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| This is for 12 T |  |

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| iter=25;  #setting Input for inertial sensor and positioning  AIMU=0.1;  sigmaIMU=30;  ADVL=0.1;  sigmaDVL=2;  AUSBL=40;  sigmaUSBL=0.1;    if 806<=t && iDvl<6301 && t<=1896 # to overcome below water abruptness  xDVL = G1D(range,localTrajvar,30,40);  endif |  |
| iter=25;  #setting Input for inertial sensor and positioning  AIMU=0.1;  sigmaIMU=30;  ADVL=0.1;  sigmaDVL=2;  AUSBL=40;  sigmaUSBL=0.1;  if 806<=t && iDvl<6301 && t<=1906 # to overcome below water abruptness  xDVL = G1D(range,localTrajvar,30,40);  endif | z |
| iter=25;  #setting Input for inertial sensor and positioning  AIMU=0.1;  sigmaIMU=30;  ADVL=0.1;  sigmaDVL=2;  AUSBL=40;  sigmaUSBL=0.1;  if 806<=t && iDvl<6301 && t<=1906 # to overcome below water abruptness  xDVL = G1D(range,localTrajvar,30,10);  endif |  |
| Overshooting behaviour  iter=25;  #setting Input for inertial sensor and positioning  AIMU=0.1;  sigmaIMU=30;  ADVL=0.1;  sigmaDVL=2;  AUSBL=40;  sigmaUSBL=0.1;  if 806<=t && iDvl<6301 && t<=1906 # to overcome below water abruptness  xDVL = G1D(range,localTrajvar,30,30);  endif |  |
| Above  if 806<=t && iDvl<6301 && t<=1906 # to overcome below water abruptness  xDVL = G1D(range,localTrajvar,30,20);  endif |  |
| iter=25;  #setting Input for inertial sensor and positioning  AIMU=0.1;  sigmaIMU=20;  ADVL=0.1;  sigmaDVL=2;  AUSBL=40;  sigmaUSBL=0.1;  if 806<=t && iDvl<6301 && t<=2026 # to overcome below water abruptness  xDVL = G1D(range,localTrajvar,30,20);  endif |  |
| if 774<=t && iDvl<6301 && t<=2015 # to overcome below water abruptness  xDVL = G1D(range,localTrajvar,30,20);  Endif  X  Y  Z |  |