

Set parameters in SIS

Parameters controlling the Geographical view

	Parameter Name	Data type	Value
▶	Default Font Size in the Helmsman Display	Integer	30
	Max number of pings in realtime depths tail	Integer	25
	Auto Screen dump file (full path name)	String	
	Auto Screen dump interval (sec.)	Integer	0
	Tun off gridding. (1= OFF) (Active at new line)	Integer	0
	Helmsman Survey folder. Empty if same as SIS	String	
	Missing input from ROV depth sensor during logging (0=no flash, 1=flash)	Integer	1
	Missing input from active motion sensor during logging (0=no flash, 1=flash)	Integer	1
	Missing input from active position sensor during logging (0=no flash, 1=flash)	Integer	1
	Margin (%) for issuing warning when depth approaches min/max values.	Integer	10
	Alarm threshold for min. depth below keel within swath, 0 = disabled	Float	0
	Alarm A popup appears when you are in too shallow water.	Float	0
	Alarm threshold for max depth below keel, 0 = disabled	Float	0
	Crosstrack depth re. 1=waterline, 2=transducer	Integer	1
	Font in NumDisp: 0=normal, 1=14pt, 2=18pt, 3=24pt; 11,12,13: Bold type	Integer	0
	Safety Contour Range Minimum (cm).	Integer	-1000
	Safety Contour Range Maximum (cm)	Integer	500
	Enable or disable depth Safety contours (0=disable, 1=enable).	Integer	1

Note: Please restart SIS to effectuate.

Exit Help

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Parameters for Total Propagation Error (TPE)

Parameter Name	Data type	Value
Error in sound speed if SVP is not present	Float	20
Error estimate in tide (m)	Float	0.03
Error estimate in heave (m)	Float	0.02
Error estimate in roll (deg.)	Float	0.05
Error estimate in pitch (deg.)	Float	0.05
Error estimate in heading (deg.)	Float	0.1
Error estimate in SVP (m./s)	Float	0.05
Send error estimate to LAN address (IP:port)	String	
Log error estimate to file. (0=off, 1=basic fomat, 2=ext. format)	Integer	0

Note: Changed error estimate parameters are used at start of new survey. Others are used after SIS restart.

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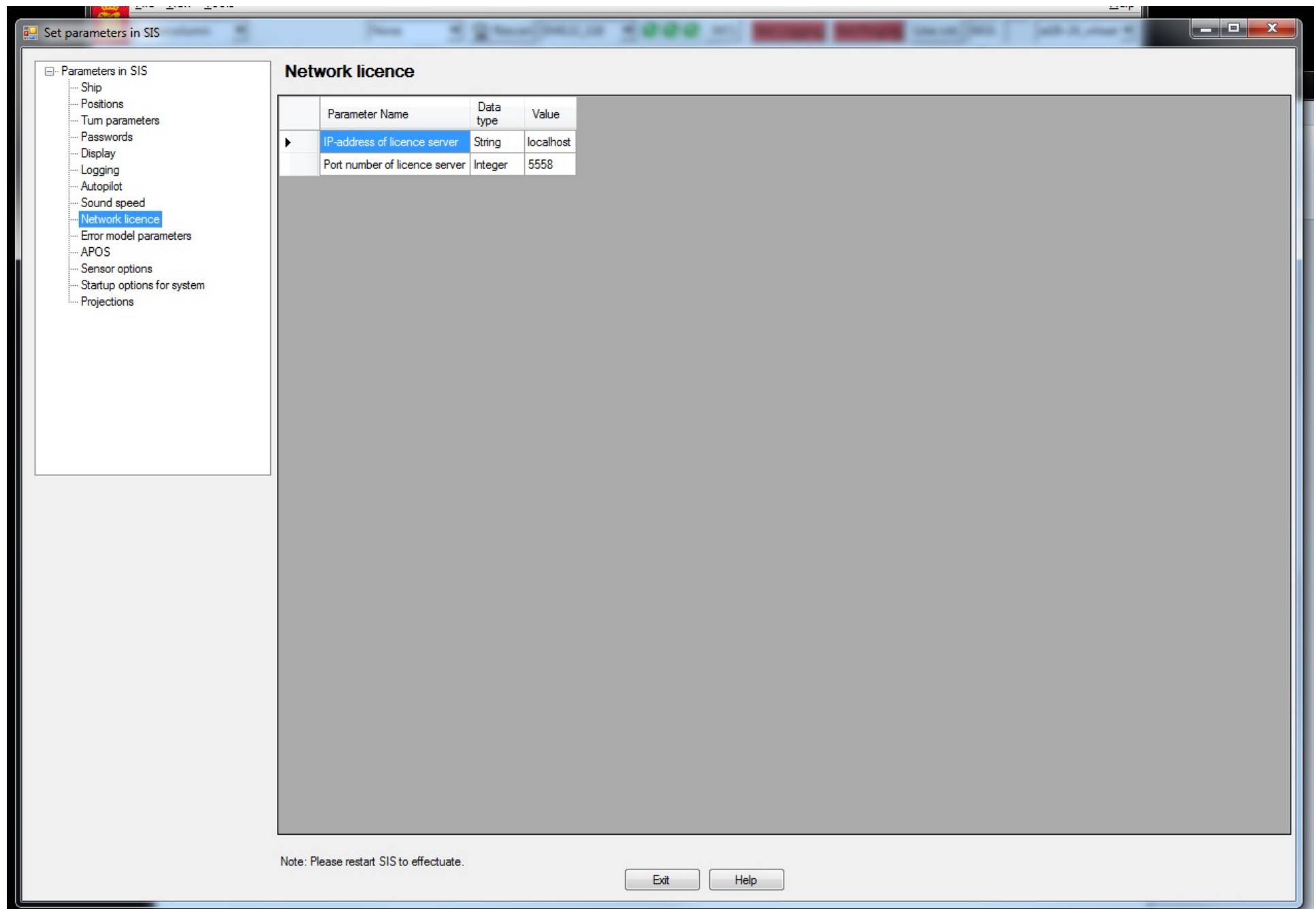
- Ship
- Positions
- Tun parameters
- Passwords
- Display
- Logging**
- Autopilot
- Sound speed
- Network licence
- Error model parameters
- APOS
- Sensor options
- Startup options for system
- Projections

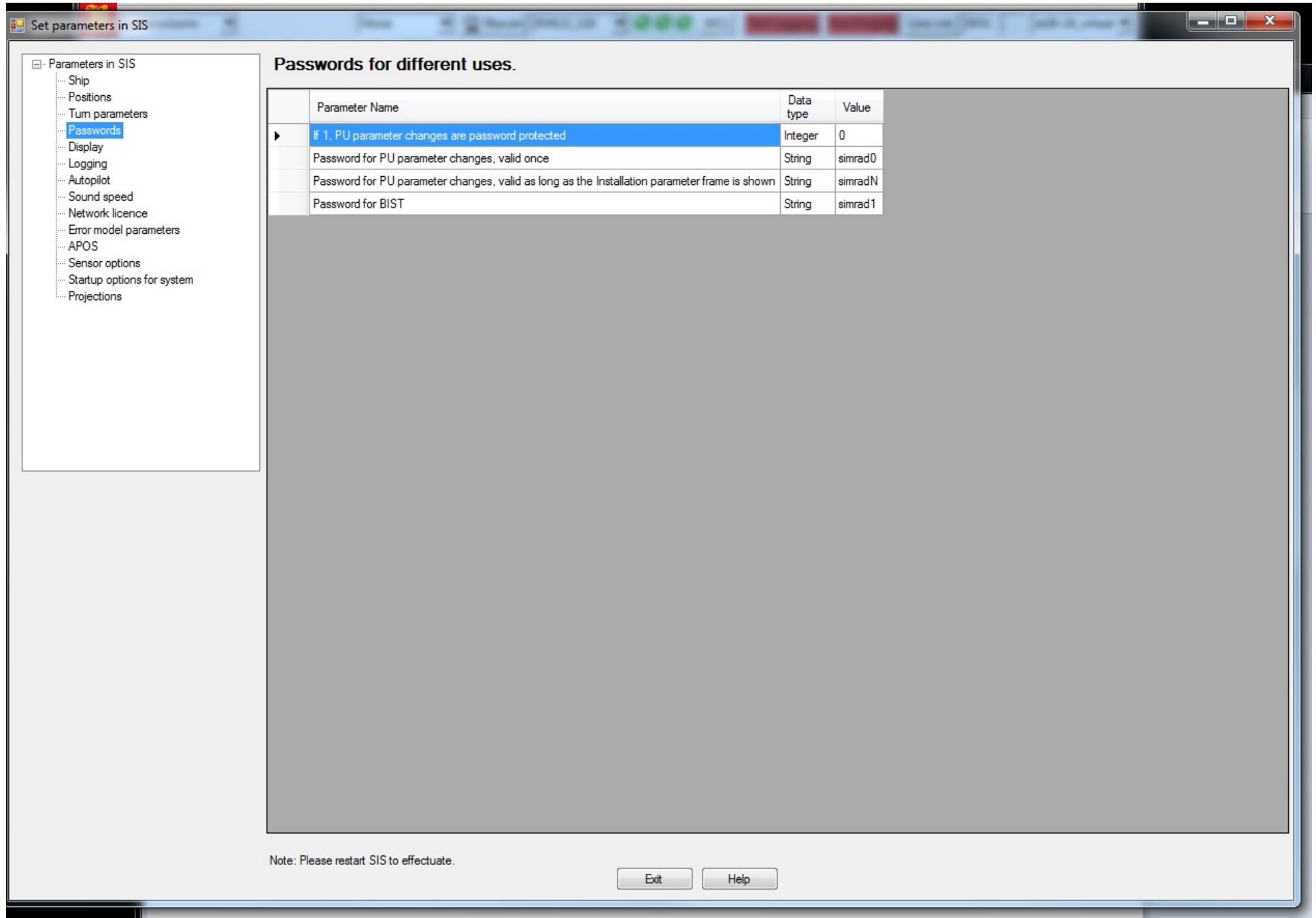
Logging control

Parameter Name	Data type	Value
Interval for line counter in sec.	Integer	3600
Put all depths in grid if set to 1, save selected depths if set to 0	Integer	0
Hotkey for logging on/off	String	F2
Hotkey for New line	String	F5
Hotkey for Pinging on/off	String	F10
Enable or disable support for rawdata logger. (0=disable, 1=enable)	Integer	0
Eiva compatible start/stop datagram = 1. SIS default = 0	Integer	0
Water column disk. (Default: Raw data disk.)	String	
SVP change should generate new logged line (No=0, Yes=1)	Integer	0
Enable EA raw data logging (No=0, Yes=1)	Integer	1
Gives current data cleaning method, 1-GridEngine, 2-CUBE	Integer	1
Send range and bearing for objects to address (IP:port)	String	
Initial watercolumn logging off or on (0=off, 1=on)	Integer	0
Highest approved swath density in percent of requested density (0=no checking, 110-2500=highest approved density in %).	Integer	0
Lowest approved swath density in percent of requested density (0=no checking, 10-90=lowest approved density in %).	Integer	90

Note: Please restart SIS to effectuate.

Exit Help





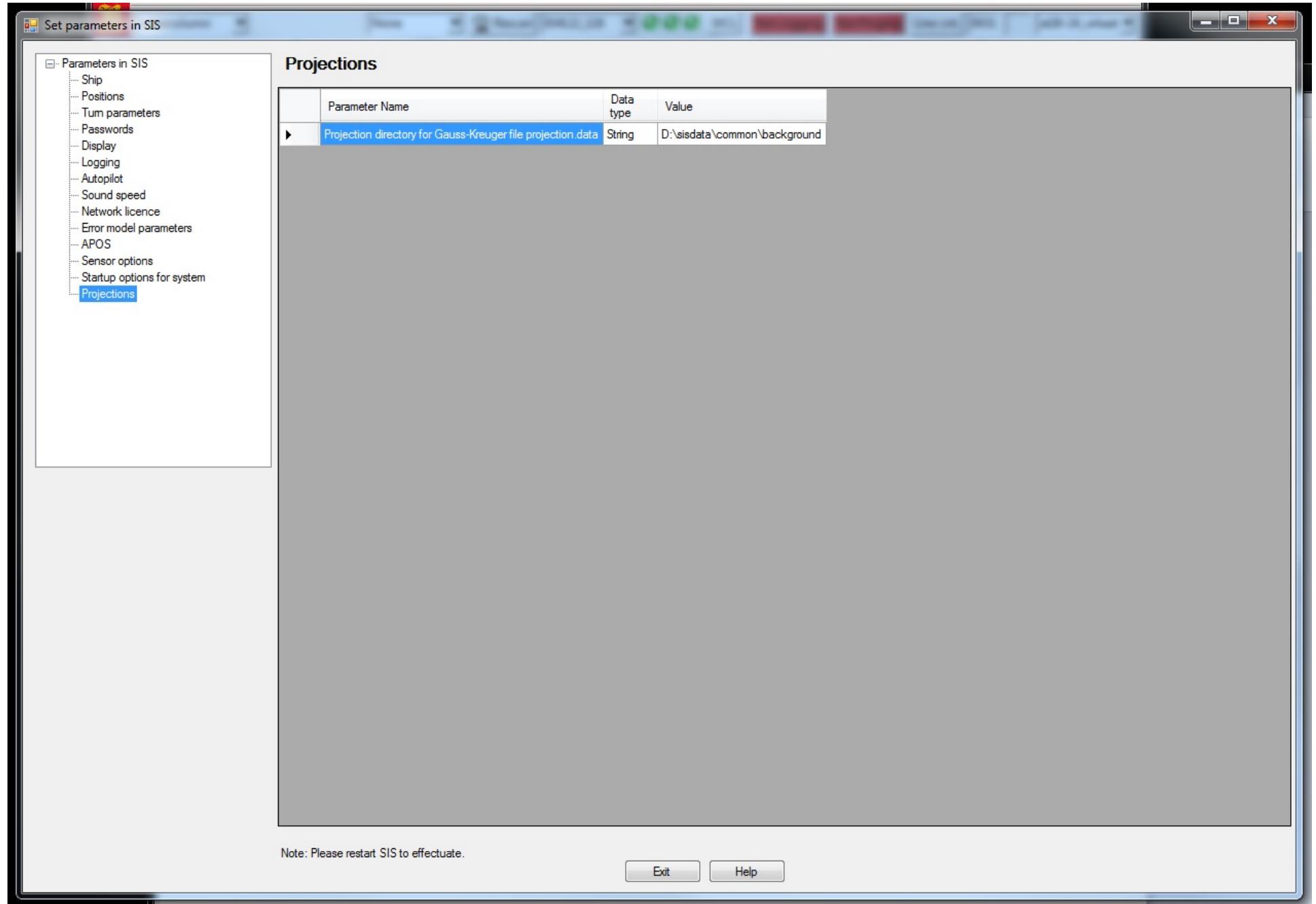
Set parameters in SIS

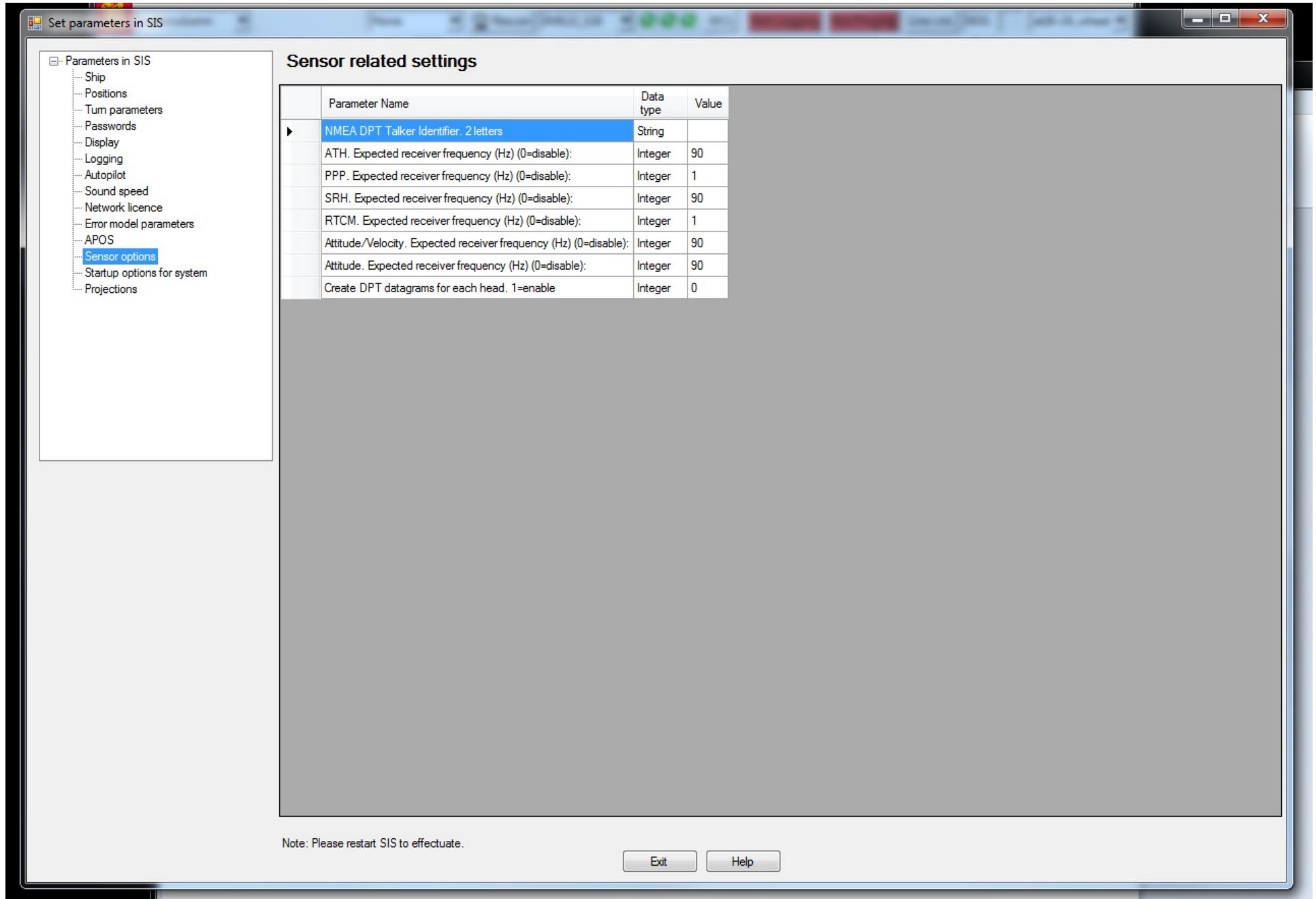
Error limits and filter settings for positions

	Parameter Name	Data type	Value
▶	Suspicious position jump (m/sec.)	Integer	20
	Error position jump (m/sec.)	Integer	30
	Few satellites	Integer	3
	Too few satellites	Integer	2
	Position quality too low (warning) (cm)	Integer	3000
	Position quality too low (error) (cm)	Integer	5000
	Change in time difference too big (msec.)	Integer	1500
	Time difference too big (sec.)	Integer	3600
	Position jump filter on or off. (off=0, on=1)	Integer	0
	Dead reckoning on or off. (off=0, on=1)	Integer	1
	Max age for ROV depth datagram (sec.)	Integer	2

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Define size and shape of the boat

	Parameter Name	Data type	Value
▶	Distance from reference point to bow of ship in cm	Integer	0
	Distance from reference point to stem of ship in cm	Integer	8500
	Distance from reference point to port side of ship in cm	Integer	800
	Distance from reference point to starboard side of ship in cm	Integer	800
	Length of the bow spear in cm	Integer	1850
	Distance from reference point to the deck of the ship in cm	Integer	500
	Distance from reference point to the keel of the ship in cm	Integer	0
	Minimum length of ship hull in cm (on screen)	Float	1
	Position marker body length in cm (on screen)	Float	0.4
	Position marker spear length in cm (on screen)	Float	1.6
	Position marker line width in pixels	Integer	3
	Fill (1) or do not fill (0) the ship symbol	Integer	1

Note: Close and reopen the geographical view to effectuate.

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Parameters in SIS

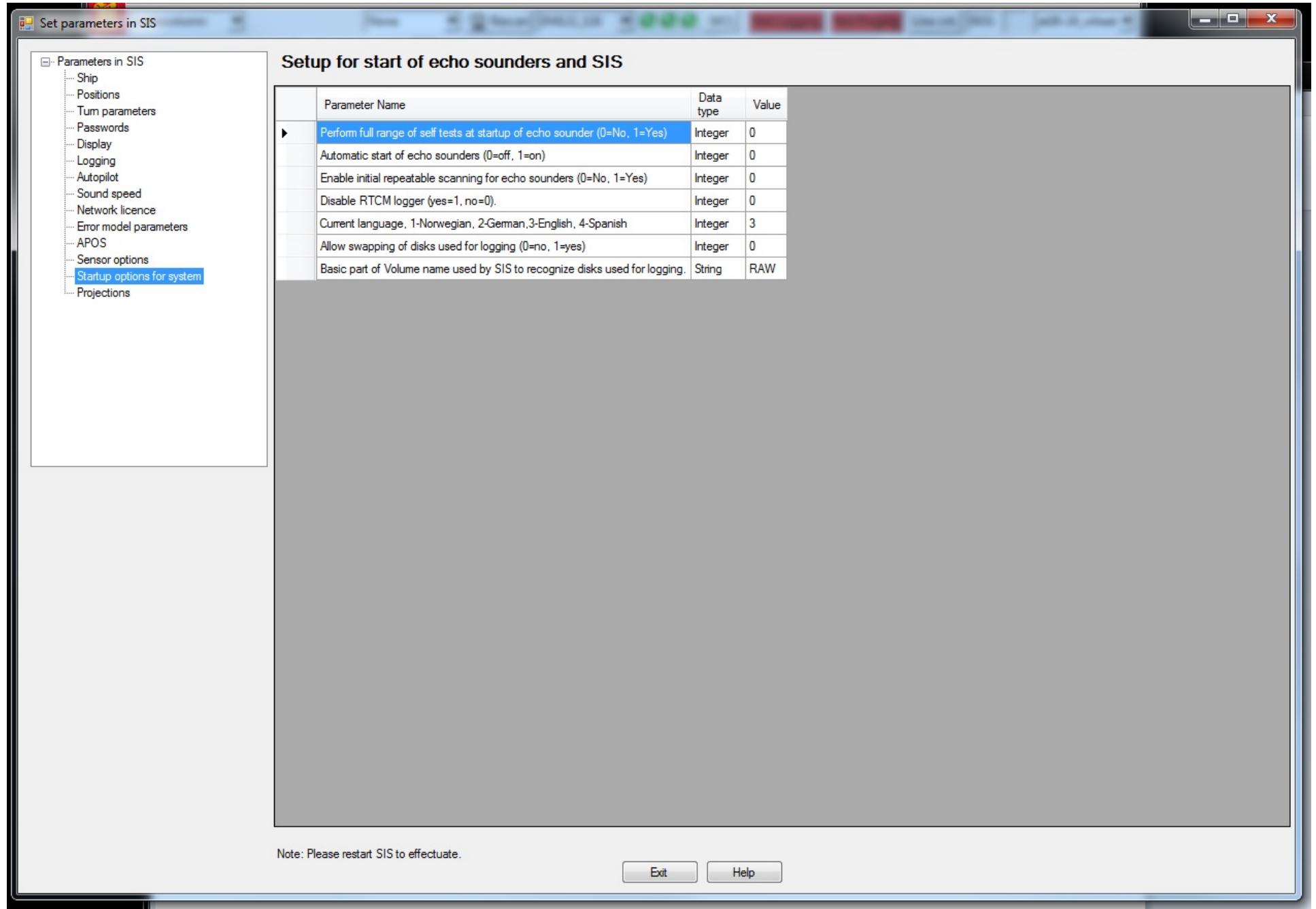
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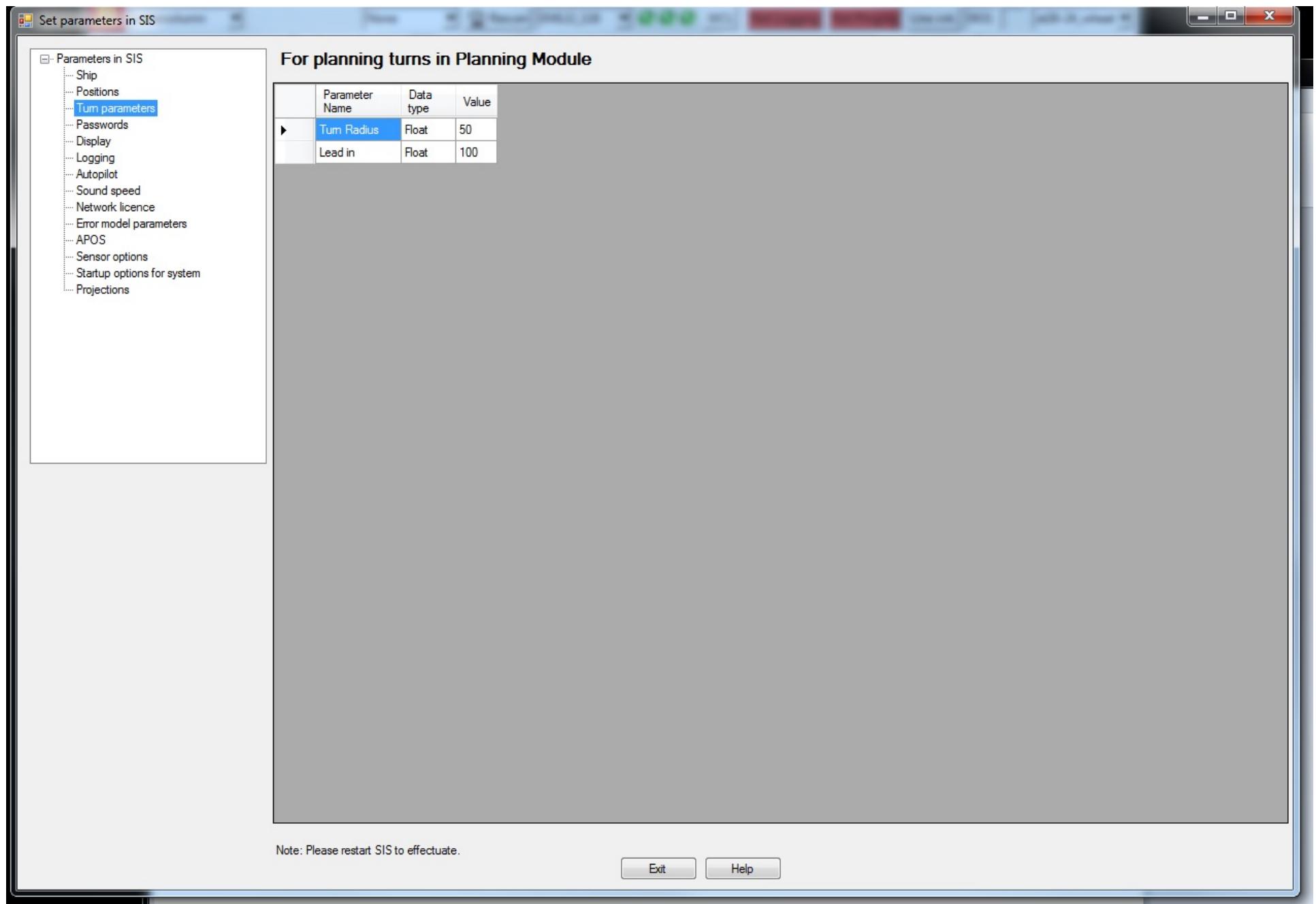
Sound speed error limits etc.

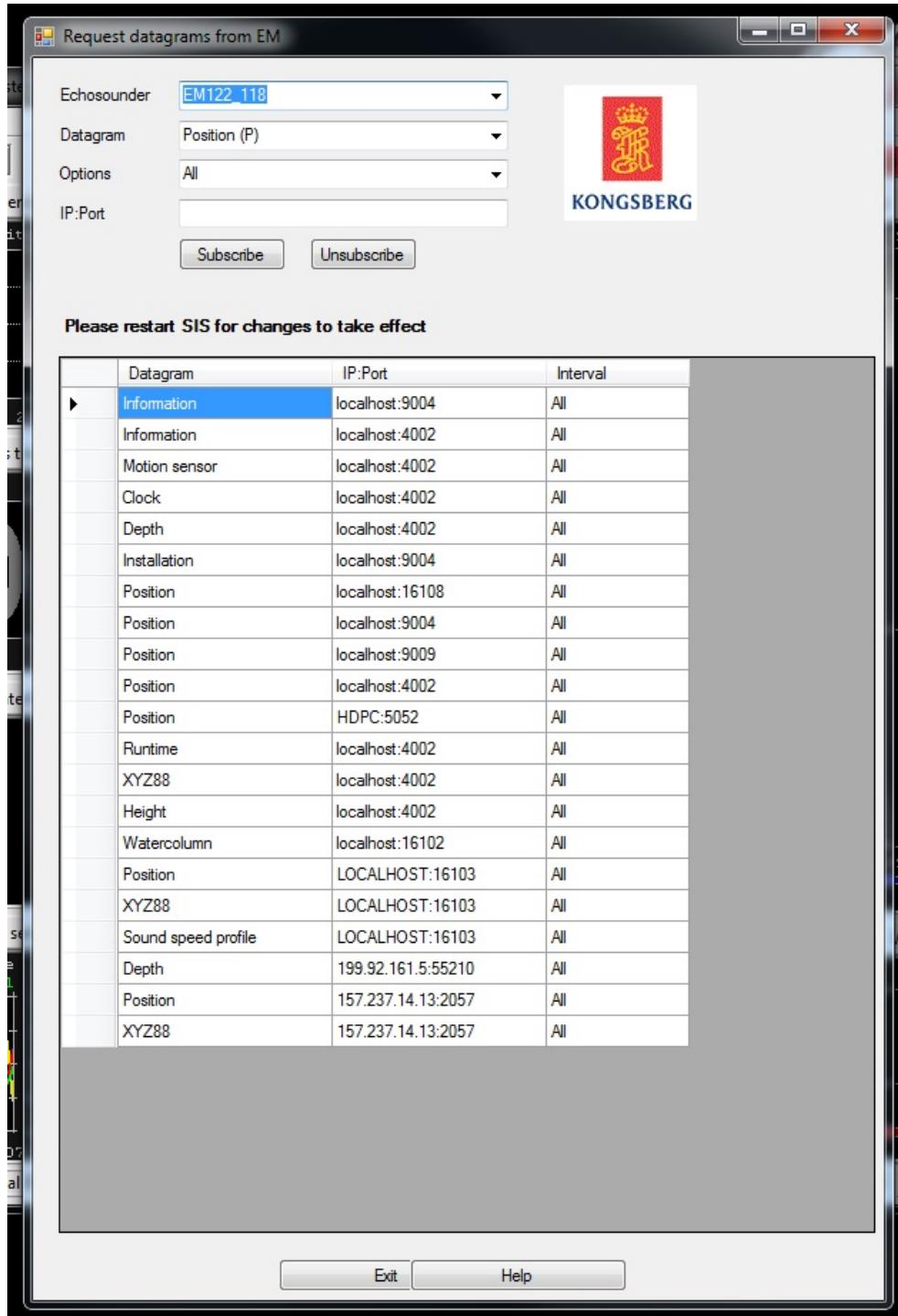
Parameter Name	Data type	Value
Big difference between sound speed at transducer from profile and probe	Float	5
Too big difference between sound speed at transducer from profile and probe	Float	10
Automatic start of Sound Speed Editor. (0=disabled, 1=enabled)	Integer	1
Max. no. of samples in a sound velocity profile to be used by the old types of echo sounders.	Integer	470
Max. no. of samples in a sound velocity profile to be used by the new types of echo sounders.	Integer	1000
Extend received sound speed profile automatically to 12000m (0=No, 1=Yes)	Integer	0

Note: Please restart SIS to effectuate.

Exit Help







Seatfloor Information System - version 4.1.3

External sensors

Input Setup

Sound Velocity Probe

Port: COM2
Probe available:
Probe type: AML SV&T (C+T)

SVP Logger

Port:
SVP Logger avail:

Barometer

Port:
Barometer avail:

Real time Tide

Port:
Realtime Tide avail:

Geodimeter

Port:
Geodimeter avail:

Echosounder

Port:

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

Port:
Auto Pilot avail:

Dyn Pos

Port:
Serial:
IP addr.:
Port addr.:
Ethernet:

Depth below keel

Port:
Depth below keel avail: COM1

Port:
Baud rate: 9600
Data bits: 8
Stop bits: 1
Parity: NONE

Waterline for NMEA single beam(m). Downward (Z) 5.27

OK CANCEL

