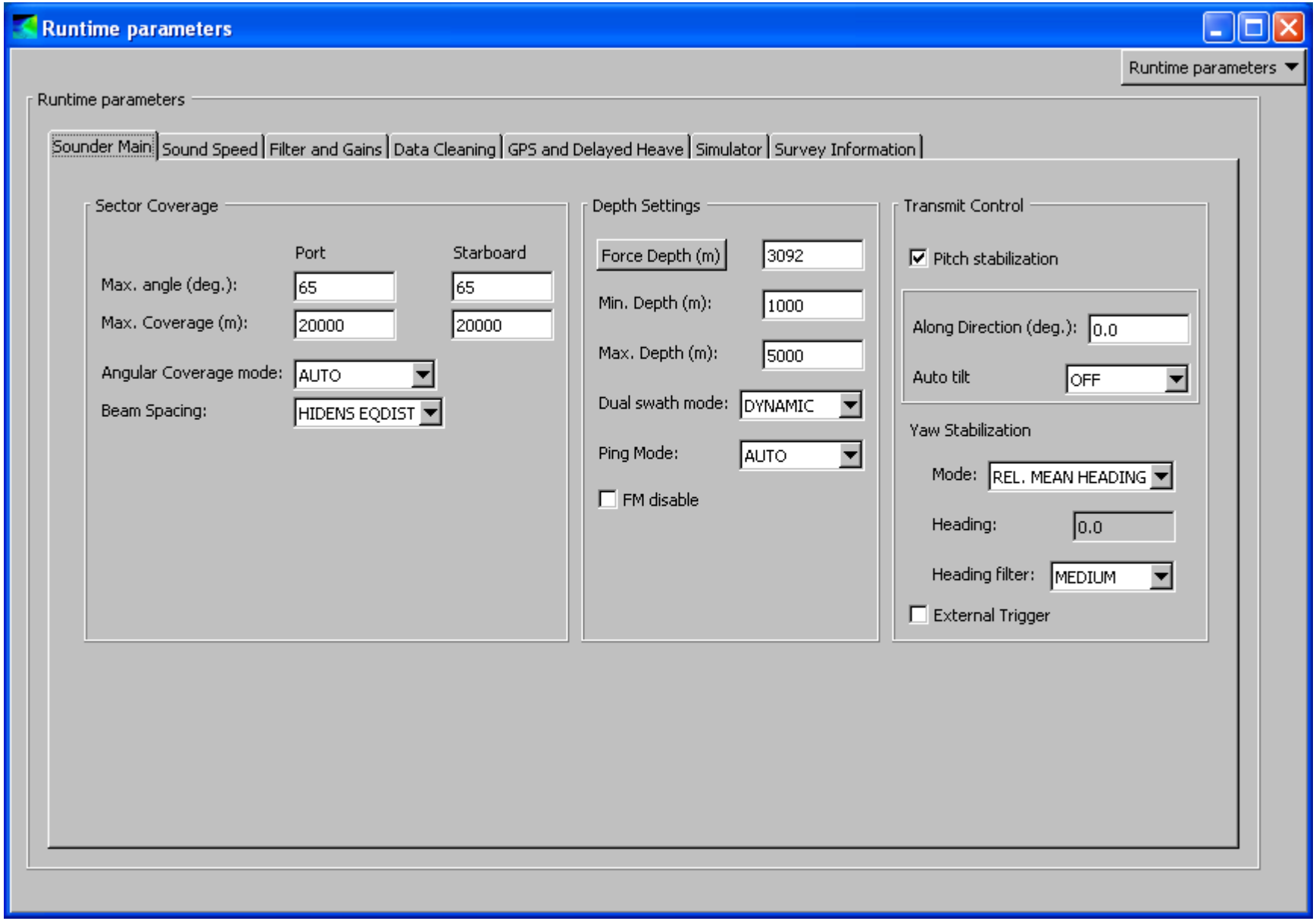
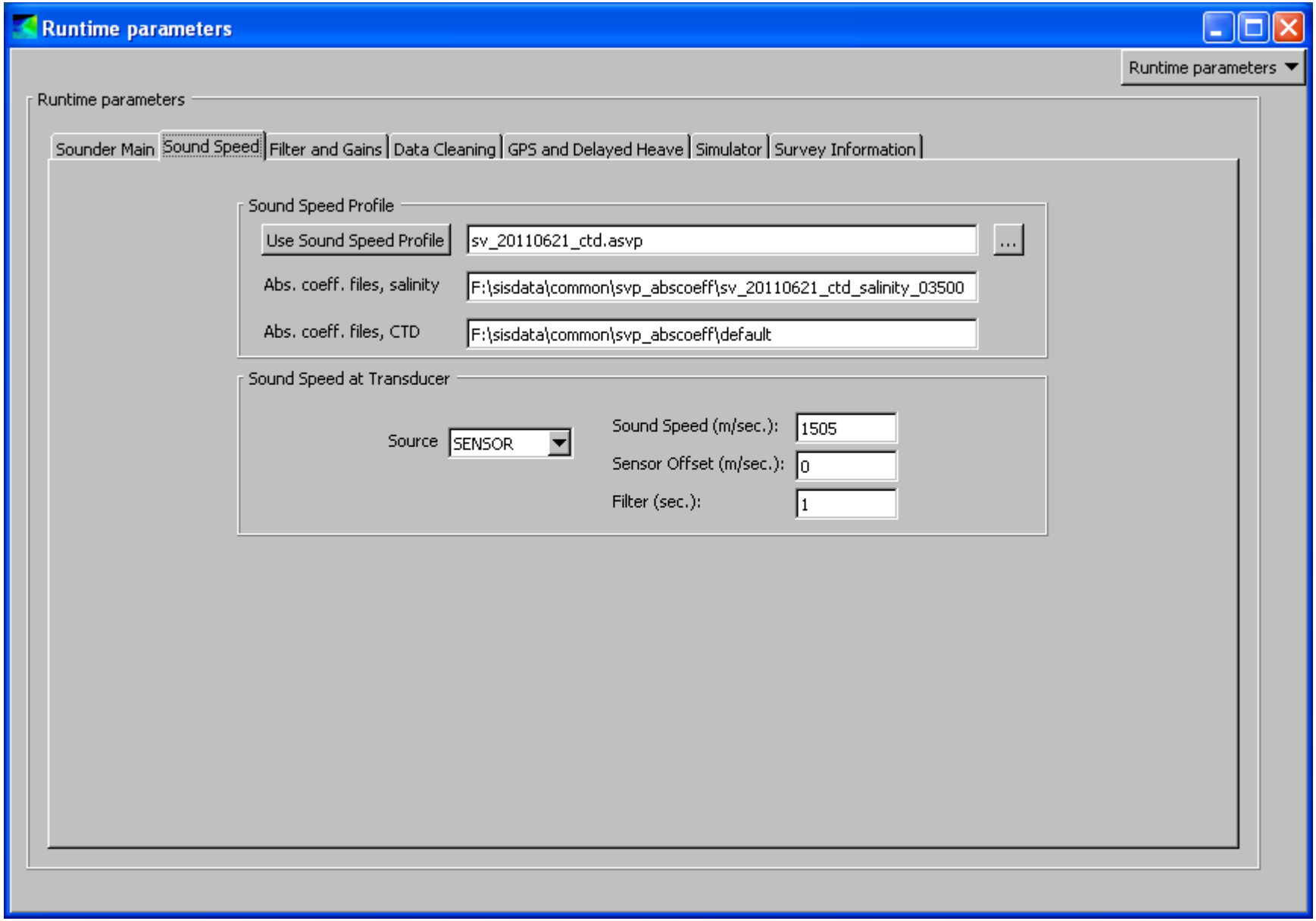
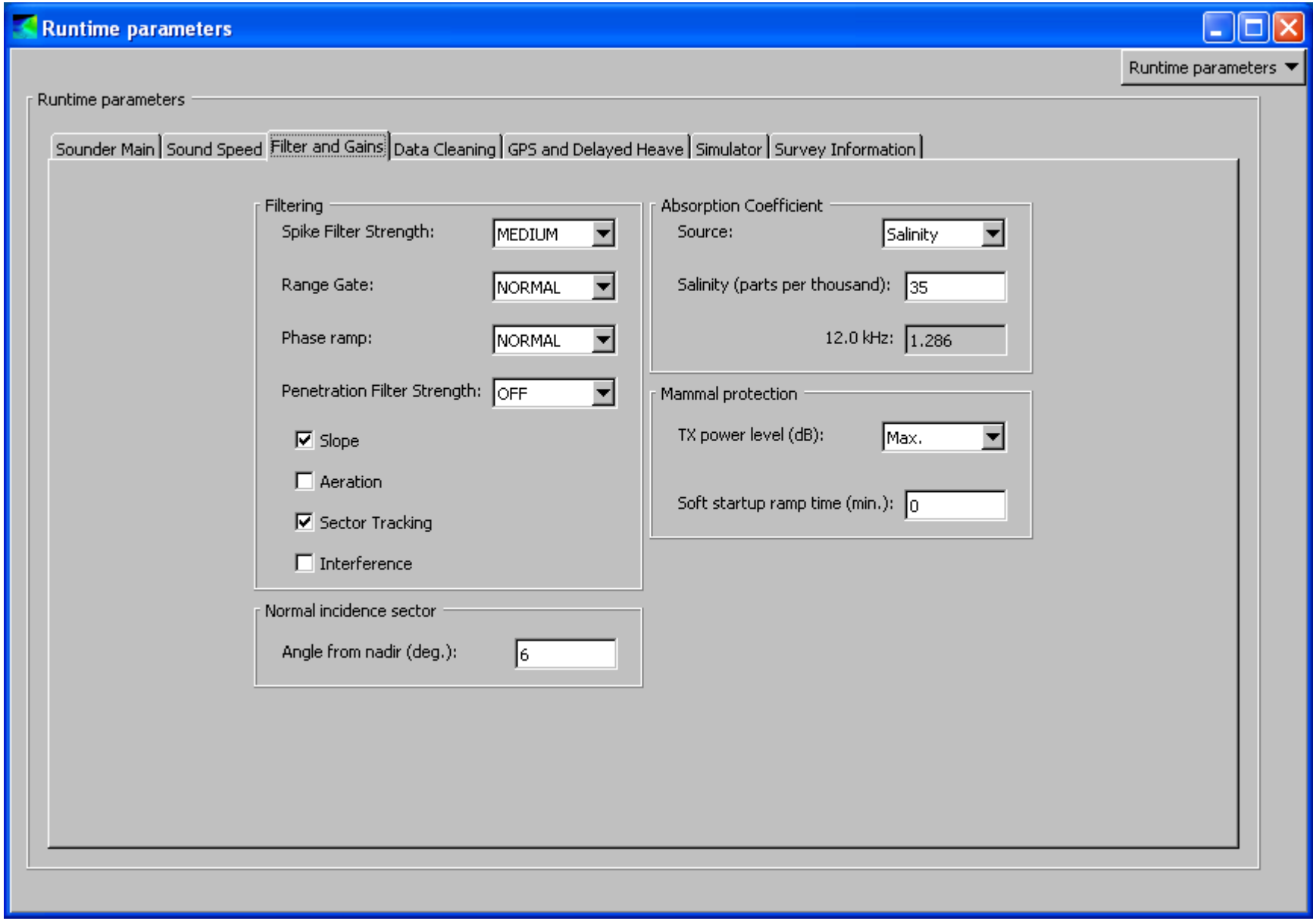
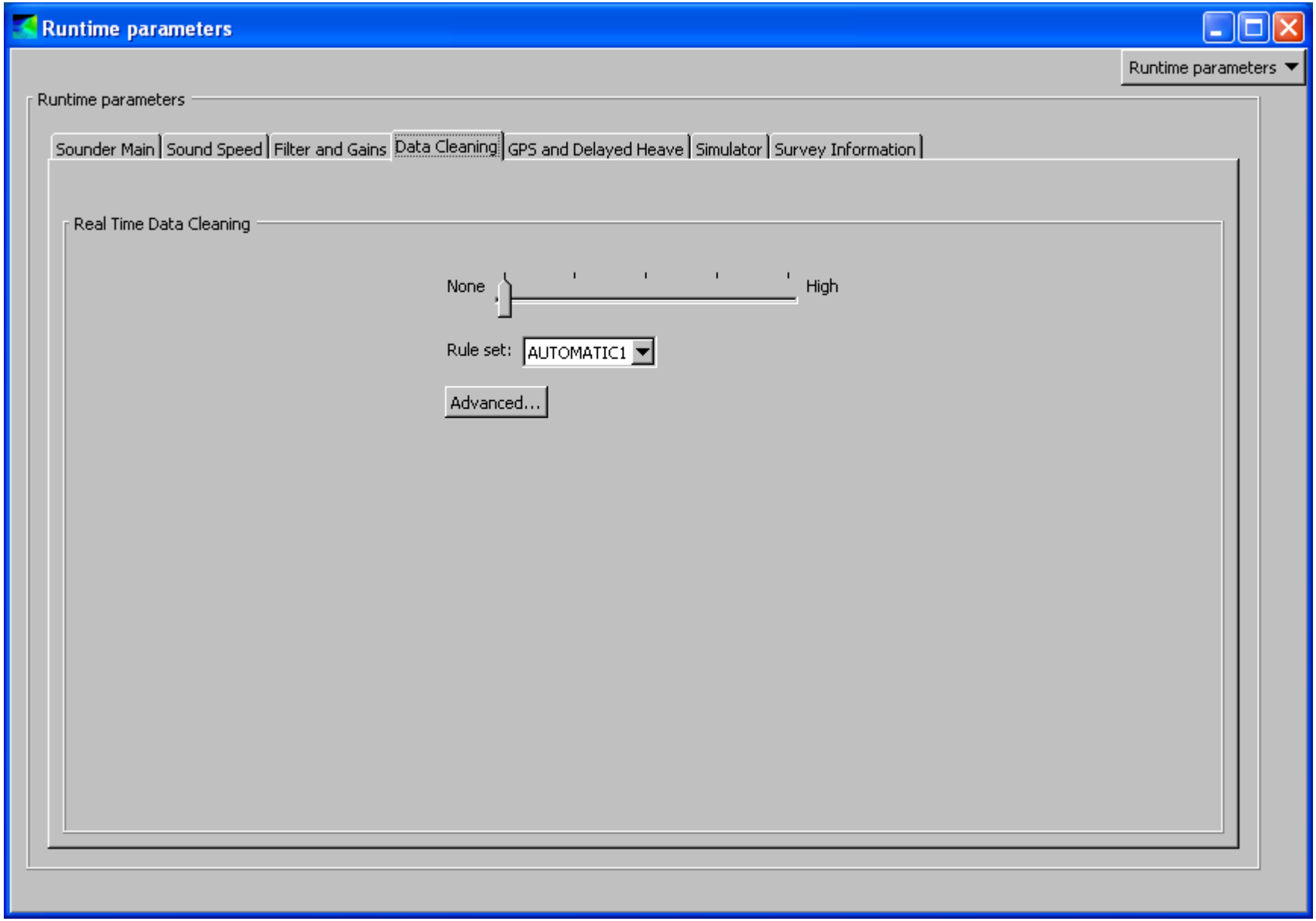
SIS Settings
SAT Test
June 21-22, 2011
R/V Atlantis

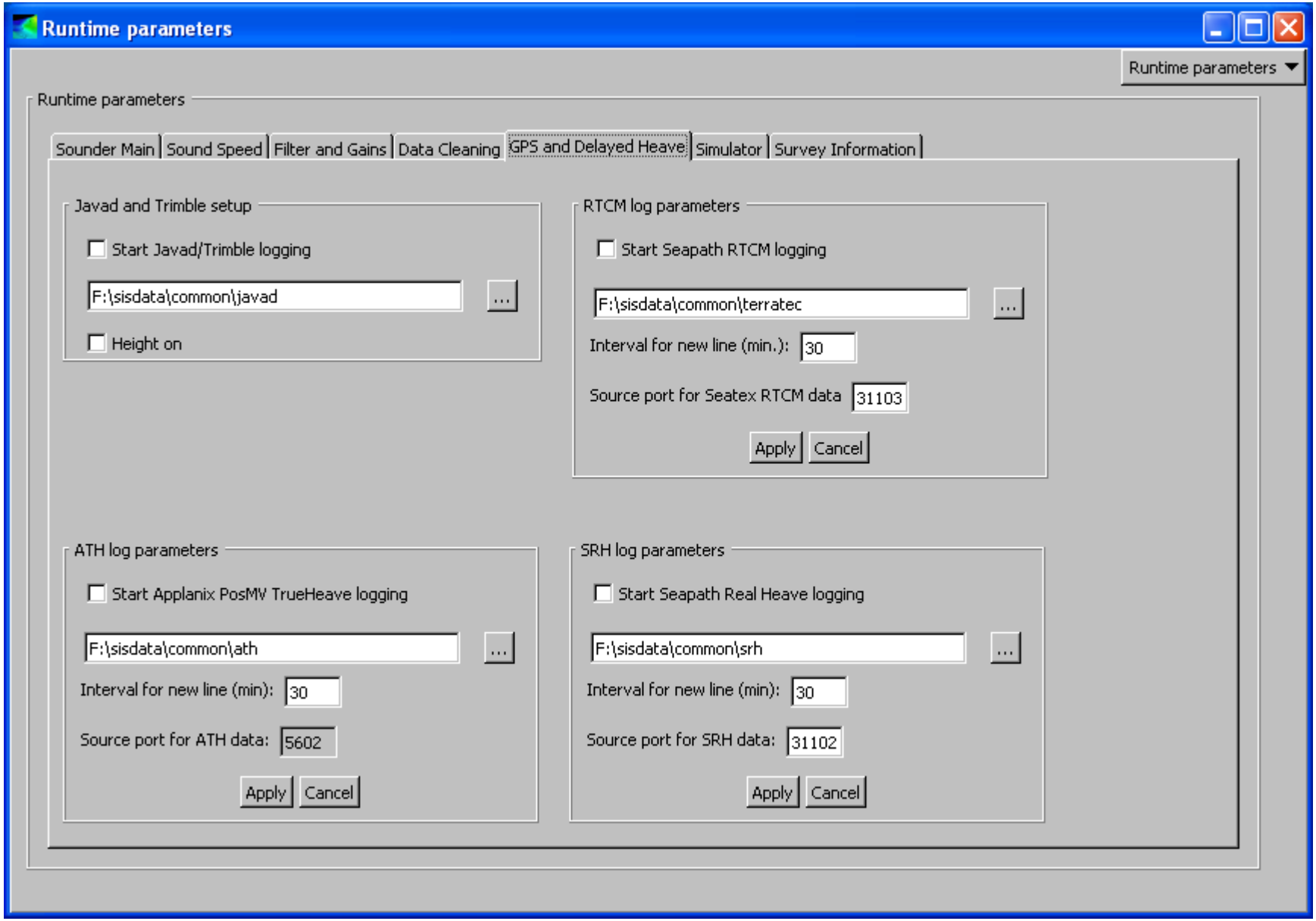

SIS
File View Tools
Help
peter
None
Rescan
EM122_118
Logging
Pinging
Line cnt.
rollcal_21jun2011
Beam intensity
Intensity
Quality
Cross track
Depth (Z)
3093
Waterfall
Time series
Active Heave
Active Pitch Roll
08:58:42
08:59:42
D S 3D I
1:353000 (42.36N,-125.26E)
Geographical
W125°30.0'
W125°15.0'
W125°0.0'
N42°30.0'
N42°20.0'
N42°10.0'
2988.59
Depth (Z Minimum)
3158.51
Numerical display
N 42.22903 North DD
W 125.38489 East DD.
8.30 Heading
0.20 Pitch
1.76 Roll
0.26 Heave
10.84 Speed kn
2011 6 21 ZDA Date
08:59:42 ZDA Time
On PPS
570 PU - ZDA
610 PU - POS
3092.51 Depth
DEEP Mode
HIDENS EQDIST Beam sp.
432/432 Beams
65/65 Coverage
6398/6470 Port/Stb.
1492.20 SV Profile
1496.30 SV Used
1496.3 SV sensor
13.2 Temp. pr
-0.16 AttVel do
5.65 AttVel for
0.33 AttVel sta
0.07 Ping Hz
0.49 Yaw stab
0.00 TX pow.
MIX TX pulse
10.0 TX pulse
Dyn. Dual swat
13.2 Temp. pr
11 PU load
9 No. sat.
3096.00 TWG RN
Satellites
Water Column
Port
Stbd
NOT LOGGING
3429.3
-13277
12818
-50
0
Ready.
Mode: DEEP
Depth: 3092.51
Across: 12869.29
Soundspeed: 1492.20

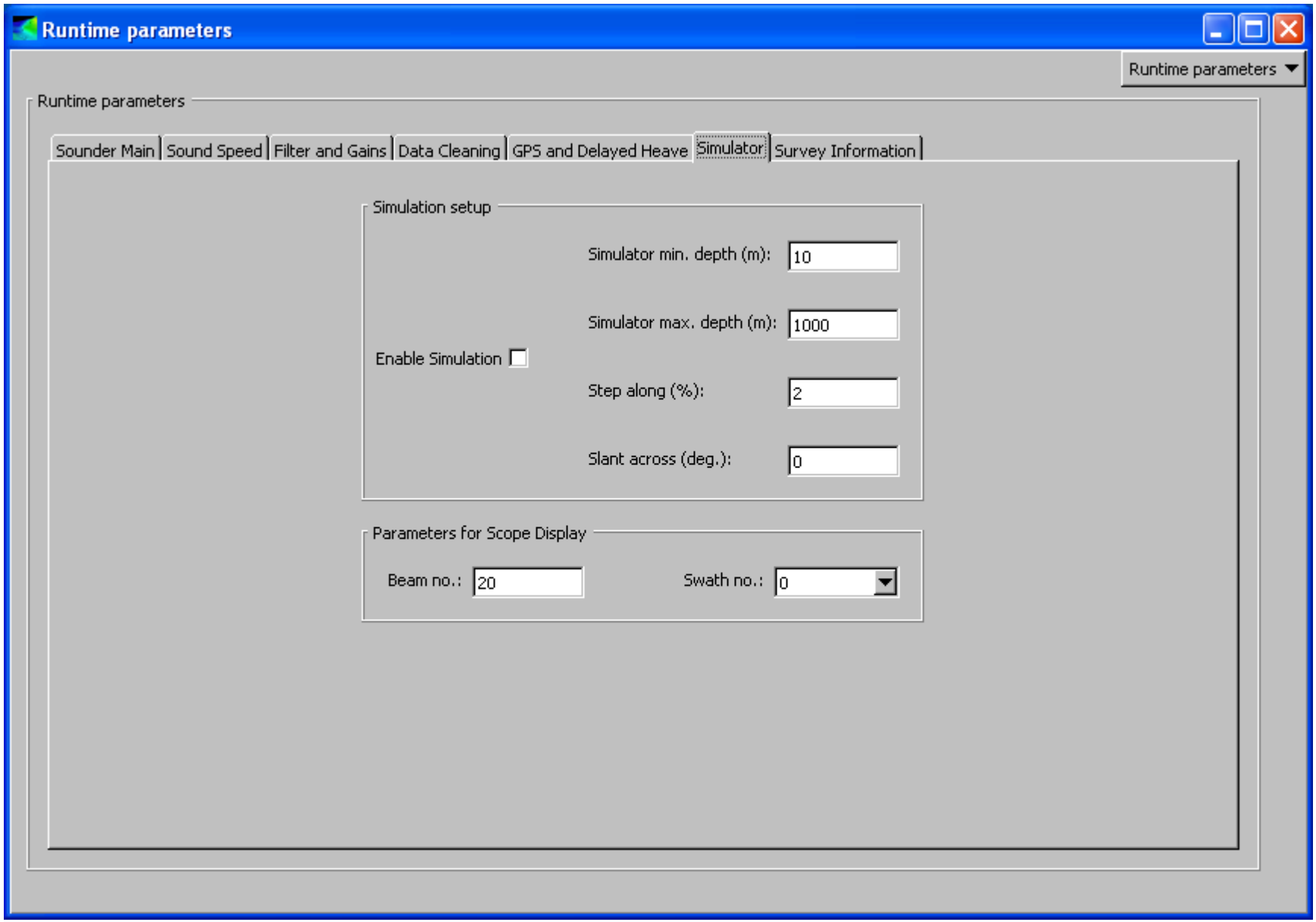

Runtime parameters
Runtime parameters
Runtime parameters
Runtime parameters
Sounder Main
Sound Speed
Filter and Gains
Data Cleaning
GPS and Delayed Heave
Simulator
Survey Information
Sector Coverage
Port
Starboard
Max. angle (deg.):
65
65
Max. Coverage (m):
20000
20000
Angular Coverage mode:
AUTO
Beam Spacing:
HIDENS EQDIST
Depth Settings
Force Depth (m)
3092
Min. Depth (m):
1000
Max. Depth (m):
5000
Dual swath mode:
DYNAMIC
Ping Mode:
AUTO
FM disable
Transmit Control
Pitch stabilization
Along Direction (deg.):
0.0
Auto tilt
OFF
Yaw Stabilization
Mode:
REL. MEAN HEADING
Heading:
0.0
Heading filter:
MEDIUM
External Trigger

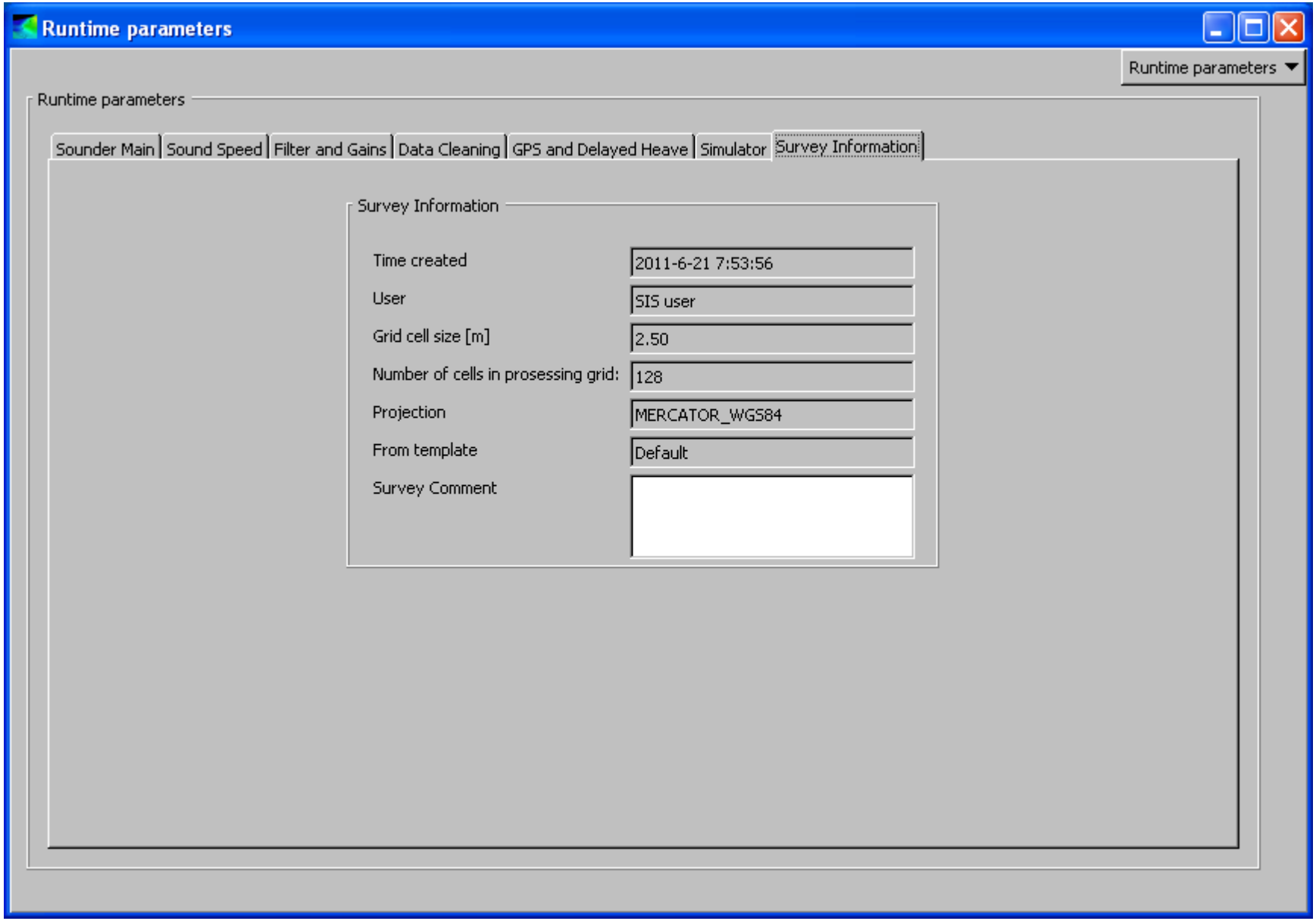

Runtime parameters
Runtime parameters
Runtime parameters
Runtime parameters
Sounder Main
Sound Speed
Filter and Gains
Data Cleaning
GPS and Delayed Heave
Simulator
Survey Information
Sound Speed Profile
Use Sound Speed Profile
sv_20110621_ctd.asvp
...
Abs. coeff. files, salinity
F:\sisdata\common\svp_abscoeff\sv_20110621_ctd_salinity_03500
Abs. coeff. files, CTD
F:\sisdata\common\svp_abscoeff\default
Sound Speed at Transducer
Source
SENSOR
Sound Speed (m/sec.):
1505
Sensor Offset (m/sec.):
0
Filter (sec.):
1

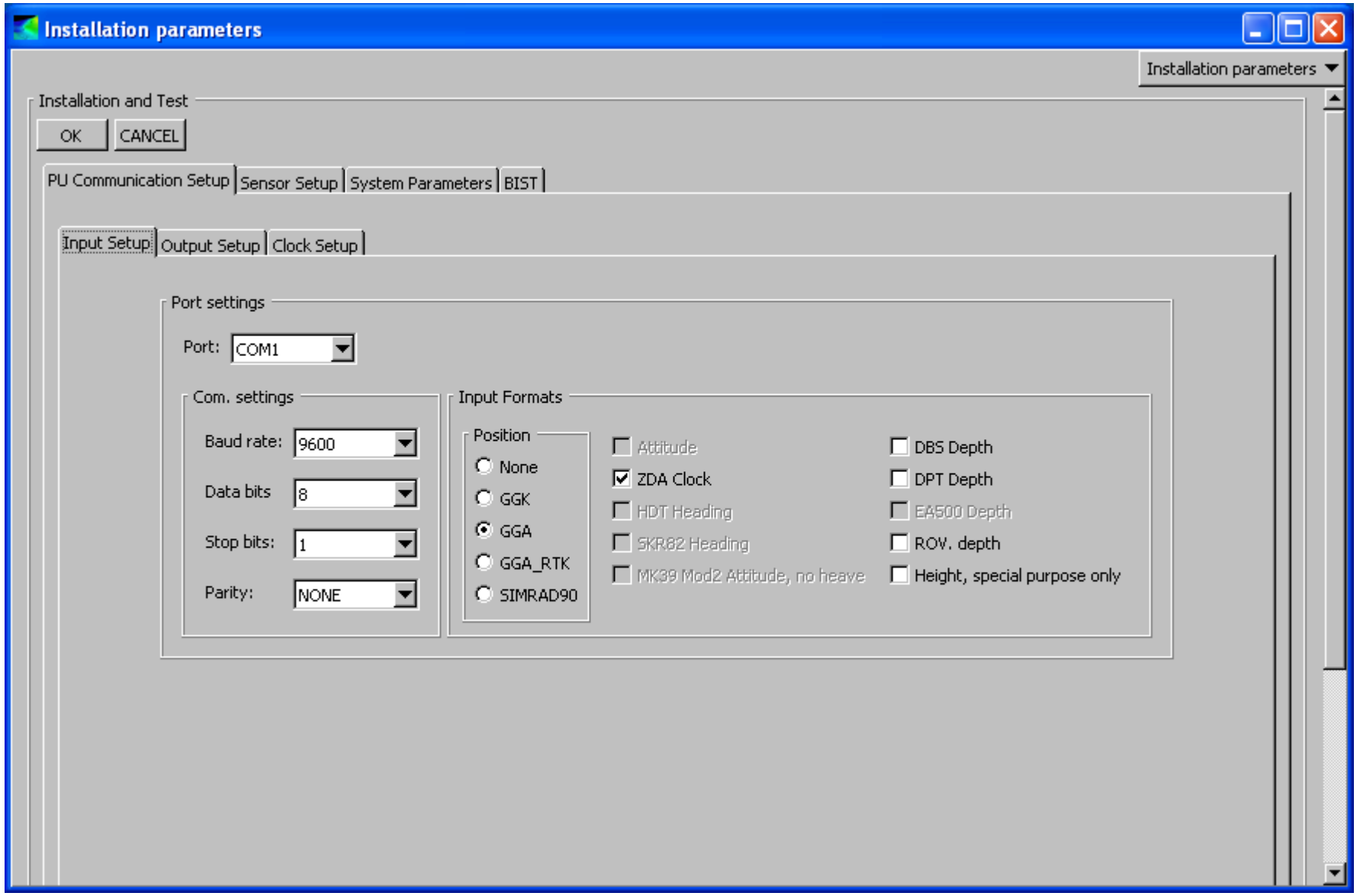

Runtime parameters
Runtime parameters
Runtime parameters
Sounder Main
Sound Speed
Filter and Gains
Data Cleaning
GPS and Delayed Heave
Simulator
Survey Information
Filtering
Spike Filter Strength:
MEDIUM
Range Gate:
NORMAL
Phase ramp:
NORMAL
Penetration Filter Strength:
OFF
Slope
Aeration
Sector Tracking
Interference
Normal incidence sector
Angle from nadir (deg.):
6
Absorption Coefficient
Source:
Salinity
Salinity (parts per thousand):
35
12.0 kHz:
1.286
Mammal protection
TX power level (dB):
Max.
Soft startup ramp time (min.):
0

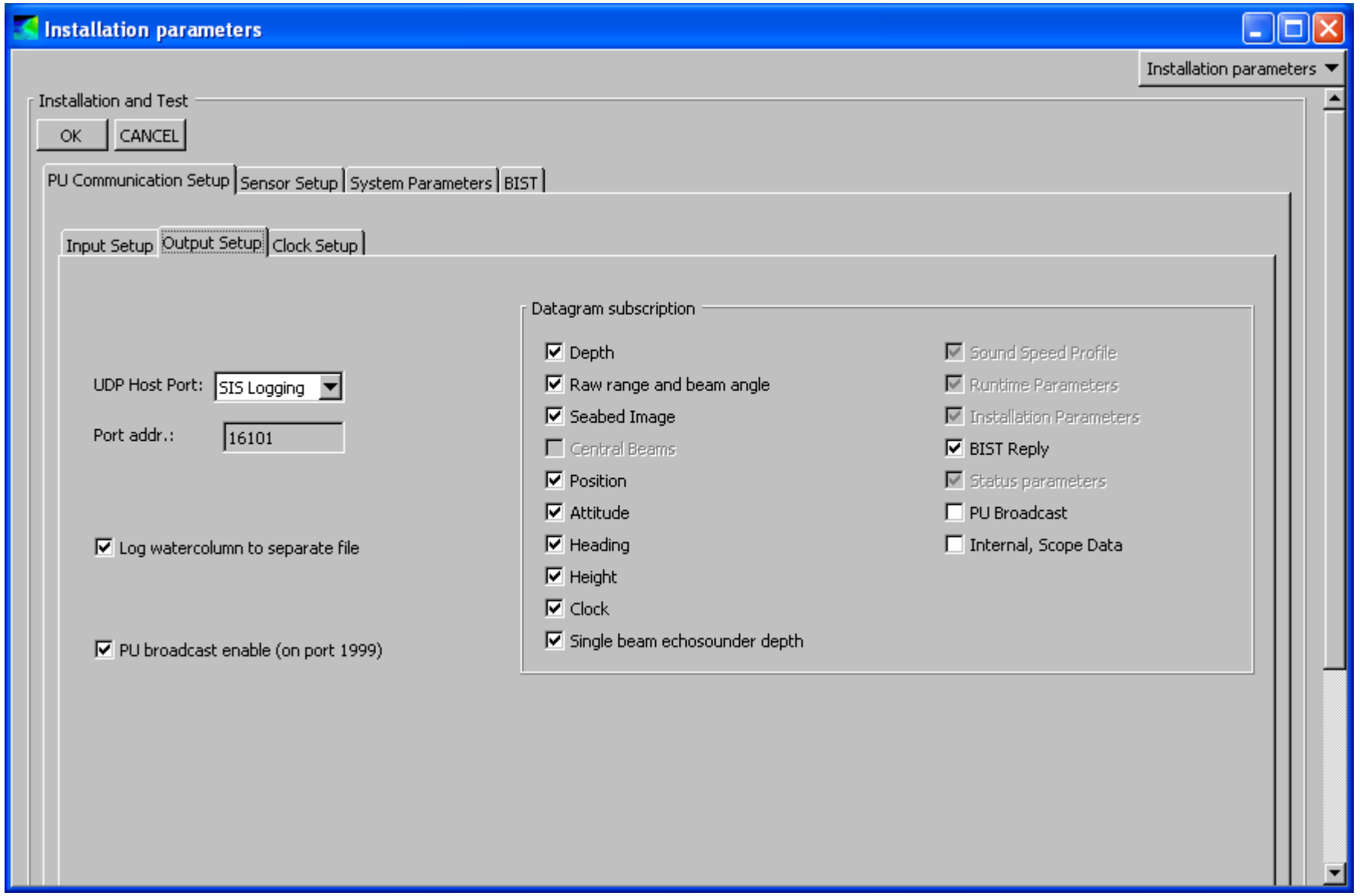

Runtime parameters
Runtime parameters
Runtime parameters
Sounder Main
Sound Speed
Filter and Gains
Data Cleaning
GPS and Delayed Heave
Simulator
Survey Information
Real Time Data Cleaning
None
High
Rule set:
AUTOMATIC1
Advanced...

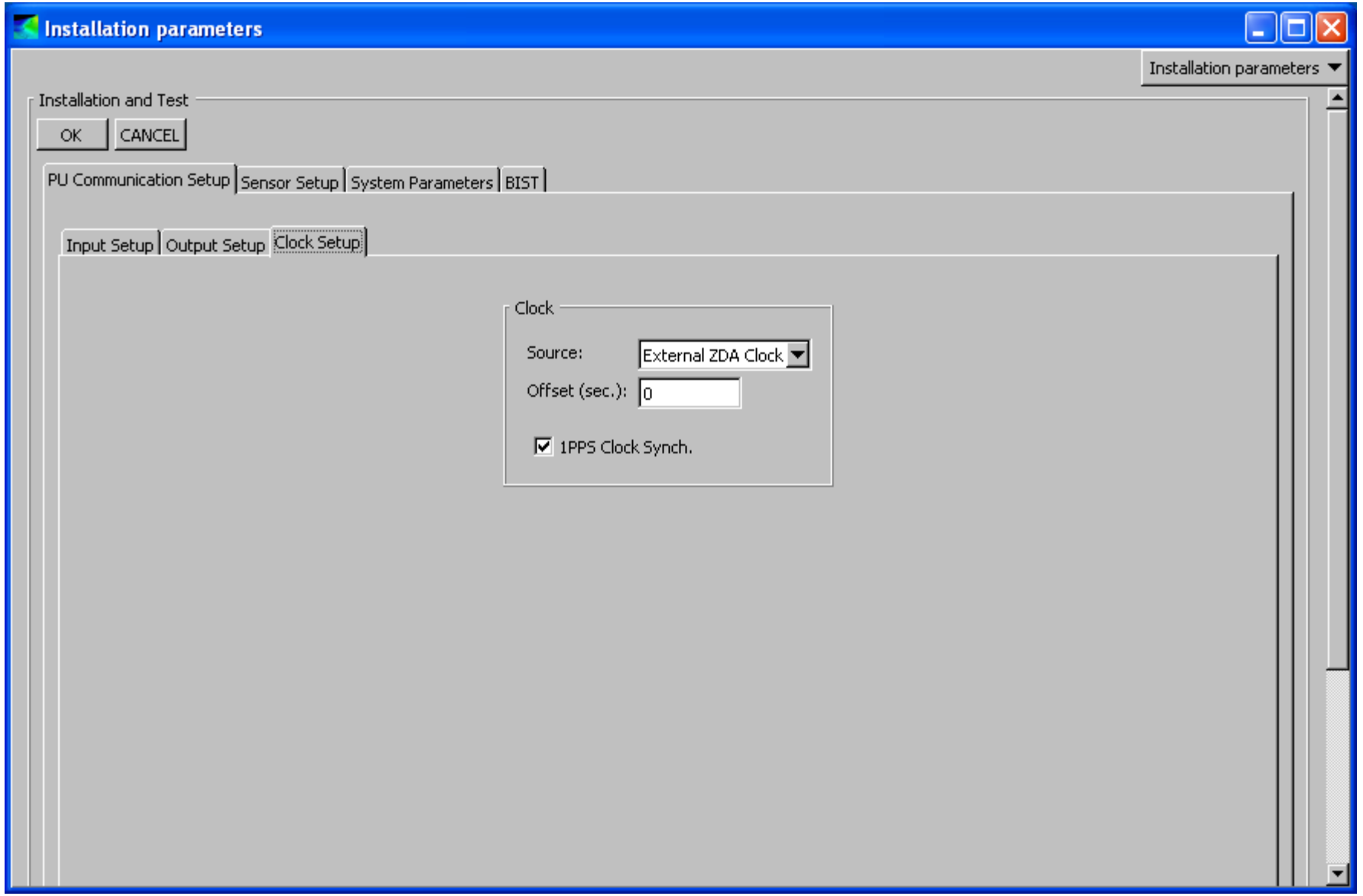

Runtime parameters
Runtime parameters
Runtime parameters
Sounder Main
Sound Speed
Filter and Gains
Data Cleaning
GPS and Delayed Heave
Simulator
Survey Information
Javad and Trimble setup
Start Javad/Trimble logging
F:\sisdata\common\javad
...
Height on
RTCM log parameters
Start Seapath RTCM logging
F:\sisdata\common\terratec
...
Interval for new line (min.):
30
Source port for Seatex RTCM data
31103
Apply
Cancel
ATH log parameters
Start Applanix PosMV TrueHeave logging
F:\sisdata\common\ath
...
Interval for new line (min):
30
Source port for ATH data:
5602
Apply
Cancel
SRH log parameters
Start Seapath Real Heave logging
F:\sisdata\common\srh
...
Interval for new line (min):
30
Source port for SRH data:
31102
Apply
Cancel

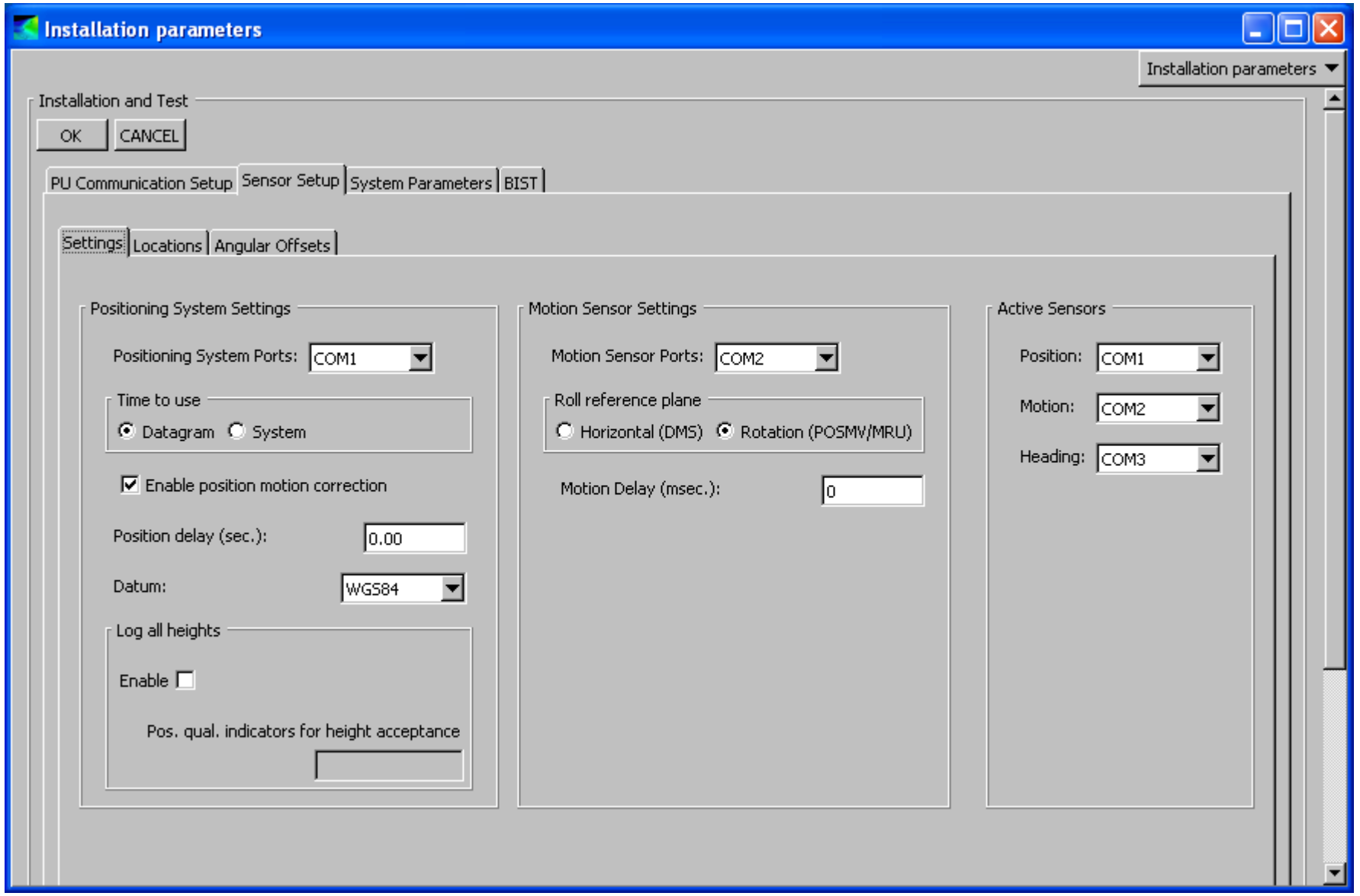

Runtime parameters
Runtime parameters
Runtime parameters
Sounder Main
Sound Speed
Filter and Gains
Data Cleaning
GPS and Delayed Heave
Simulator
Survey Information
Simulation setup
Simulator min. depth (m):
10
Simulator max. depth (m):
1000
Enable Simulation
Step along (%):
2
Slant across (deg.):
0
Parameters for Scope Display
Beam no.:
20
Swath no.:
0

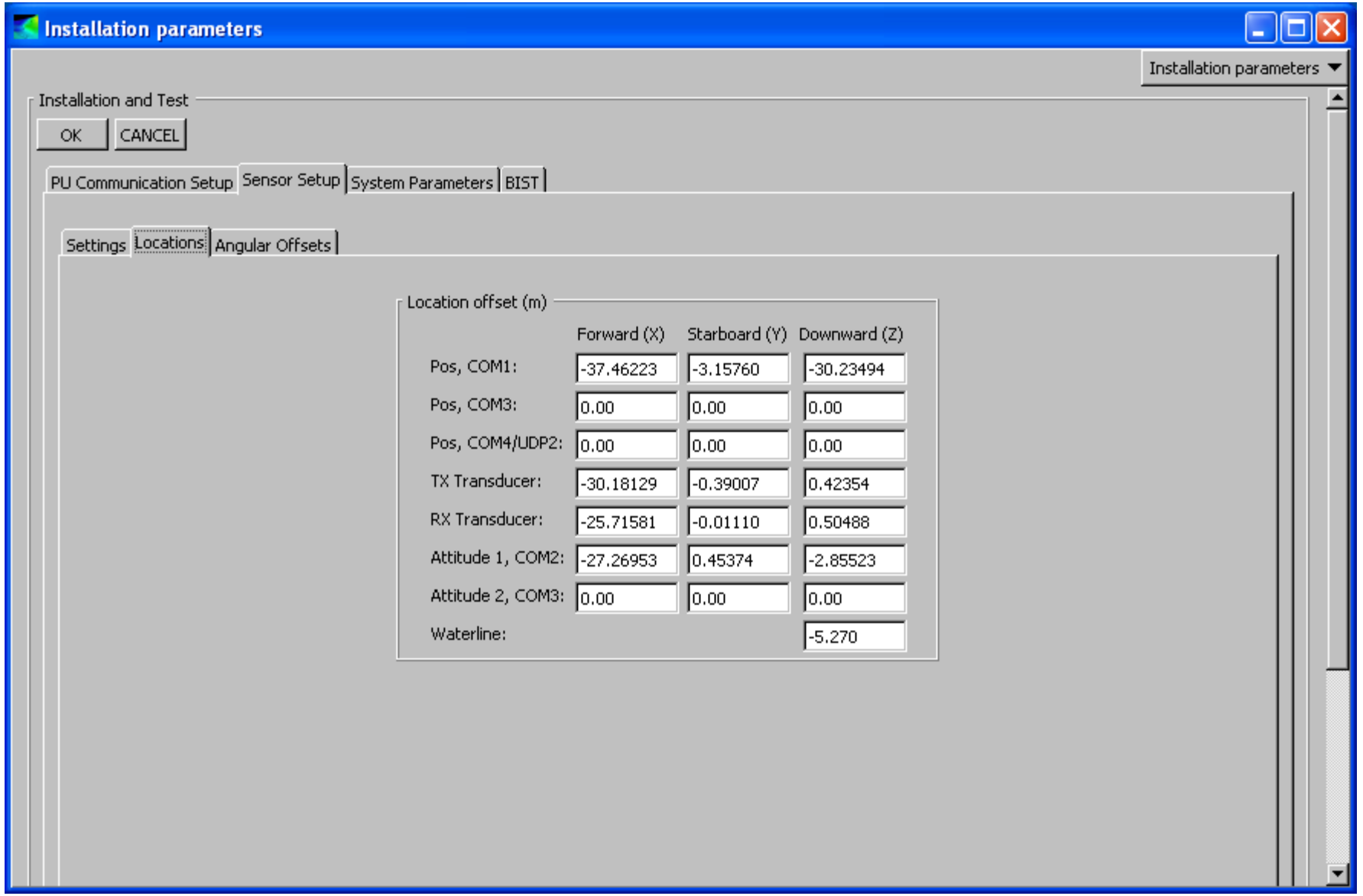

Runtime parameters
Runtime parameters
Runtime parameters
Sounder Main
Sound Speed
Filter and Gains
Data Cleaning
GPS and Delayed Heave
Simulator
Survey Information
Survey Information
Time created
2011-6-21 7:53:56
User
SIS user
Grid cell size [m]
2.50
Number of cells in prosessing grid:
128
Projection
MERCATOR_WGS84
From template
Default
Survey Comment

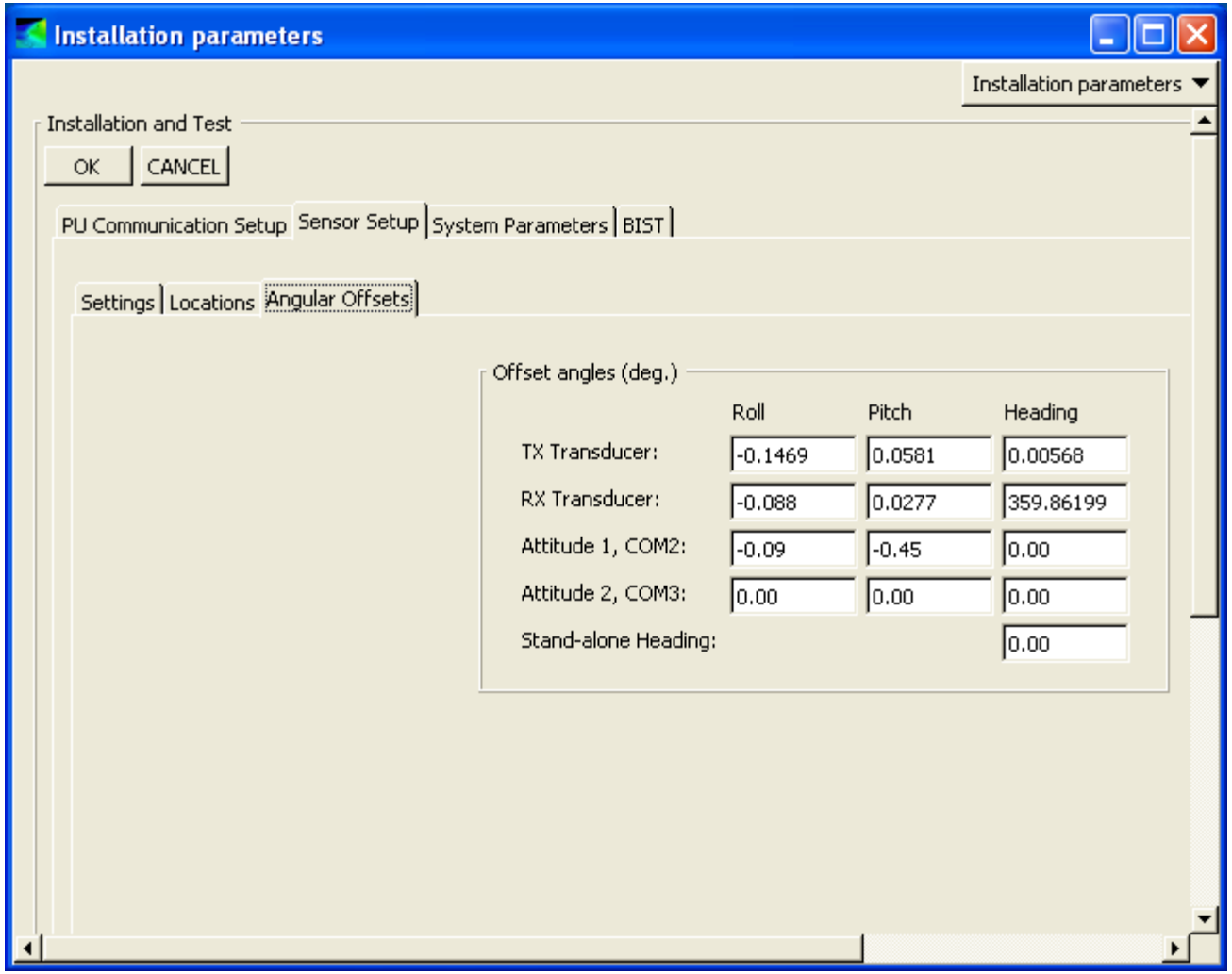

Installation parameters
Installation parameters
Installation and Test
OK
CANCEL
PU Communication Setup
Sensor Setup
System Parameters
BIST
Input Setup
Output Setup
Clock Setup
Port settings
Port:
COM1
Com. settings
Baud rate:
9600
Data bits
8
Stop bits:
1
Parity:
NONE
Input Formats
Position
None
GGK
GGA
GGA_RTK
SIMRAD90
Attitude
ZDA Clock
HDT Heading
SKR82 Heading
MK39 Mod2 Attitude, no heave
DBS Depth
DPT Depth
EA500 Depth
ROV. depth
Height, special purpose only

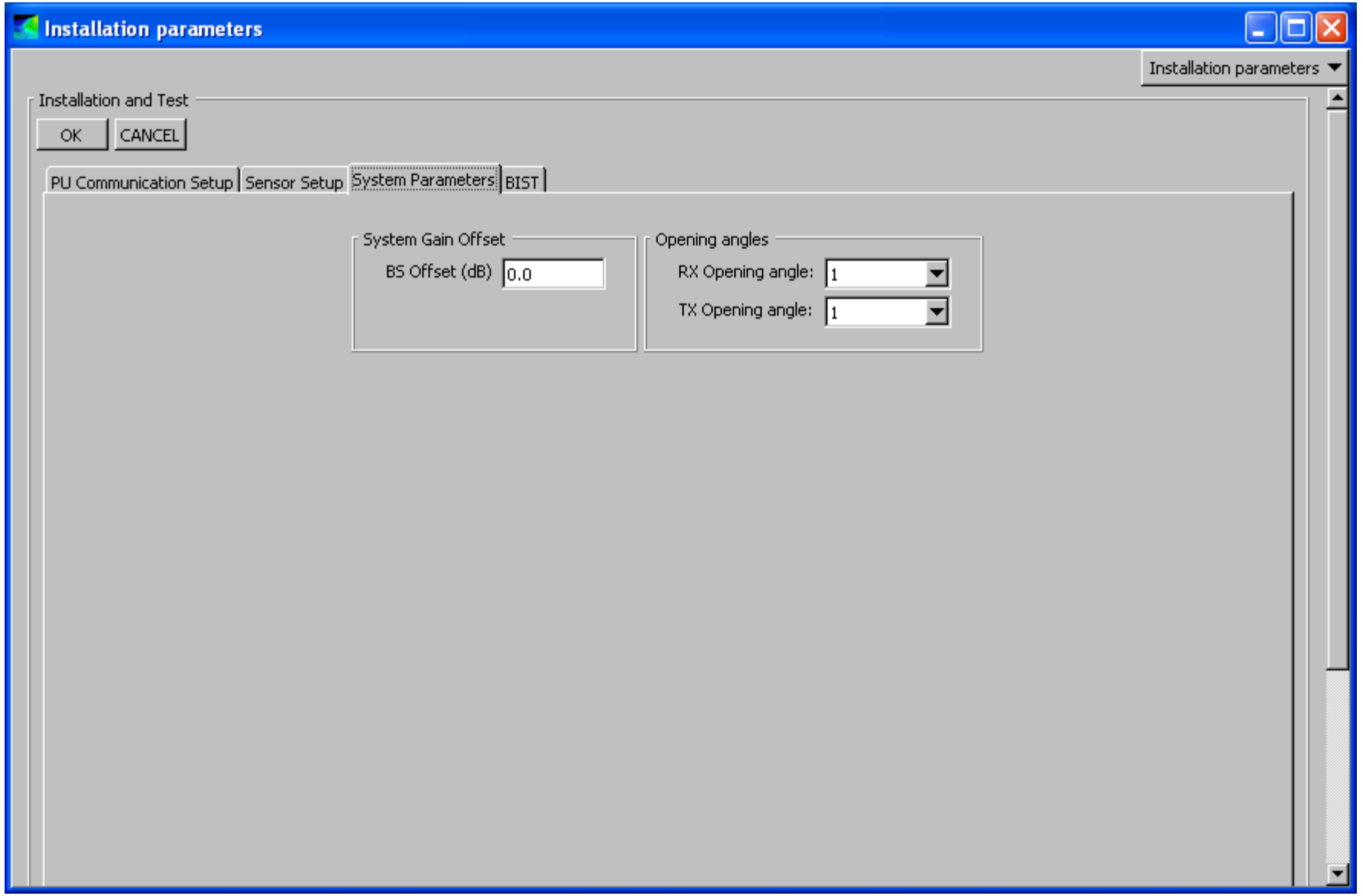

Installation parameters
Installation parameters
Installation and Test
OK
CANCEL
PU Communication Setup
Sensor Setup
System Parameters
BIST
Input Setup
Output Setup
Clock Setup
UDP Host Port:
SIS Logging
Port addr.:
16101
Log watercolumn to separate file
PU broadcast enable (on port 1999)
Datagram subscription
Depth
Raw range and beam angle
Seabed Image
Central Beams
Position
Attitude
Heading
Height
Clock
Single beam echosounder depth
Sound Speed Profile
Runtime Parameters
Installation Parameters
BIST Reply
Status parameters
PU Broadcast
Internal, Scope Data

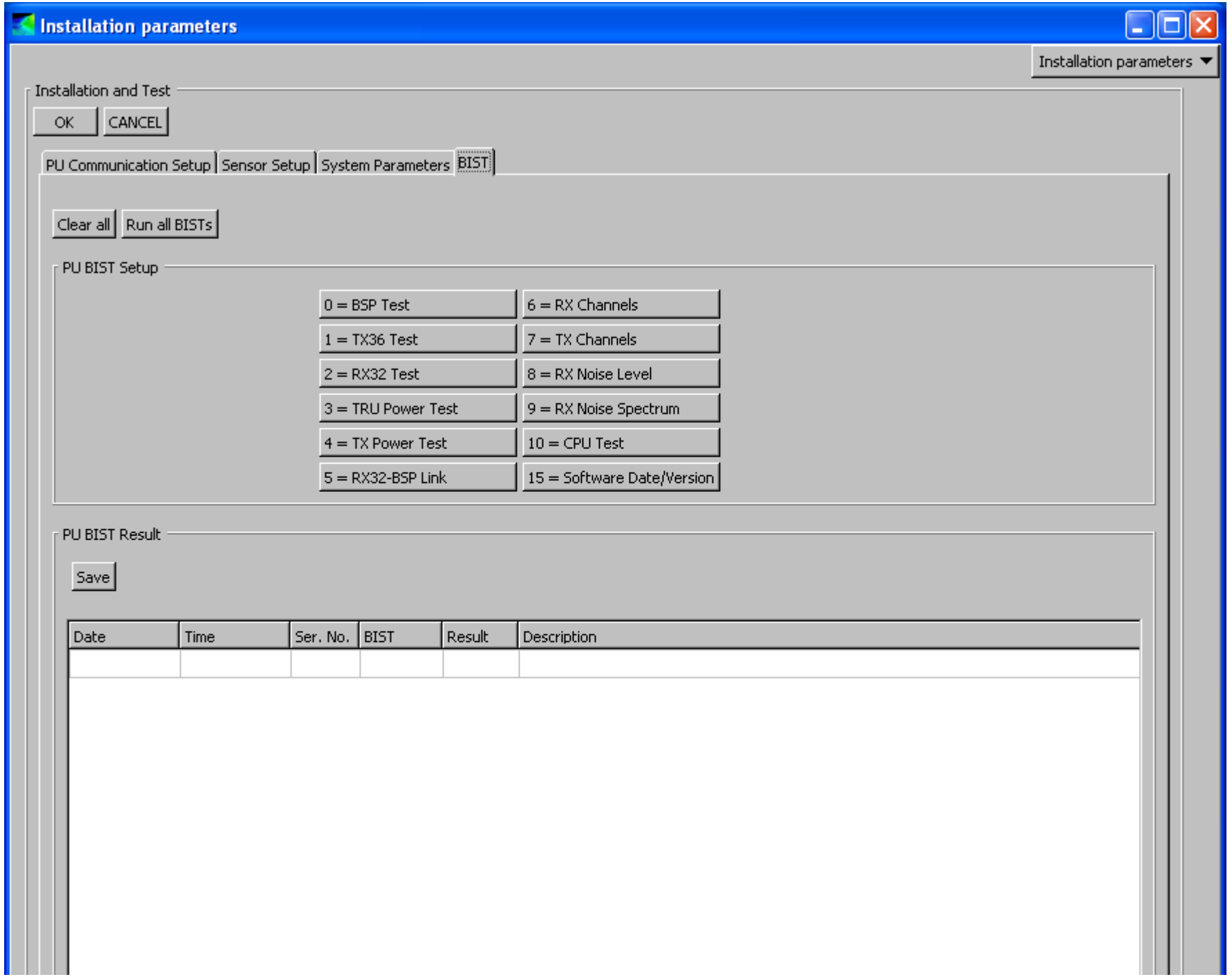

Installation parameters
Installation parameters
Installation and Test
OK
CANCEL
PU Communication Setup
Sensor Setup
System Parameters
BIST
Input Setup
Output Setup
Clock Setup
Clock
Source:
External ZDA Clock
Offset (sec.):
0
1PPS Clock Synch.

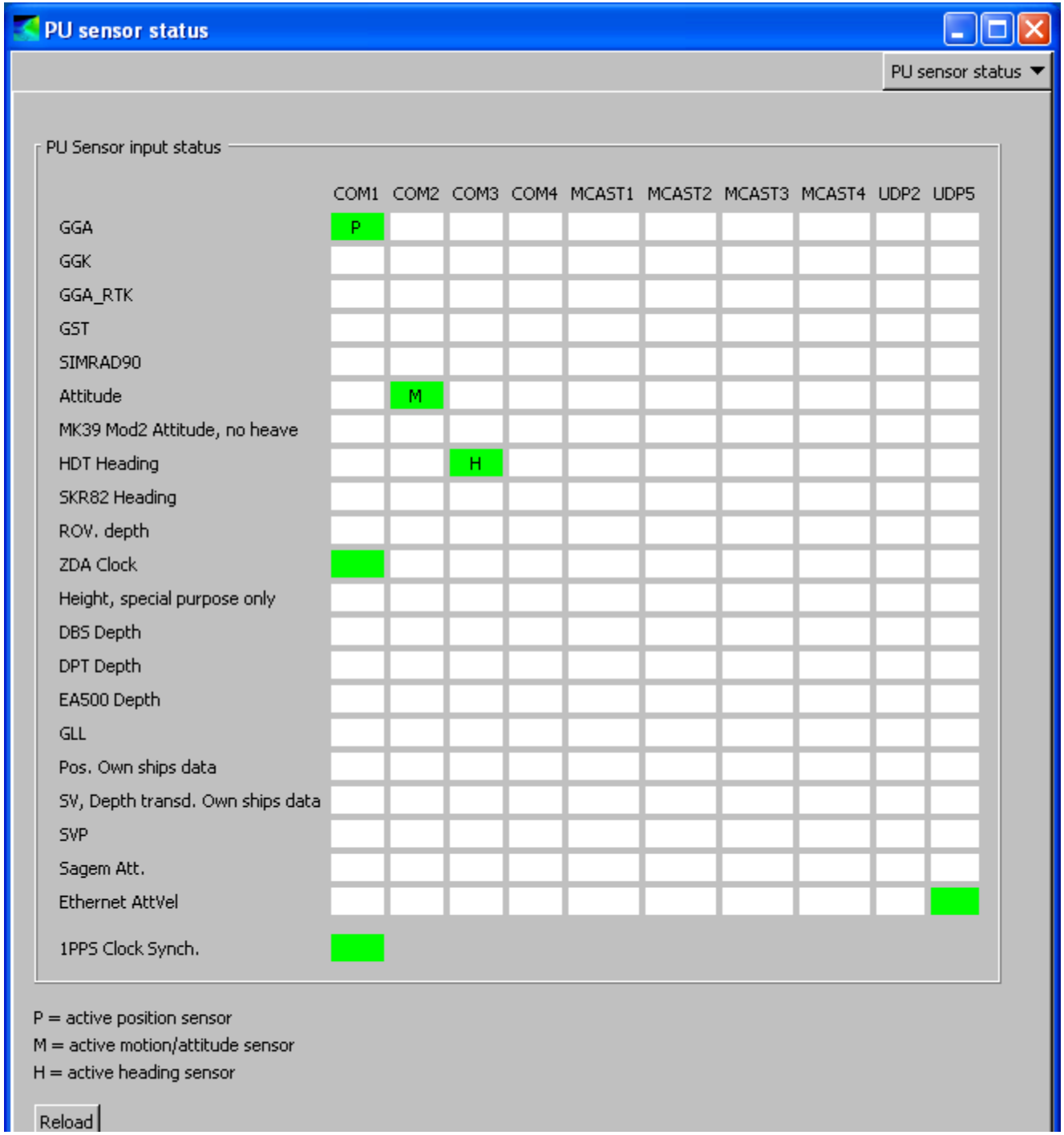

Installation parameters
Installation parameters
Installation and Test
OK
CANCEL
PU Communication Setup
Sensor Setup
System Parameters
BIST
Settings
Locations
Angular Offsets
Positioning System Settings
Positioning System Ports:
COM1
Time to use
Datagram
System
Enable position motion correction
Position delay (sec.):
0.00
Datum:
WGS84
Log all heights
Enable
Pos. qual. indicators for height acceptance
Motion Sensor Settings
Motion Sensor Ports:
COM2
Roll reference plane
Horizontal (DMS)
Rotation (POSMV/MRU)
Motion Delay (msec.):
0
Active Sensors
Position:
COM1
Motion:
COM2
Heading:
COM3

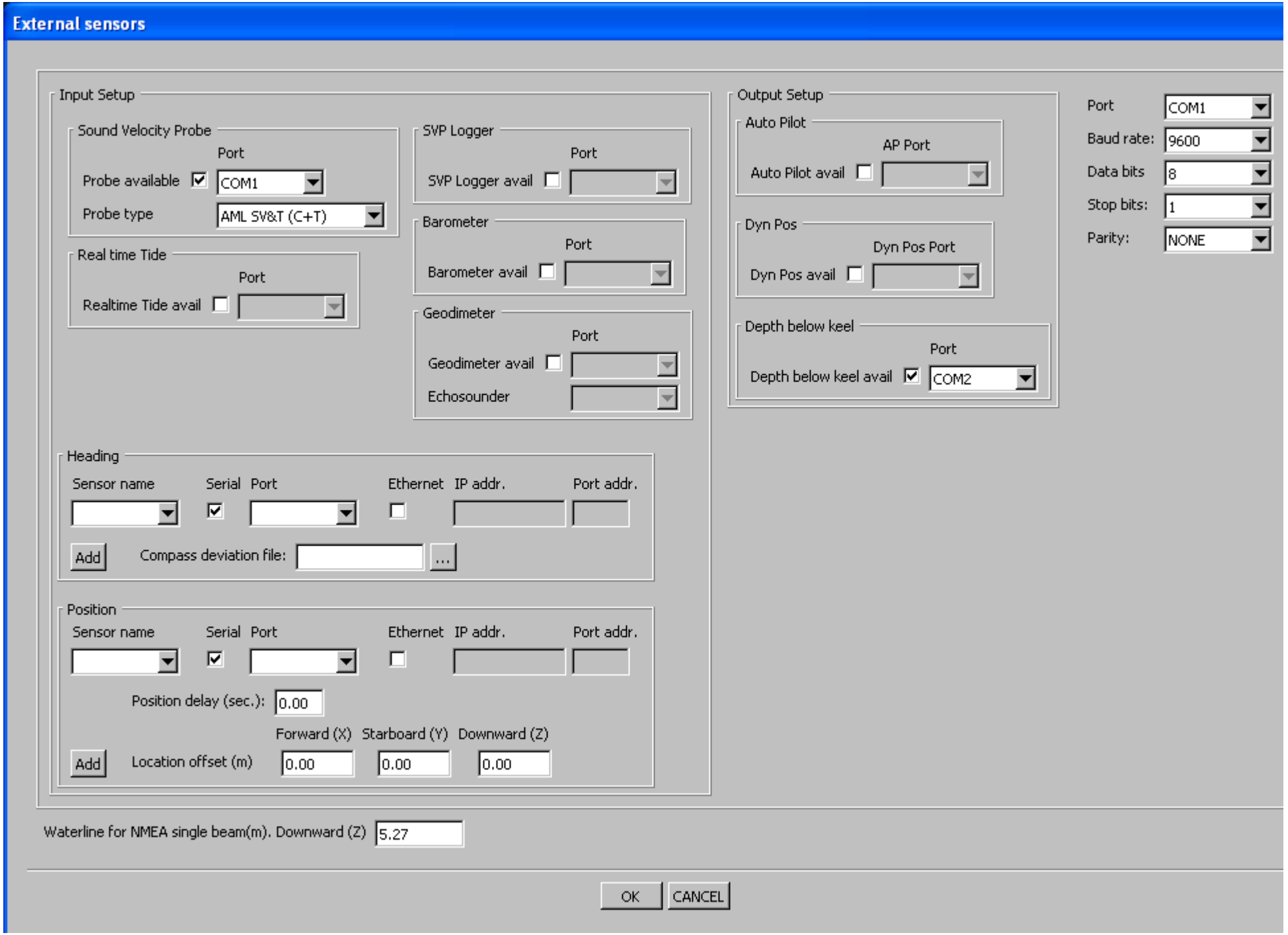

Installation parameters
Installation parameters
Installation and Test
OK
CANCEL
PU Communication Setup
Sensor Setup
System Parameters
BIST
Settings
Locations
Angular Offsets
Location offset (m)
Forward (X)
Starboard (Y)
Downward (Z)
Pos, COM1:
-37.46223
-3.15760
-30.23494
Pos, COM3:
0.00
0.00
0.00
Pos, COM4/UDP2:
0.00
0.00
0.00
TX Transducer:
-30.18129
-0.39007
0.42354
RX Transducer:
-25.71581
-0.01110
0.50488
Attitude 1, COM2:
-27.26953
0.45374
-2.85523
Attitude 2, COM3:
0.00
0.00
0.00
Waterline:
-5.270

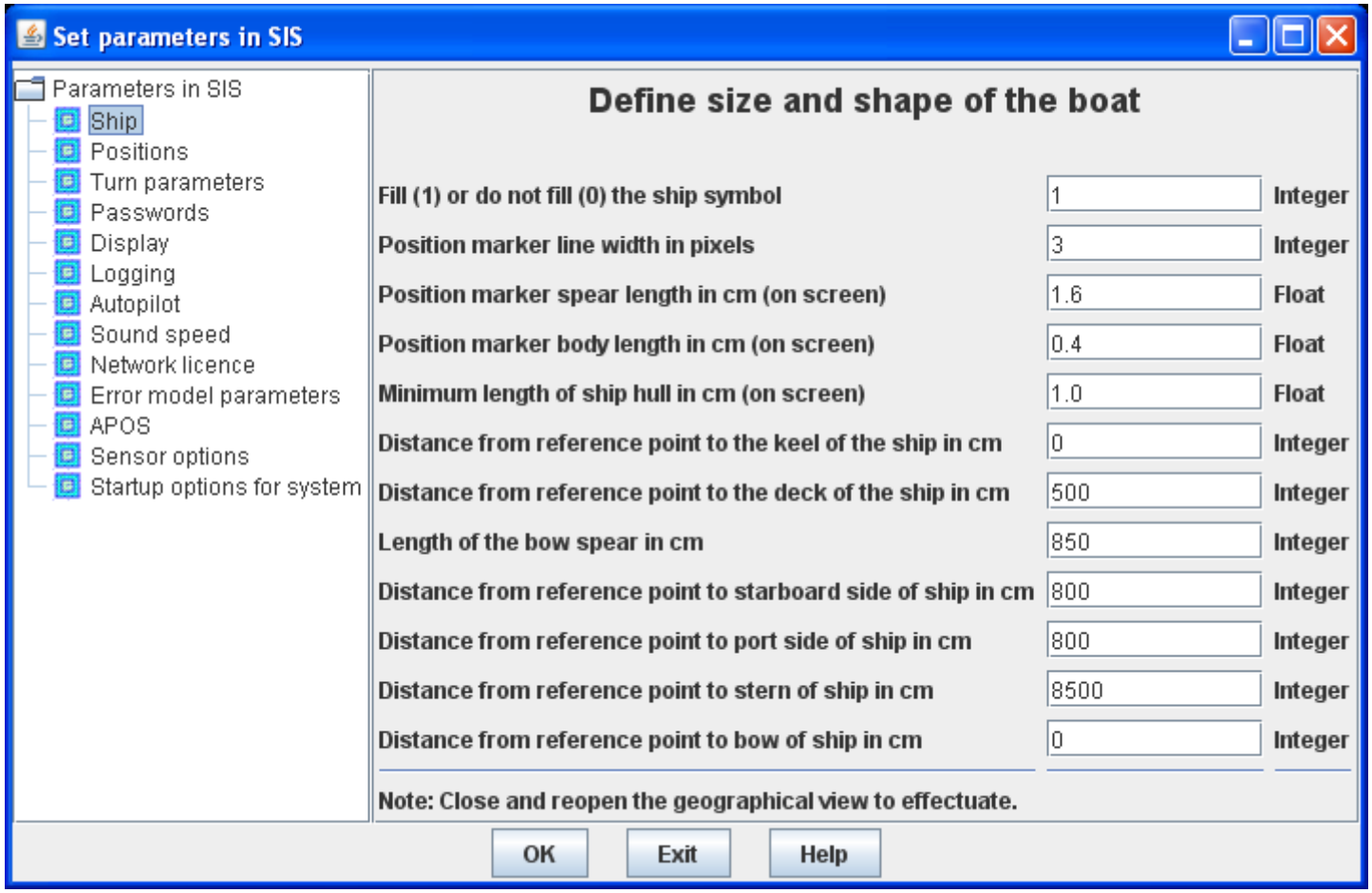

Installation parameters
Installation parameters
Installation and Test
OK
CANCEL
PU Communication Setup
Sensor Setup
System Parameters
BIST
Settings
Locations
Angular Offsets
Offset angles (deg.)
Roll
Pitch
Heading
TX Transducer:
-0.1469
0.0581
0.00568
RX Transducer:
-0.088
0.0277
359.86199
Attitude 1, COM2:
-0.09
-0.45
0.00
Attitude 2, COM3:
0.00
0.00
0.00
Stand-alone Heading:
0.00

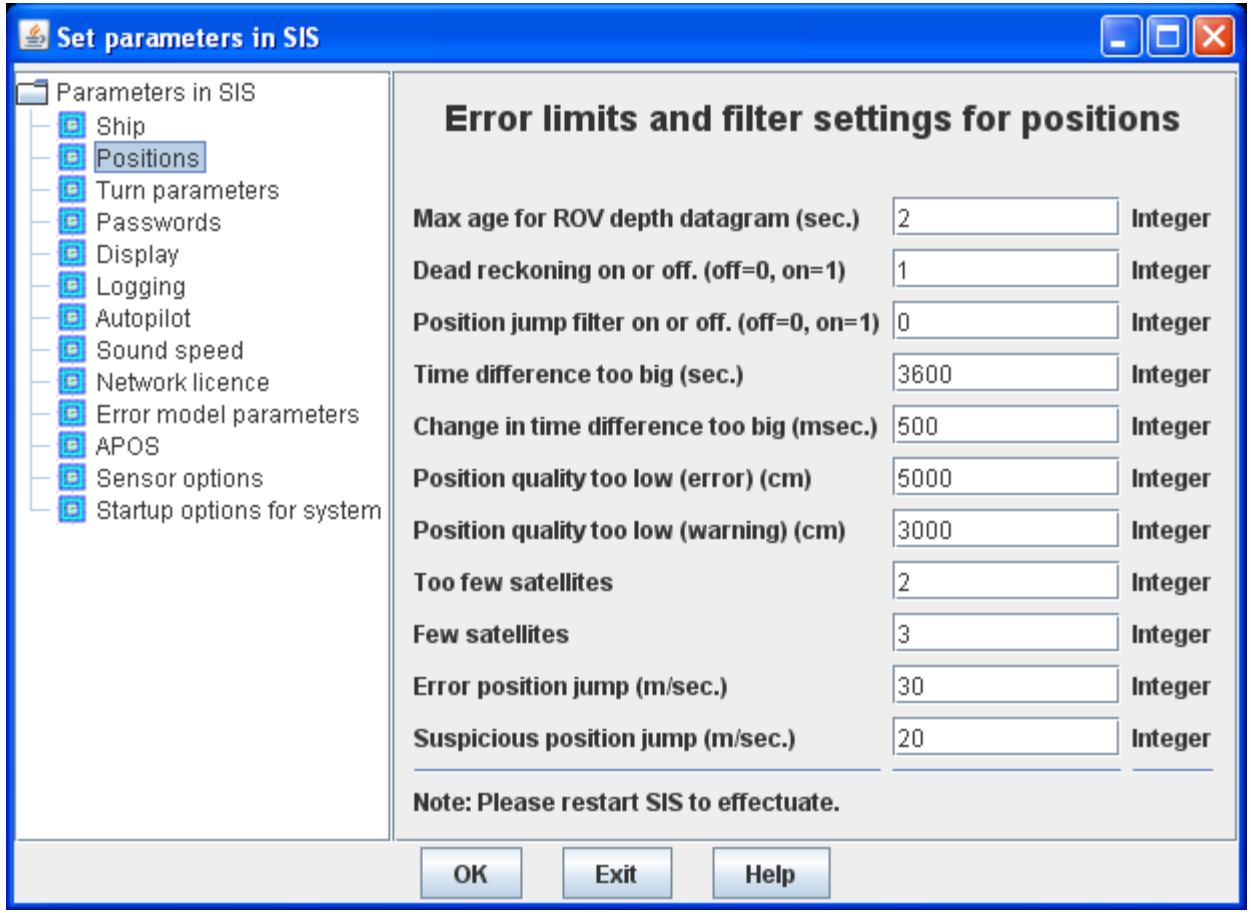

Installation parameters
Installation parameters
Installation and Test
OK
CANCEL
PU Communication Setup
Sensor Setup
System Parameters
BIST
System Gain Offset
BS Offset (dB)
0.0
Opening angles
RX Opening angle:
1
TX Opening angle:
1

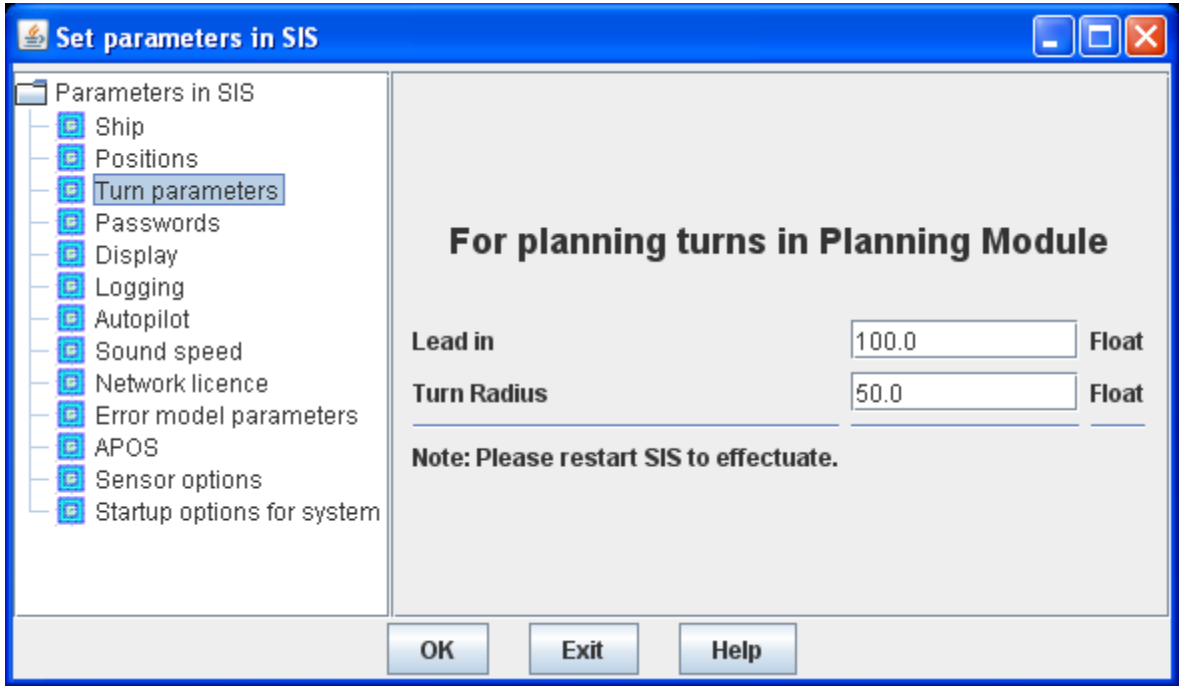

Installation parameters
Installation parameters
Installation and Test
OK
CANCEL
PU Communication Setup
Sensor Setup
System Parameters
BIST
Clear all
Run all BISTs
PU BIST Setup
0 = BSP Test
1 = TX36 Test
2 = RX32 Test
3 = TRU Power Test
4 = TX Power Test
5 = RX32-BSP Link
6 = RX Channels
7 = TX Channels
8 = RX Noise Level
9 = RX Noise Spectrum
10 = CPU Test
15 = Software Date/Version
PU BIST Result
Save
Date
Time
Ser. No.
BIST
Result
Description

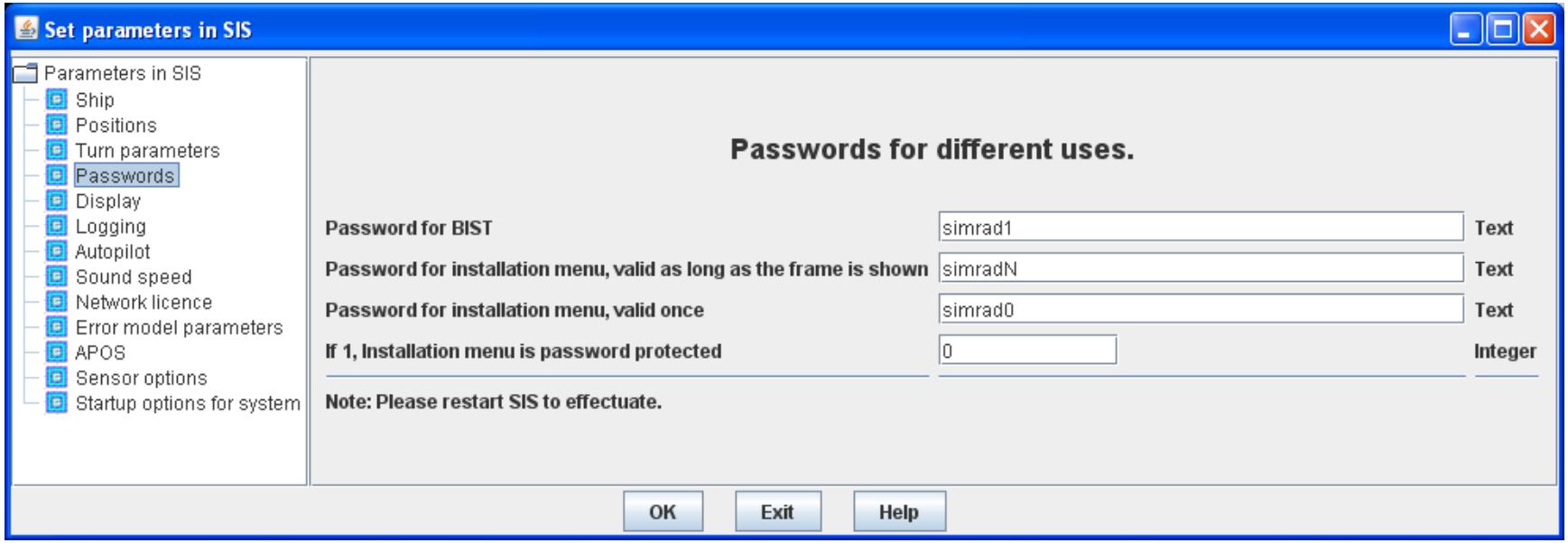

PU sensor status
PU sensor status
PU Sensor input status
COM1 COM2 COM3 COM4 MCAST1 MCAST2 MCAST3 MCAST4 UDP2 UDP5
GGA
GGK
GGA_RTK
GST
SIMRAD90
Attitude
MK39 Mod2 Attitude, no heave
HDT Heading
SKR82 Heading
ROV. depth
ZDA Clock
Height, special purpose only
DBS Depth
DPT Depth
EA500 Depth
GLL
Pos. Own ships data
SV, Depth transd. Own ships data
SVP
Sagem Att.
Ethernet AttVel
1PPS Clock Synch.
P
M
H
P = active position sensor
M = active motion/attitude sensor
H = active heading sensor
Reload

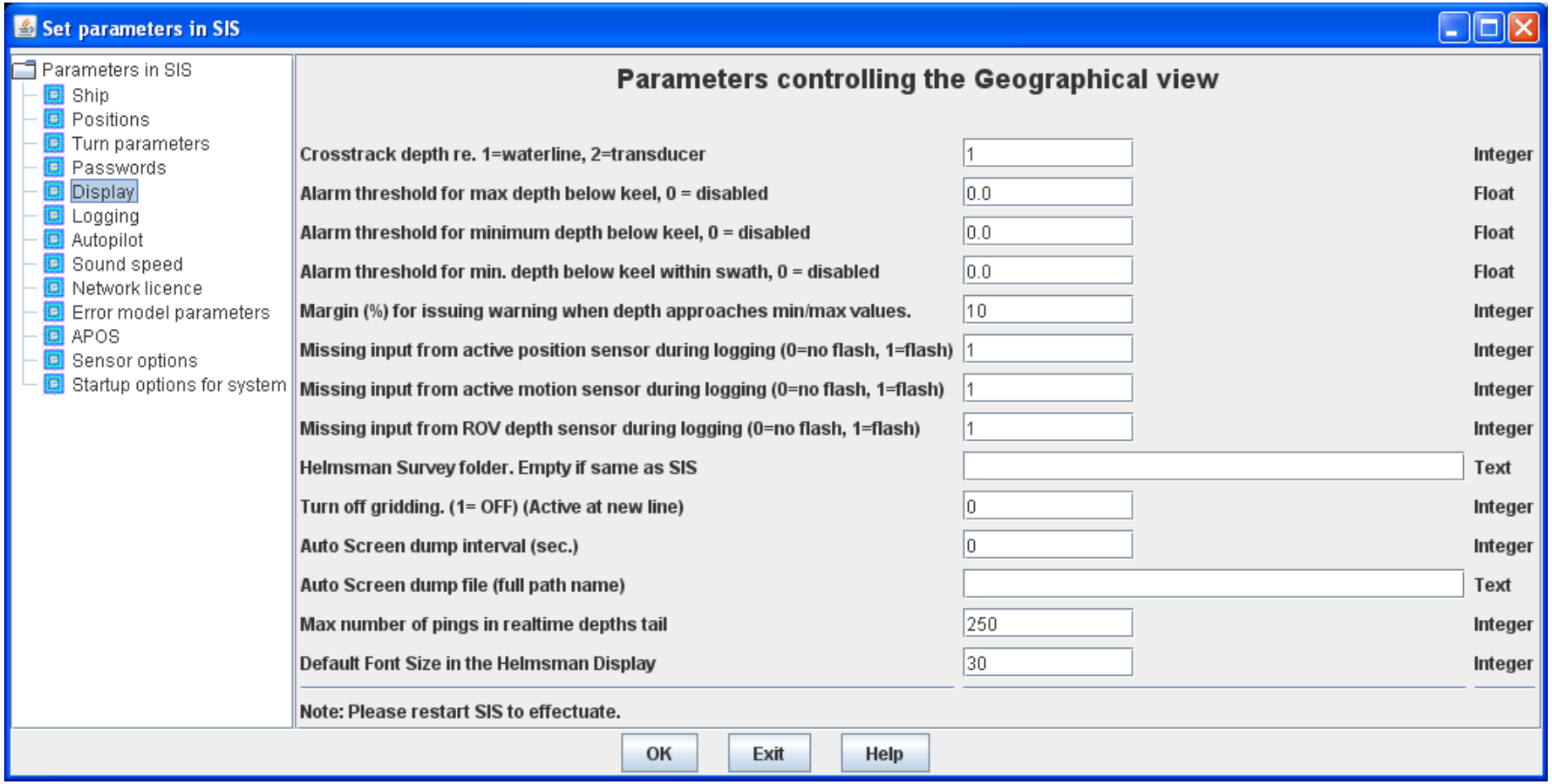

External sensors
Input Setup
Sound Velocity Probe
Port
Probe available
COM1
Probe type
AML SV&T (C+T)
Real time Tide
Port
Realtime Tide avail
SVP Logger
Port
SVP Logger avail
Barometer
Port
Barometer avail
Geodimeter
Port
Geodimeter avail
Echosounder
Heading
Sensor name
Serial
Port
Ethernet
IP addr.
Port addr.
Add
Compass deviation file:
...
Position
Sensor name
Serial
Port
Ethernet
IP addr.
Port addr.
Position delay (sec.):
0.00
Forward (X)
Starboard (Y)
Downward (Z)
Add
Location offset (m)
0.00
0.00
0.00
Output Setup
Auto Pilot
AP Port
Auto Pilot avail
Dyn Pos
Dyn Pos Port
Dyn Pos avail
Depth below keel
Port
Depth below keel avail
COM2
Port
COM1
Baud rate:
9600
Data bits
8
Stop bits:
1
Parity:
NONE
Waterline for NMEA single beam(m). Downward (Z)
5.27
OK
CANCEL

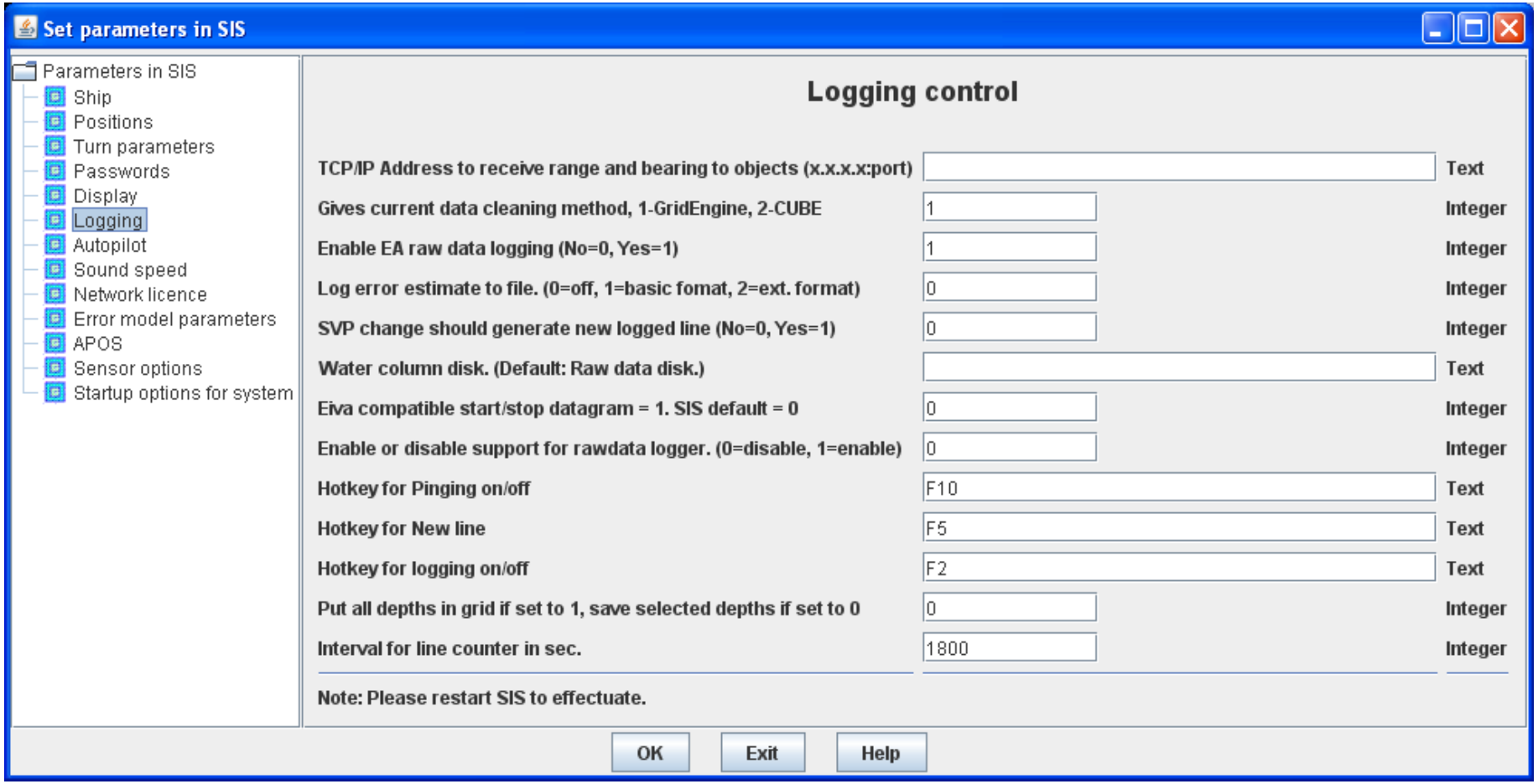

Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Define size and shape of the boat
Fill (1) or do not fill (0) the ship symbol
1
Integer
Position marker line width in pixels
3
Integer
Position marker spear length in cm (on screen)
1.6
Float
Position marker body length in cm (on screen)
0.4
Float
Minimum length of ship hull in cm (on screen)
1.0
Float
Distance from reference point to the keel of the ship in cm
0
Integer
Distance from reference point to the deck of the ship in cm
500
Integer
Length of the bow spear in cm
850
Integer
Distance from reference point to starboard side of ship in cm
800
Integer
Distance from reference point to port side of ship in cm
800
Integer
Distance from reference point to stern of ship in cm
8500
Integer
Distance from reference point to bow of ship in cm
0
Integer
Note: Close and reopen the geographical view to effectuate.
OK
Exit
Help

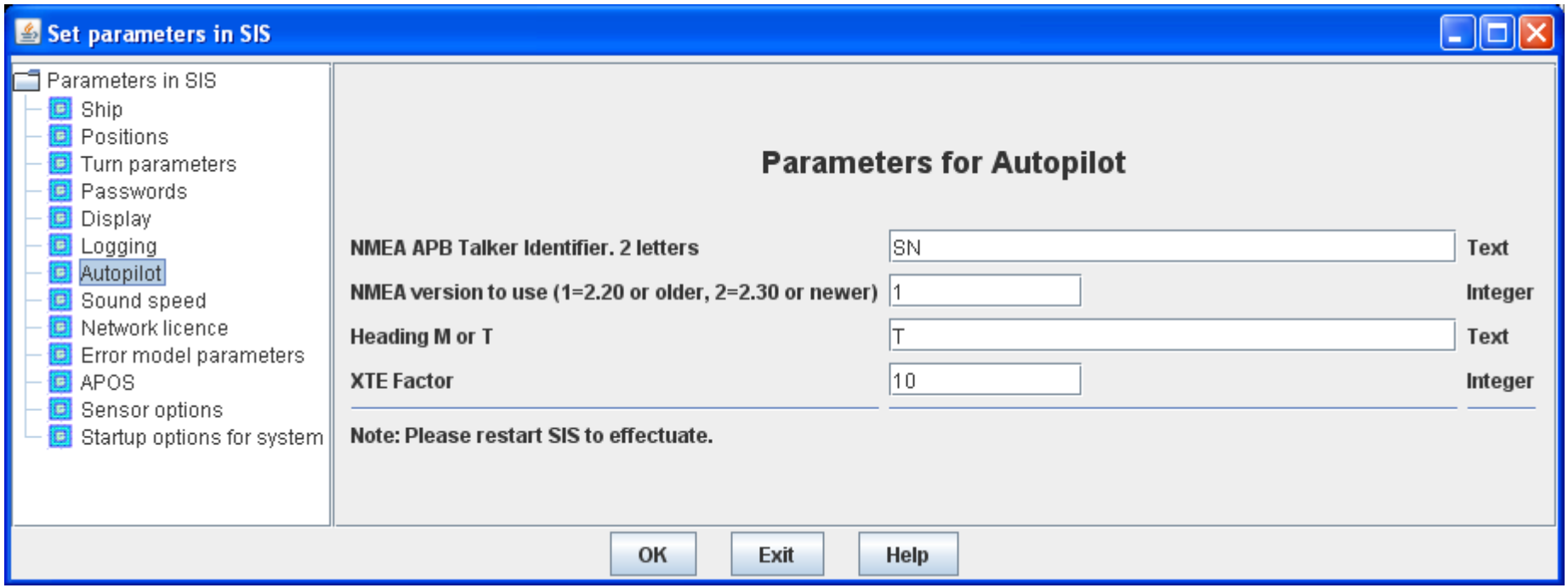

Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Error limits and filter settings for positions
Max age for ROV depth datagram (sec.) 2 Integer
Dead reckoning on or off. (off=0, on=1) 1 Integer
Position jump filter on or off. (off=0, on=1) 0 Integer
Time difference too big (sec.) 3600 Integer
Change in time difference too big (msec.) 500 Integer
Position quality too low (error) (cm) 5000 Integer
Position quality too low (warning) (cm) 3000 Integer
Too few satellites 2 Integer
Few satellites 3 Integer
Error position jump (m/sec.) 30 Integer
Suspicious position jump (m/sec.) 20 Integer
Note: Please restart SIS to effectuate.
OK
Exit
Help

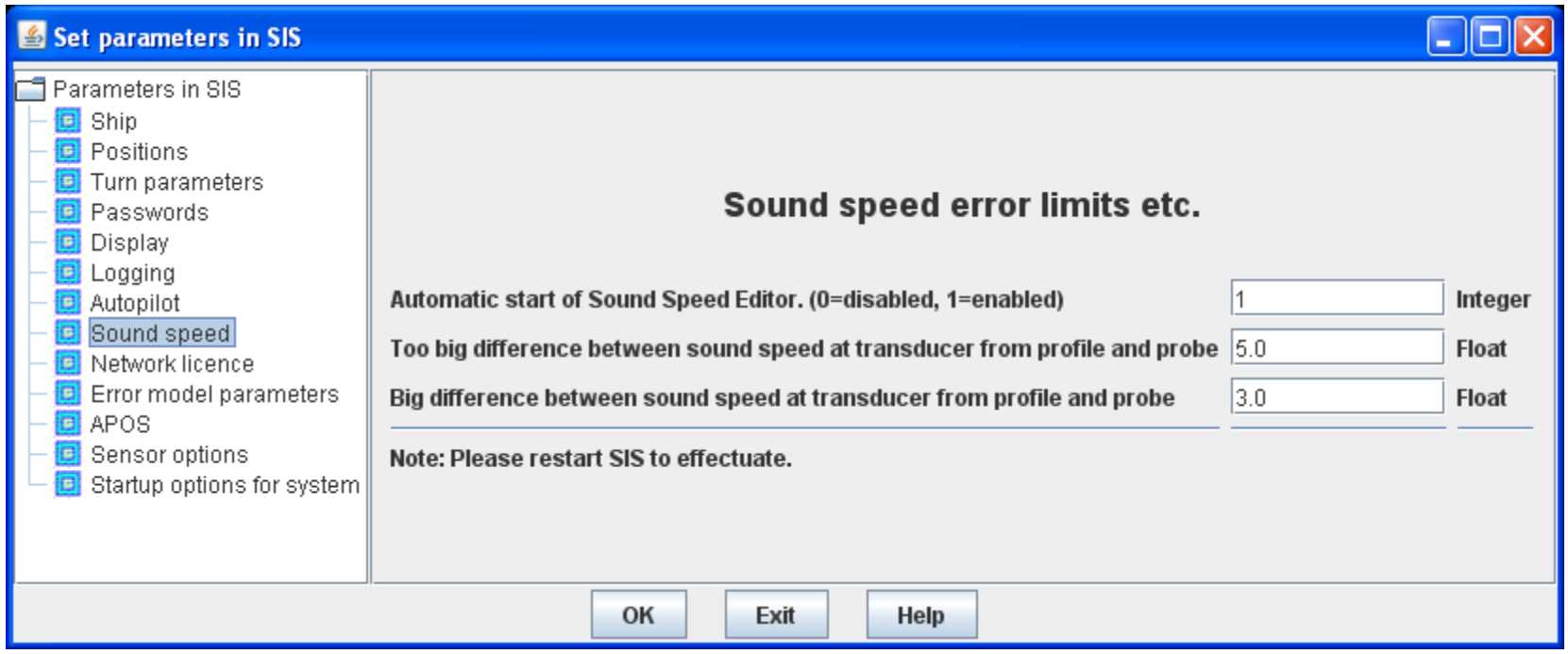

Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
For planning turns in Planning Module
Lead in
100.0
Float
Turn Radius
50.0
Float
Note: Please restart SIS to effectuate.
OK
Exit
Help

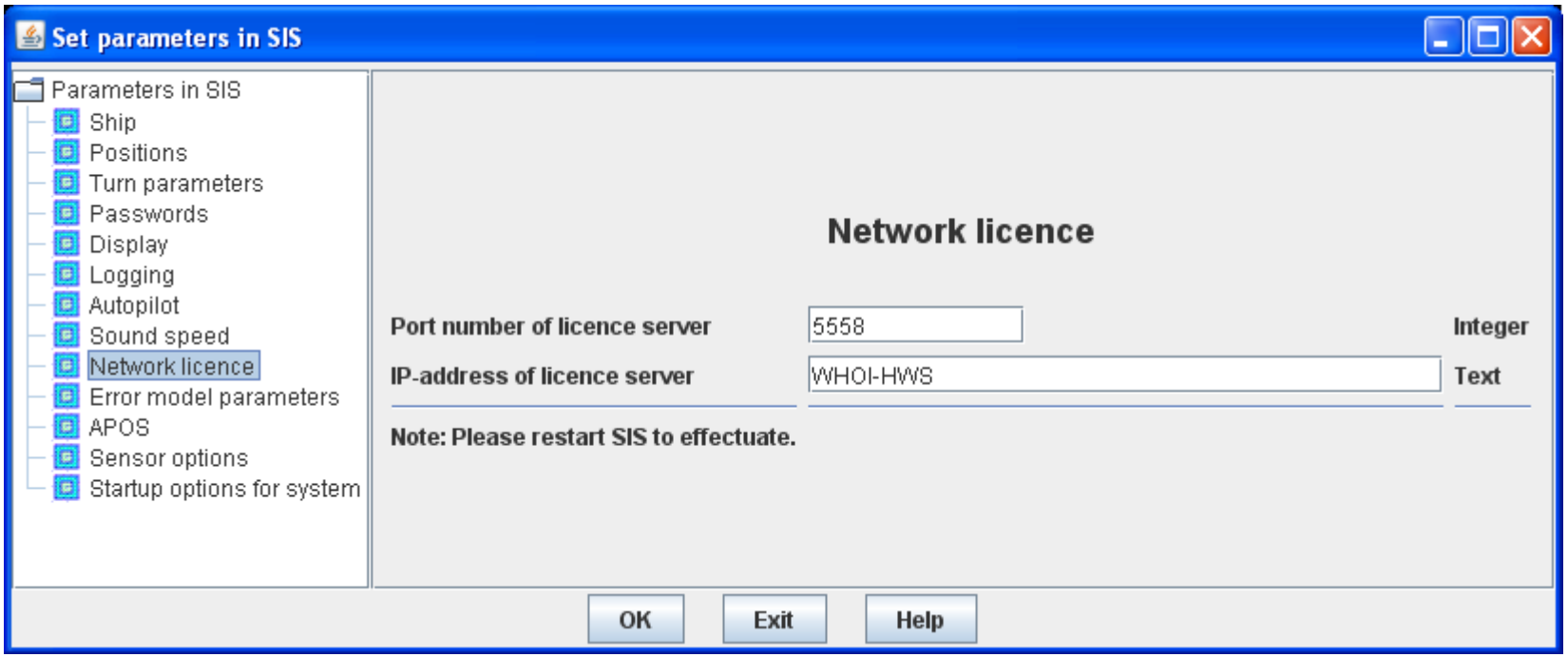

Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Passwords for different uses.
Password for BIST
simrad1
Text
Password for installation menu, valid as long as the frame is shown
simradN
Text
Password for installation menu, valid once
simrad0
Text
If 1, Installation menu is password protected
0
Integer
Note: Please restart SIS to effectuate.
OK
Exit
Help

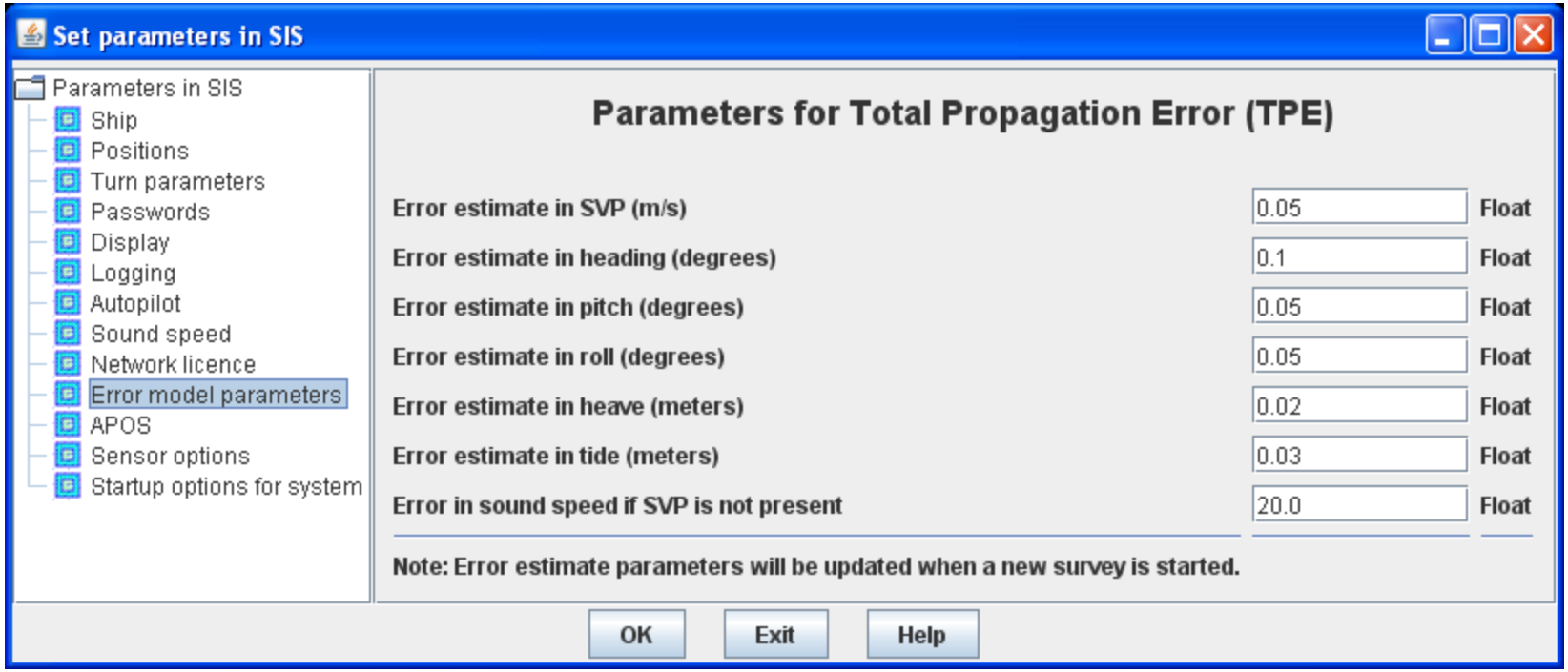

Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Parameters controlling the Geographical view
Crosstrack depth re. 1=waterline, 2=transducer
1
Integer
Alarm threshold for max depth below keel, 0 = disabled
0.0
Float
Alarm threshold for minimum depth below keel, 0 = disabled
0.0
Float
Alarm threshold for min. depth below keel within swath, 0 = disabled
0.0
Float
Margin (%) for issuing warning when depth approaches min/max values.
10
Integer
Missing input from active position sensor during logging (0=no flash, 1=flash)
1
Integer
Missing input from active motion sensor during logging (0=no flash, 1=flash)
1
Integer
Missing input from ROV depth sensor during logging (0=no flash, 1=flash)
1
Integer
Helmsman Survey folder. Empty if same as SIS
Text
Turn off gridding. (1= OFF) (Active at new line)
0
Integer
Auto Screen dump interval (sec.)
0
Integer
Auto Screen dump file (full path name)
Text
Max number of pings in realtime depths tail
250
Integer
Default Font Size in the Helmsman Display
30
Integer
Note: Please restart SIS to effectuate.
OK
Exit
Help

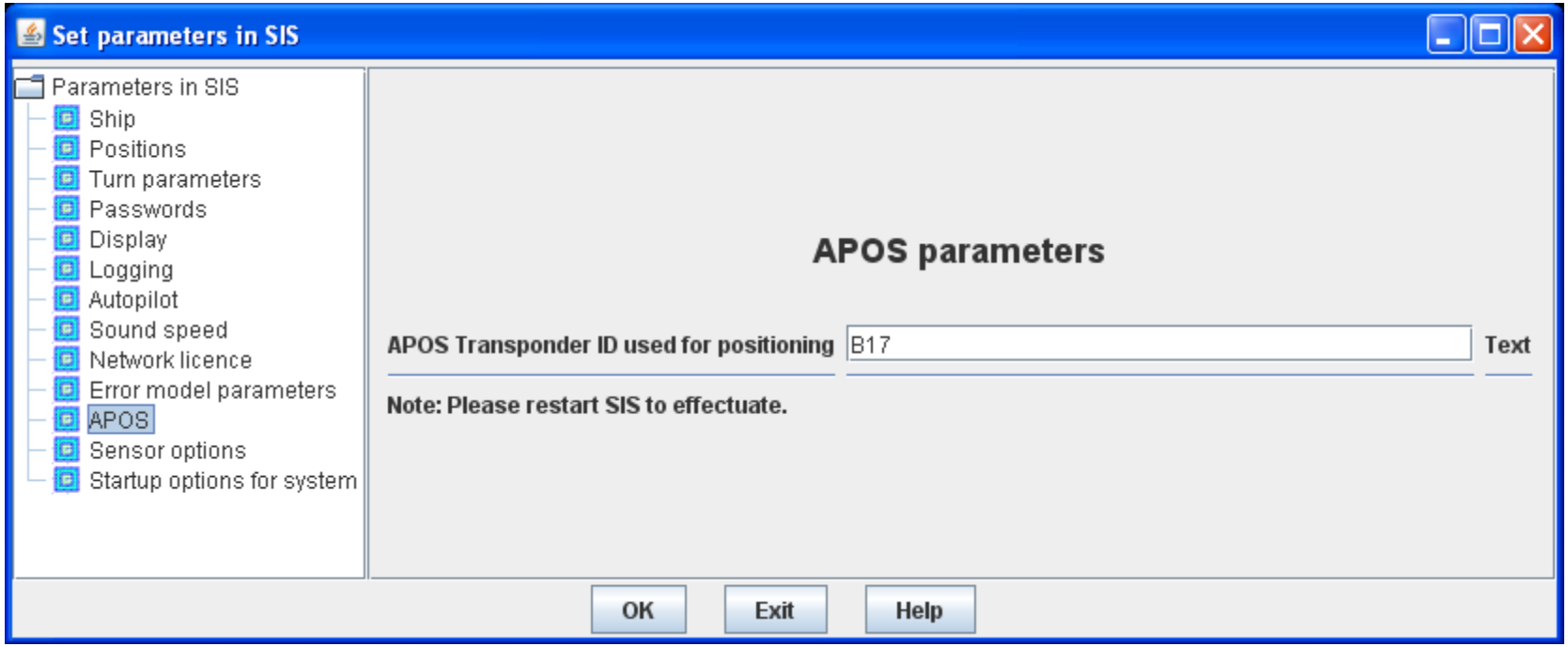

Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Logging control
TCP/IP Address to receive range and bearing to objects (x.x.x.x:port)
Text
Gives current data cleaning method, 1-GridEngine, 2-CUBE
1
Integer
Enable EA raw data logging (No=0, Yes=1)
1
Integer
Log error estimate to file. (0=off, 1=basic fomat, 2=ext. format)
0
Integer
SVP change should generate new logged line (No=0, Yes=1)
0
Integer
Water column disk. (Default: Raw data disk.)
Text
Eiva compatible start/stop datagram = 1. SIS default = 0
0
Integer
Enable or disable support for rawdata logger. (0=disable, 1=enable)
0
Integer
Hotkey for Pinging on/off
F10
Text
Hotkey for New line
F5
Text
Hotkey for logging on/off
F2
Text
Put all depths in grid if set to 1, save selected depths if set to 0
0
Integer
Interval for line counter in sec.
1800
Integer
Note: Please restart SIS to effectuate.
OK
Exit
Help

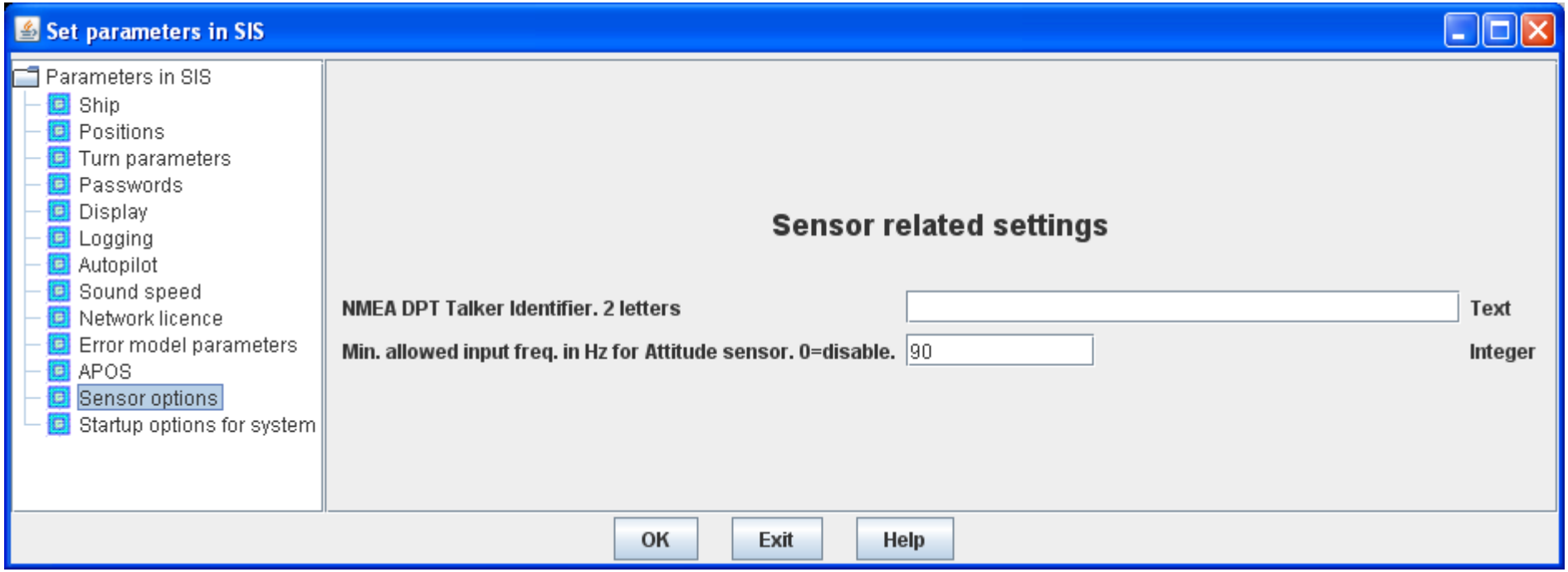

Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Parameters for Autopilot
NMEA APB Talker Identifier. 2 letters
SN
Text
NMEA version to use (1=2.20 or older, 2=2.30 or newer)
1
Integer
Heading M or T
T
Text
XTE Factor
10
Integer
Note: Please restart SIS to effectuate.
OK
Exit
Help

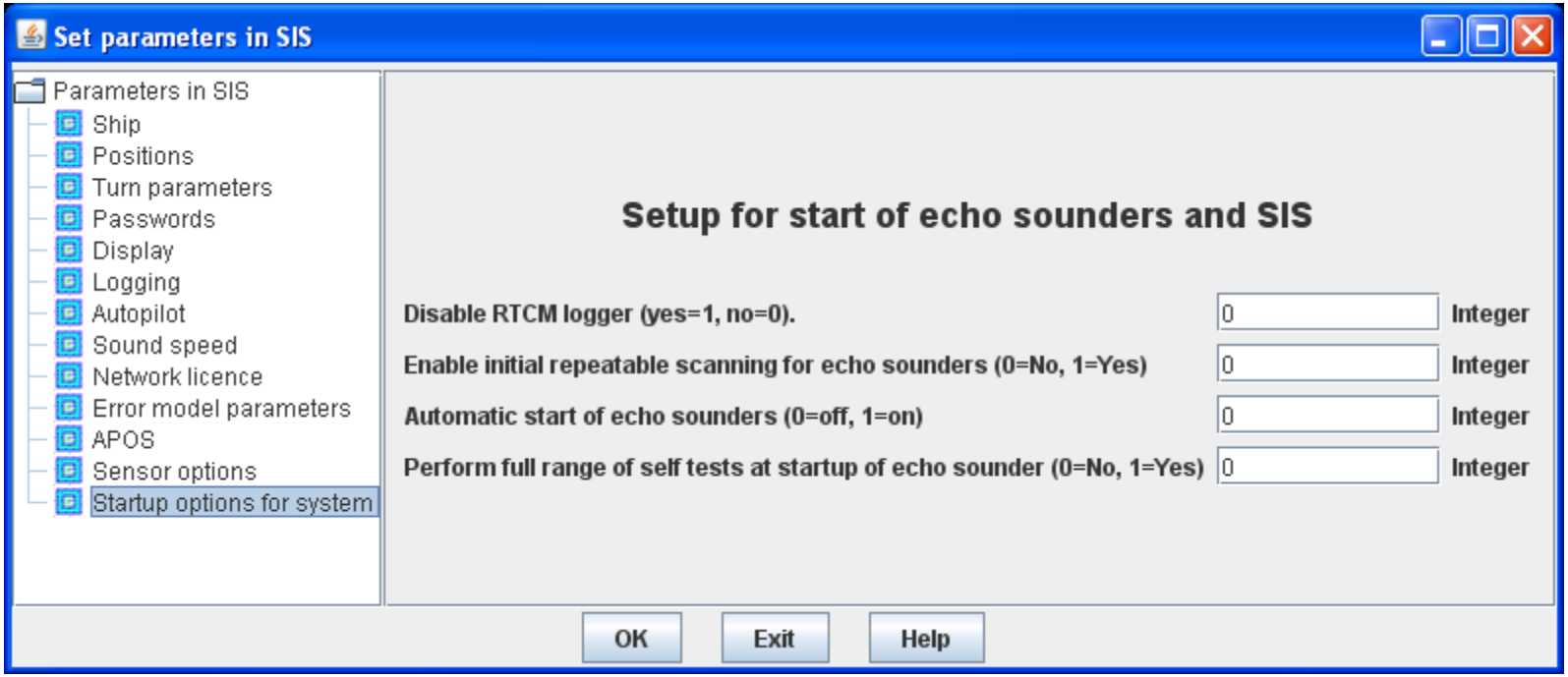

Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Sound speed error limits etc.
Automatic start of Sound Speed Editor. (0=disabled, 1=enabled)
1
Integer
Too big difference between sound speed at transducer from profile and probe
5.0
Float
Big difference between sound speed at transducer from profile and probe
3.0
Float
Note: Please restart SIS to effectuate.
OK
Exit
Help


Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Network licence
Port number of licence server
5558
Integer
IP-address of licence server
WHOI-HWS
Text
Note: Please restart SIS to effectuate.
OK
Exit
Help


Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Parameters for Total Propagation Error (TPE)
Error estimate in SVP (m/s)
0.05
Float
Error estimate in heading (degrees)
0.1
Float
Error estimate in pitch (degrees)
0.05
Float
Error estimate in roll (degrees)
0.05
Float
Error estimate in heave (meters)
0.02
Float
Error estimate in tide (meters)
0.03
Float
Error in sound speed if SVP is not present
20.0
Float
Note: Error estimate parameters will be updated when a new survey is started.
OK
Exit
Help


Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
APOS parameters
APOS Transponder ID used for positioning
B17
Text
Note: Please restart SIS to effectuate.
OK
Exit
Help


Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Sensor related settings
NMEA DPT Talker Identifier. 2 letters
Text
Min. allowed input freq. in Hz for Attitude sensor. 0=disable.
90
Integer
OK
Exit
Help


Set parameters in SIS
Parameters in SIS
Ship
Positions
Turn parameters
Passwords
Display
Logging
Autopilot
Sound speed
Network licence
Error model parameters
APOS
Sensor options
Startup options for system
Setup for start of echo sounders and SIS
Disable RTCM logger (yes=1, no=0).
0
Integer
Enable initial repeatable scanning for echo sounders (0=No, 1=Yes)
0
Integer
Automatic start of echo sounders (0=off, 1=on)
0
Integer
Perform full range of self tests at startup of echo sounder (0=No, 1=Yes)
0
Integer
OK
Exit
Help

SIS