

**Subject:** PANDORA Fort William - 2014/10/07 - Day 2

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**Date:** 07/10/14 23:33

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**\*Weather conditions\***

- cloudy
- Day Temperature: ~ 6C

**\*Incidents and near misses\***

- 0 - Incidents
- 0 - Accidents
- 0 - Near misses

**\*Personnel in place\***

Valerio De Carolis, Mariela De Lucas, Francesco Maurelli, Len McLean, Jamil Sawas

**\*Goals of the Day\***

- setup Nessie with p/t at TUC Pier
- gather data of the pier with tilt option on

**\*Report (GMT)\***

07:00 start of the day  
08:30 start packing from Ocean Frontier  
10:30 set-up at divers' pier, MB sonar re-mounted with the right orientation  
11:05 Nessie on, checks  
11:30 Nessie in water, low tide – path on paper  
13:00 lunch break / rosbag checking / GoPro download and charge  
15:40 new recording, high tide – mainly loops across next “cell”  
16:40 recovering, tide coming very high  
15:40 packing in the van/track  
18:00 dinner  
18:40 TUC ROV simulator  
20:30 rosbag checking  
22:00 planning for the next day  
22:30 call the day finished

**\*General comments\***

- tidal currents are very strong, Nessie able to fight them with lots of difficulties, impossible later control. Investigation needed to see historical data, possibly linked to moon phases, to plan best trial period (new moon?)
- in low-tide the P/T was making the MB sonar pointing to the bottom of the loch very often
- in order to play the first bagfile, rosmaster was changed to trieste, but was not set back to Nessie. When rosbag record -a, it only captured the bvt topics (run on laptop), ignoring everything on Nessie. Even if on the network, rosbag record does not record everything flying in the network, but only things directly linked to master. So, second bag (afternoon), was very good in terms of images, but with no other data associated.

**\*Weather forecast for tomorrow\***

fog, light rain  
Temperature about 6 DEG

**\*Objectives for tomorrow\***

- try new nav from Valerio, in order to use joystick at fixed depth
- run high-tide data gathering, possibly pointing MB at 45DEG pan, in order to maximise camera view and overlap for both sonars