



Master Track RV Polarstern ANT-XIX/4

Data Processing Report

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Contact:

Dr. Rainer Knust

Alfred Wegener Institute

Columbusstrasse, D-27568 Bremerhaven, GERMANY

Tel: +49(471)4831-1709 Fax: +49(471)4831-1918

Mail: Polarstern-Coordination@awi.de

Processing Agency:

FIELAX

Gesellschaft für wissenschaftliche Datenverarbeitung mbH Schleusenstr. 14, D-27568 Bremerhaven, GERMANY

Tel: +49 (0) 471 30015 0 Fax: +49 (0) 471 30015 22 Mail: info@fielax.de

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| | | | |



1 Introduction

This report describes the processing of raw data acquired by position sensors on board RV Polarstern during expedition ANT-XIX/4 to receive a validated master track which is used as reference of further expedition data.

2 Workflow

The different steps of processing and validation are visualized in figure 1. Unvalidated data of up to three sensors and ship-motion data are extracted from the DAVIS SHIP data base (https://dship.awi.de) in a 1-second interval. They are converted to ESRI point shapefiles and imported to ArcGIS. A visual screening is performed to evaluate data quality and remove outliers manually. The position data from each position sensor are centered to the destined master track origin by applying ship-motion data (angles of roll, pitch and heading) and lever arms. For all three resulting position tracks, a quality check is performed using a ship's speed filter and an acceleration filter. Filtered positions are flagged. In addition, a manual check is performed to flag obvious outliers. Those position tracks are combined to a single master track depending on a sensor priority list (by accuracy, reliability) and availability / applied exclusion of automatically or manually flagged of data. Missing data up to a time span of 60 seconds are linearly interpolated. To reduce the amount of points for overview maps the master track is generalized by using the Ramer-Douglas-Peucker algorithm. This algorithm returns only the most significant points from the track. Full master track and generalized master track are written to text files and imported to PANGAEA (http://www.pangaea.de) for publication.

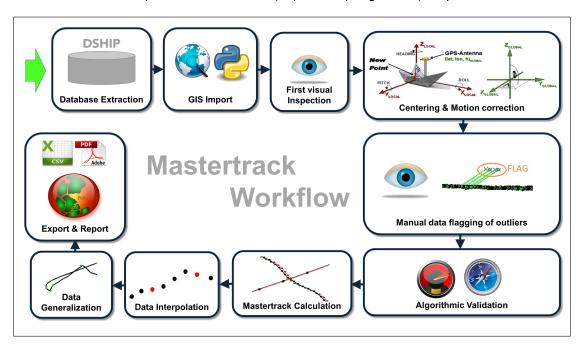


Figure 1: Workflow of master track data processing



3 Sensor Layout

This chapter describes the position sensors mounted during this cruise.

Cruise details

Vessel name RV Polarstern
Cruise name ANT-XIX/4

Cruise start 01.03.2002 Punta Arenas
Cruise end 02.04.2002 Punta Arenas

Cruise duration 33 days

Master track reference point: Resulting master track is referenced to MINS installation point.

Position sensors

| Sensor name | Raytheon Anschuetz MINS2, short: MINS | | | |
|---------------------|--|--|--|--|
| Description | Marine inertial navigation system with reference positions from Trimble | | | |
| | DGPS | | | |
| Accuracy | < 60 m CEP50 (with SPS GPS) | | | |
| Installation point | Gravimeter room on F-Deck, close to COG | | | |
| Installation offset | Offset from master track reference point to sensor installation point X Positive to bow 0.000 m Y Positive to starboard 0.000 m Z Positive upwards 0.000 m | | | |

| Sensor name | Trimble Marine SPS461 (1), short: Trimble 1 | | | | |
|---------------------|---|--|--|--|--|
| Description | DGPS-Receiver, correction type DGPS RTCM 2.x, correction source | | | | |
| | DGPS Base via radio | | | | |
| Accuracy | Horizontal: \pm 0.25 m + 1 ppm & Vertical: \pm 0.50 m + 1 ppm | | | | |
| Installation point | Observation deck (starboard) | | | | |
| Installation offset | Offset from master track reference point to sensor installation point X Positive to bow 22.777 m Y Positive to starboard -5.460 m Z Positive upwards 21.525 m | | | | |



| Sensor name | Trimble Marine SPS461 (2), short: Trimble 2 | | | | |
|---------------------|---|--|--|--|--|
| Description | DGPS-Receiver, correction type DGPS RTCM 2.x, correction source | | | | |
| | DGPS Base via radio | | | | |
| Accuracy | Horizontal: \pm 0.25 m + 1 ppm & Vertical: \pm 0.50 m + 1 ppm | | | | |
| Installation point | Observation deck (port) | | | | |
| Installation offset | Offset from master track reference point to sensor installation point X Positive to bow 16.527 m Y Positive to starboard 12.408 m Z Positive upwards 21.538 m | | | | |

Motion sensor

| Sensor name | Raytheon Anschuetz MINS2, short: MINS | | |
|---|---|--|--|
| Description | Marine inertial navigation system with reference positions from Trimble | | |
| | DGPS | | |
| Accuracy $\pm~0.02^{\circ}~\text{roll}, \pm~0.02^{\circ}~\text{pitch}, \pm~0.05^{\circ}~\text{heading}$ | | | |
| Installation point Gravimeter room on F-Deck, close to COG | | | |

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Database Extraction

| Data source | DSHIP database (dship.awi.de) | |
|---------------------------------------|-------------------------------|--|
| Exported values | 2851200 | |
| First dataset 2002-03-01T00:00:00 UTC | | |
| Last dataset 2002-04-02T23:50:59 UTC | | |

Centering & Motion Compensation

Each position track has been centered to the *MINS installation point* by applying the correspondent motion angles for heading, roll and pitch as well as the installation offsets from chapter 2. The motion data were acquired by Raytheon Anschuetz MINS2.

Automatic Validation

The following thresholds were applied for the automatic flagging of the position data:

| | 11 00 0 1 |
|---|------------------------------------|
| Speed Maximum 20 kn between two datapoints. | |
| Acceleration Maximum 1 m/s ² between two datapoints. | |
| Change of course | Maximum 5° between two datapoints. |



Manual Validation

Obvious outliers were removed manually. For details see Processing Logbook of RV Polarstern (hdl:10013/epic.45909).

Flagging result

| | MINS | | Trimble 1 | | Trimble 2 | |
|--------------|--------|---------|-----------|---------|-----------|---------|
| Missing | 33525 | 1.176% | 34830 | 1.222% | 30526 | 1.071% |
| Speed | 37030 | 1.299% | 16039 | 0.563% | 6756 | 0.237% |
| Acceleration | 597413 | 20.953% | 91300 | 3.202% | 36814 | 1.291% |
| Course | 866878 | 30.404% | 1160947 | 40.718% | 1015832 | 35.628% |
| Manually | 60520 | 2.123% | 197 | 0.007% | 91 | 0.003% |

Master Track Generation

The master track is derived from the position sensors' data selected by priority.

Sensor priority used:

- 1. Trimble 1
- 2. MINS
- 3. Trimble 2

Filters applied: manual, speed, acceleration, course.

Distribution of position sensor data in master track:

| Sensor | Data points | Percentage |
|--------------|-------------|------------|
| Total | 2850660 | 99.981 % |
| MINS | 670115 | 23.507% |
| Trimble 1 | 1640566 | 57.550 % |
| Trimble 2 | 386729 | 13.566 % |
| Interpolated | 124613 | 4.371 % |
| Gaps | 28637 | 1.005% |

Remarks

None.

Score

For each cruise, a score is calculated ranging from 0 (no data) to 100 (only very good data). the score for the cruise ANT-XIX/4 is 94.



Generalization

The master track is generalized to receive a reduced set of the most significant positions of the track using the Ramer-Douglas-Peucker algorithm and allow a maximum tolerated distance between points and generalized line of 4 arcseconds.

Results:

| Number of generalized points | 1734 points |
|------------------------------|-------------|
| Data reduction | 99.9392% |



Result files

Report in XML format:

The XML contains all information of the master track generation in a machine-readable format. In addition a XSD schema file is provided.

Master track text file:

The format is a plain text (tab-delimited values) file with one data row in 1 second interval.

| Column separator | Tabulator "\t" | | | |
|------------------|--|---|--|--|
| Column 1 | Date and ti | Date and time expressed according to ISO 8601 | | |
| Column 3 | Latitude in decimal format, unit degree | | | |
| Column 4 | Longitude in decimal format, unit degree | | | |
| Column 5 | Flag for data source | | | |
| | 1 | MINS | | |
| | 2 | Trimble 1 | | |
| | 3 | Trimble 2 | | |
| | INTERP | Interpolated point | | |
| | GAP Missing data | | | |

Text file of the generalized master track:

The format is a plain text (tab-delimited values) file.

| Column separator | Tabulator "\t" |
|------------------|---|
| Column 1 | Date and time expressed according to ISO 8601 |
| Column 2 | Latitude in decimal format, unit degree |
| Column 3 | Longitude in decimal format, unit degree |

Processing Report:

This PDF document.



Cruise map

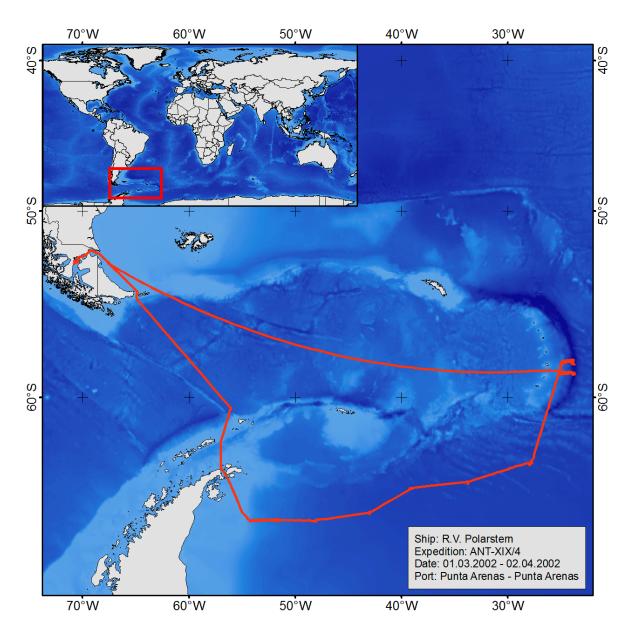


Figure 2: Map of the generalized master track