5.22 Shipboard ADCP

(1) Personnel (*: Leg-1, **: Leg-2, ***: Leg-1+2)

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(2) Objective

To obtain continuous measurement of the current profile along the ship's track.

(3) Methods

Upper ocean current measurements were made in MR11-07 cruise, using the hull-mounted Acoustic Doppler Current Profiler (ADCP) system, which consists of following components;

1) R/V MIRAI has installed vessel-mount ADCP (75 kHz "Ocean Surveyor", Teledyne RD Instruments). It has a phased-array transducer with single assembly and creates 4 acoustic beams electronically.
2) For heading source, we use ship's gyro compass (Tokimec, Japan), continuously providing heading to the ADCP system directory. Also we have Inertial Navigation System (PHINS, iXSEA) which provide high-precision heading and attitude information are stored in ".N2R" data files.
3) DGPS system (Trimble SPS751 & StarFixXP) providing position fixes.
4) We used VmDas version 1.4.2 (TRD Instruments) for data acquisition.
5) To synchronize time stamp of pinging with GPS time, the clock of the logging computer is adjusted to GPS time every 1 minute.
6) The sound speed at the transducer does affect the vertical bin mapping and vertical velocity measurement, is calculated from temperature, salinity (constant value; 35.0 psu) and depth (6.5 m; transducer depth) by equation in Medwin (1975).

Data was configured for 16-m intervals starting 23-m below the surface. Every ping was recorded as raw ensemble data (.ENR). Also, 60 seconds and 300 seconds averaged data were recorded as short term average (.STA) and long term average (.LTA) data, respectively. Major parameters for the measurement (Direct Command) are shown in Table 5.22-1.

(4) Preliminary results

Figures 5.22-1and 5.22-2 show time series plot of current U/V vector during stationary observation.

(5) Data archive

These data obtained in this cruise will be submitted to the Data Management Group (DMG) of JAMSTEC, and will be opened to the public via JAMSTEC home page.

(6) Remarks (Times in UTC)

The observation was carried out within following periods,

Leg1: 12:07 25th Sep. 2011 to 00:03 26th Oct. 2011

Leg2: 00:00 29th Oct. 2011 to 03:03 1st Dec. 2011

Table 5.22-1 Major parameters

Environmental Sensor Commands	
EA = +04500	Heading Alignment (1/100 deg)
EB = +00000	Heading Bias (1/100 deg)
ED = 00065	Transducer Depth (0 - 65535 dm)
EF = +001	Pitch/Roll Divisor/Multiplier (pos/neg) [1/99 - 99]
EH = 00000	Heading (1/100 deg)
ES = 35	Salinity (0-40 pp thousand)
EX = 00000	Coord Transform (Xform:Type; Tilts; 3Bm; Map)
EZ = 10200010	Sensor Source (C; D; H; P; R; S; T; U)
	C (1): Sound velocity calculates using ED, ES, ET (temp.)
	D (0): Manual ED
	H (2): External synchro
	P (0), R (0): Manual EP, ER (0 degree)
	S (0): Manual ES
	T (1): Internal transducer sensor
	U (0): Manual EU
Timing Commands	
TE = 00:00:02.00	Time per Ensemble (hrs:min:sec.sec/100)
TP = 00:02.00	Time per Ping (min:sec.sec/100)
Water-Track Commands	
WA = 255	False Target Threshold (Max) (0-255 count)
WB = 1	Mode 1 Bandwidth Control (0=Wid, 1=Med, 2=Nar)
WC = 120	Low Correlation Threshold (0-255)
WD = 111 100 000	Data Out (V; C; A; PG; St; Vsum; Vsum^2;#G;P0)
WE = 1000	Error Velocity Threshold (0-5000 mm/s)
WF = 0800	Blank After Transmit (cm)
WG = 001	Percent Good Minimum (0-100%)
WI = 0	Clip Data Past Bottom (0 = OFF, 1 = ON)
WJ = 1	Rcvr Gain Select (0 = Low, 1 = High)
WM = 1	Profiling Mode (1-8)
WN = 40	Number of depth cells (1-128)
WP = 00001	Pings per Ensemble (0-16384)
WS= 1600	Depth Cell Size (cm)
WT = 000	Transmit Length (cm) [0 = Bin Length]
WV = 0390	Mode 1 Ambiguity Velocity (cm/s radial)

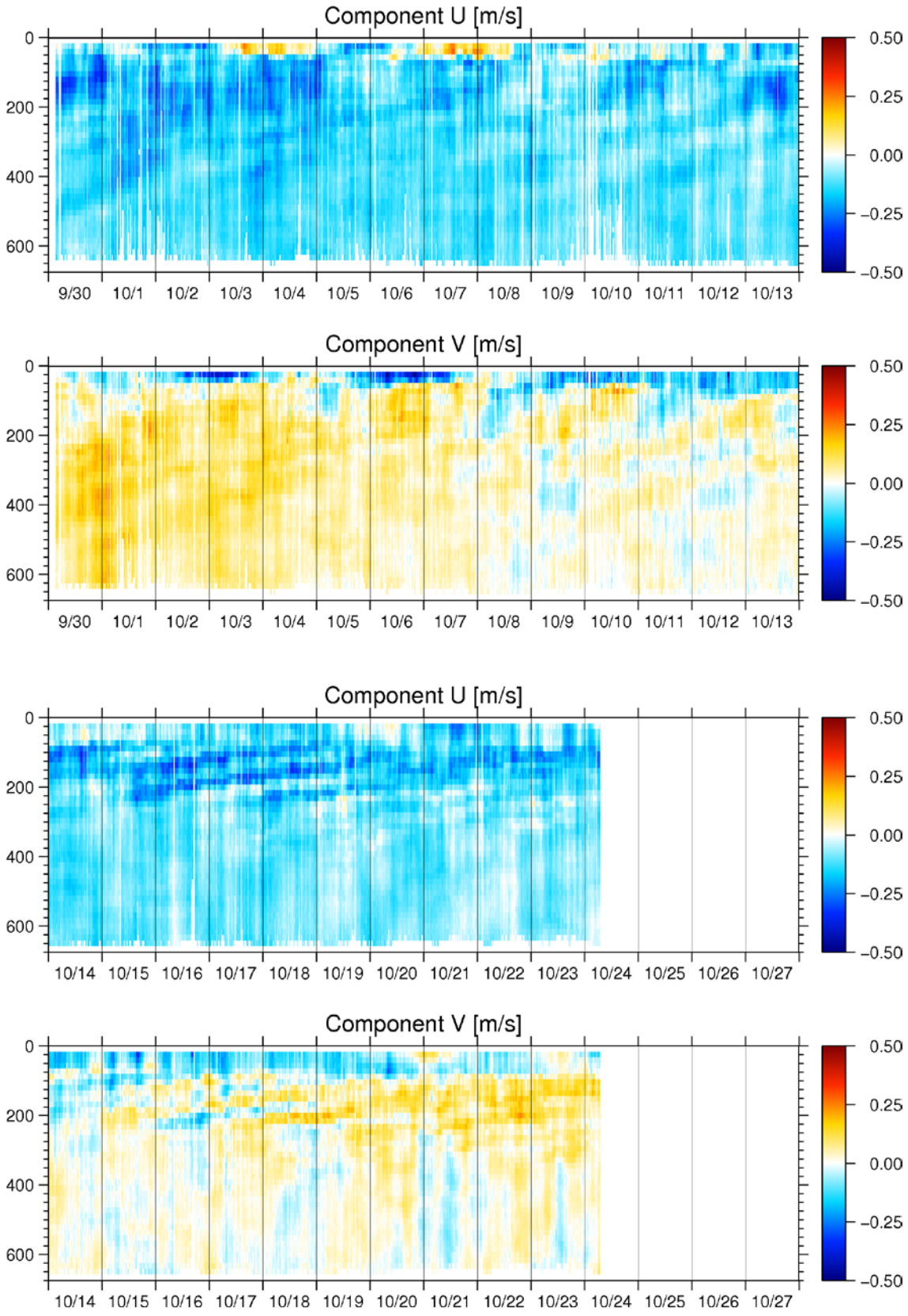

Fig 5.22-1: Time series plot of zonal and meridional current during stationary observation in Leg-1.

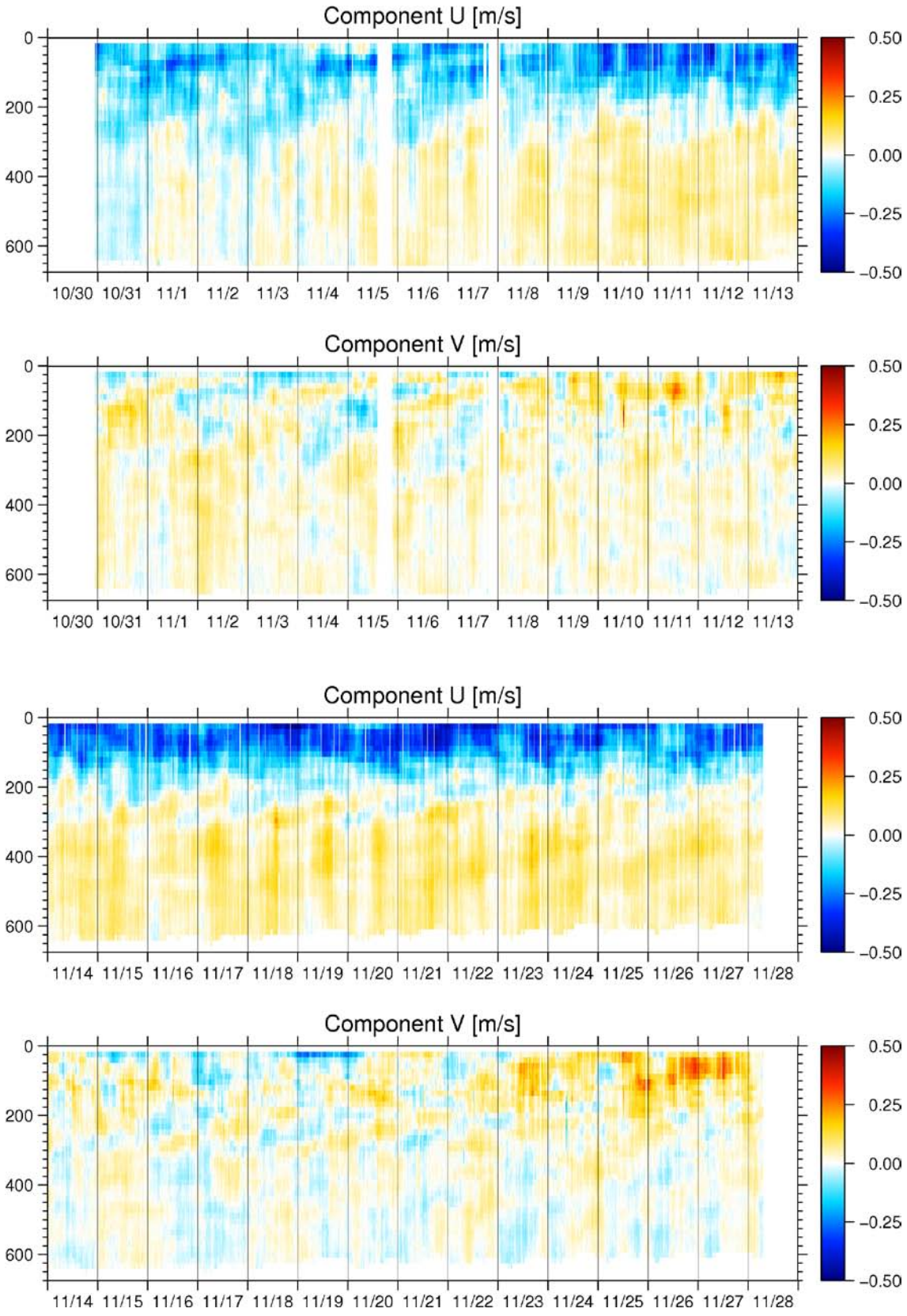

Fig 5.22-2: Time series plot of zonal and meridional current during stationary observation in Leg-2.