



KONGSBERG

Maintenance Manual

EM 3000

Multibeam echo sounder

Base version



852-164371

EM 3000

Maintenance manual

Document revisions

Rev	Date	Written by	Checked by	Approved by
A	20.12.00	EGj	BHL	EHa
B	21.02.02	EGj	KN	EHa
C	11.06.02	EGj	KN	KN
D	26.06.02	EGj	KN	KN
E	08.07.04	EGj	KN	KN

Rev.A	Original issue.
Rev.B	Minor changes to the text due to misprints and changes of the product.
Rev.C	Minor changes in Datagram formats and drawing of AUV Sonar Head cable.
Rev.D	This revision includes the AUV Processing Unit as well as the "New" and "Old" Standard Processing Unit.
Rev.E	HWS 10 included. General update.

About this document

The information contained in this document is subject to change without prior notice. Kongsberg Maritime AS shall not be liable for errors contained herein, or for incidental or consequential damages in connection with the furnishing, performance, or use of this document.

© 2004 Kongsberg Maritime AS. All rights reserved. No part of this work covered by the copyright hereon may be reproduced or otherwise copied without prior permission from Kongsberg Maritime AS.

Kongsberg Maritime AS

Strandpromenaden 50
P.O.Box 111
N-3191 Horten,
Norway

Telephone: +47 33 02 38 00
Telefax: +47 33 04 47 53
www.kongsberg.com
E-mail: subsea@kongsberg.com



KONGSBERG

Note

Kongsberg Maritime AS makes every effort to ensure that the information contained within this document is correct. However, our equipment is continuously being improved and updated, so we cannot assume liability for any errors which may occur.

Warning

The equipment to which this manual applies must only be used for the purpose for which it was designed. Improper use or maintenance may cause damage to the equipment or injury to personnel. The user must be familiar with the contents of the appropriate manuals before attempting to install, operate or maintain the equipment.

Kongsberg Maritime AS disclaims any responsibility for damage or injury caused by improper installation, use or maintenance of the equipment.

Copyright

© 2004 Kongsberg Maritime AS

The information contained within this document remains the sole property of Kongsberg Maritime AS. No part of this document may be copied or reproduced in any form or by any means, and the information contained within is not to be communicated to a third party, without the prior written consent of Kongsberg Maritime AS.

Contact information

Support: hydrographic.support@kongsberg.com

Sales: subsea@kongsberg.com

24 hrs support telephone: +47 99 20 38 01

Kongsberg Maritime AS

Strandpromenaden 50
P.O.Box 111
N-3191 Horten,
Norway

Telephone: +47 33 02 38 00
Telefax: +47 33 04 47 53
www.kongsberg.com
E-mail: subsea@kongsberg.com



KONGSBERG

Sections

This book is the maintenance manual for the EM 3000 multibeam echo sounder. It describes how to perform intermediate maintenance on the system.

1 Introduction

This section presents a general introduction to the echo sounder system, and defines the maintenance philosophy. Refer to page 1.

2 Technical specifications

This chapter presents the main technical specifications. Refer to page 6.

3 Cable layout and interconnections

This chapter describes the cabling, and details the necessary cable specifications. Refer to page 10.

4 Processing Unit

This chapter describes the design and operation of the Processing Unit. Each circuit board is explained, as well as overall block diagrams and the theory of operation. Refer to page 53.

5 Sonar Head

This chapter gives a description of the design and operation of the Sonar Head. Each circuit board is explained, as well as overall block diagrams and the theory of operation. Refer to page 89.

6 Troubleshooting

This chapter provides basic procedures for automatic and traditional troubleshooting. Refer to page 99.

7 Replacement procedures

This chapter explains how to perform replacement of the line replaceable units (LRU). Refer to page 161.

8 Datagram formats

The formats for data input and output to and from the EM Series multibeam echo sounders are described here. Refer to page 167.

9 System administration

This chapter provides basic information useful for the EM 3000 system supervisor. Refer to page 210.

10 Spare parts

This chapter provides a listing of the line replaceable units with illustrations and order numbers. Refer to page 247.

11 Drawing file

Remarks

References

Further information about the EM 3000 system may be found in the following manuals:

- EM 3000 Operator manual
- EM 3000 Installation manual

The reader

This maintenance manual is intended to be used by a trained maintenance technician or engineer, with experience of electronic and digital circuitry, computers and electromechanical design. The level of information is based on Kongsberg Maritime's maintenance philosophy: The onboard technical personnel shall, with the help of the documentation and the system's built-in test functions, be able to identify malfunctions, locate the fault, and replace major parts, modules and components on the "Line Replaceable Unit" (LRU) level. He/she will however not attempt to repair the LRUs.

Note

This manual is issued according to a registered distribution list. In the event of changes to this manual, only authorized copies with copy numbers will be updated.

Table of Contents

1	INTRODUCTION	1
1.1	Overview	1
1.2	Maintenance philosophy	1
1.3	Overview	3
1.4	Processing Unit hardware overview	4
	“New” PU*	4
	“Old” PU*	4
	General	4
2	TECHNICAL SPECIFICATIONS	6
	Overall specifications per Sonar Head	6
	Transmitter	6
	Receiver and beamformer	6
	Interfaces	7
	Physical specifications	7
3	CABLE LAYOUT & INTERCONNECTIONS	10
3.1	Introduction	10
3.2	System cabling	11
	Cable layout	11
	Cable specifications	11
	HWS 10 Operator Station cables	12
	Ordinary Operator Station cables	15
	Processing Unit cables	19
3.3	AUV Processing Unit Cable specifications	23
	Power cables	23
3.4	Sonar Head connection to AUV Processing Unit	24
	Sonar Head cable	24
	Internal wiring inside the bottle	24
3.5	Cable terminations	24
	Generic RS-232 serial line (DCE)	25
	Generic RS-232 Serial line	26
	Generic coax cable	27
	Generic RS-232 with CTS and RTS	28
	Sound speed probe interface	29
	RS-232 Serial line with Trigger signals	30
	RS-485 Serial line and power	31
	Mini Coax	32

	EM Remote synchronisation and On/Off	33
	Standard AC power cable	34
	EMC ground	35
	Ethernet with RJ-45	36
	Ethernet with IEEE 802.3	37
	Standard USB cable	38
	VGA Display cable	39
	Keyboard cable	40
	Mouse or pointing device cable	41
	Centronics printer cable	42
	Digital Video Interface (DVI) display cable	43
	W600 - Remote synchronization	44
	W801 - Sonar Head cable	45
3.6	Sonar Head cable drawings	46
	Standard Sonar Head cable	47
	AUV Sonar Head cable	48
4	OPERATOR STATION HWS 10	49
4.1	Description and main functions	49
	Overview	49
4.2	Theory of operation	51
	Overview	51
	Software	51
	Data storage	51
4.3	Installation	52
5	PROCESSING UNIT	53
5.1	Description and main functions	53
	Overview	53
5.2	Standard Processing Unit drawing	54
5.3	AUV Processing Unit drawing	55
	Circuit boards and modules	56
	AUV Processing Unit Circuit boards and modules	58
5.4	Theory of operation	59
	Overview	59
	Simplified block diagram	59
	Control functions	60
5.5	Circuit board descriptions	63
	Overview	63
	Serial Line Board (CI-104JS)	64

	4-Ports Serial Line Board (C114P)	66
	Control Processor Unit board	68
	VIPer 629 Control Processor Board	73
	Cool Monster C3/400	
	Control Processor Board, AUV PU	74
	ROM board	76
	Beamformer & Signal Processor (BSP)	77
	Beamformer Interface Board (BIFB)	80
	Passive Backplane BP-10S	83
	Ethernet Adapter	85
	Processing Unit Power Supply	88
6	SONAR HEAD	89
6.1	Description and main functions	89
	Overview	89
6.2	Sonar Head drawings	90
6.3	Circuit boards descriptions	91
	Circuit boards descriptions	91
6.4	Theory of operation	92
	Overview	92
	Simplified block diagram	92
	Control functions	93
6.5	Sonar Head details	94
	Circuit boards and modules	94
	HCT board	95
	HRX board	97
7	TROUBLESHOOTING	99
7.1	Messages (for UNIX only)	99
	Introduction	99
	Setup messages	101
	ESO messages	110
	Launchpad messages	114
	Sound Speed Profile Editor messages	137
	Ping Display messages	139
7.2	CMOS SETUP - AUV Processing Unit	140
	Setup for Cool Monster (C3/400)	140
7.3	CMOS SETUP - standard Processing Unit	146
	Setup for VIPer	146
	Processing Unit messages	152
7.4	CPU CMOS SETUP	154

Setup for SSC-486H	154
Setup for SSC-5x86H	156
7.5 BIST tests	159
8 REPLACEMENT PROCEDURES	161
8.1 Introduction	161
Overview	161
Tools required in general	162
Tools required for changing boards in the Sonar Head	162
8.2 Processing Unit procedures	163
Overview	163
Circuit boards and modules	163
Fans	164
Power Supply	164
8.3 Sonar Head procedures	165
Overview	165
9 EM DATAGRAM FORMATS	167
9.1 Introduction	167
9.2 Presentation format	167
9.3 Input datagrams	168
Introduction	168
Position	168
Attitude data	175
Clock	178
Sound Speed	179
Depth input from single beam echo sounder	183
Remote control	184
9.4 Output datagrams	186
Introduction	186
Depth	187
Raw range and beam angle (new)	190
Raw range and beam angle	192
Seabed image	192
Position	194
Depth (pressure) or height	195
Tide	196
Attitude	196
Heading	197

Clock	198
Surface sound speed	198
Sound speed profile	199
Kongsberg Maritime SSP output	200
Single beam echo sounder depth	200
Runtime parameter	201
Installation parameters	205
10 SYSTEM ADMINISTRATION (UNIX)	210
10.1 Introduction	210
10.2 Passwords	211
EM 3000 Installation setup	211
10.3 EM 3000 File system	212
Introduction	212
Survey files	212
Sound speed profiles	212
Absorption coefficient file	213
Workstation I/O	213
Echo sounder parameters	213
BIST files	214
Logfiles	215
Operator configuration files	215
Survey jobs	216
TOC files	216
Helmsman Display	216
10.4 File formats	218
Introduction	218
Survey format and I/O library	218
The survey format	218
10.5 Survey Predefined Files	235
Introduction	235
File locations	235
Using the Survey Predefined Files	235
10.6 Projection data	236
Scope and purpose	236
Projection overview	236
Projection protocol	236
Notes	238
10.7 Dynamic Projection Library	240

Introduction	240
Overview	240
Dynamic projection library definitions	240
Dynamic projection library protocol	240
Example	241
Notes	246
11 SPARE PARTS	247
11.1 Overview	247
11.2 Spares data presentation	247
Spares table	247
Parts list codes	248
11.3 Operator Station (HWS 10) spare parts	249
11.4 Processing Unit spare parts	250
Standard Processing Unit spare parts	251
AUV Processing Unit spare parts	252
11.5 Sonar Head spare parts	253
12 DRAWING FILE	254
12.1 Introduction	254
12.2 Drawing list	254

High voltage safety warning

The voltages used to power this equipment are potentially lethal. Even 110 volts can kill.

Whenever possible, the following precautionary measures should be taken before any work is carried out inside the equipment:

- Switch off all high-voltage power supplies.
- Check the operation of any door interlocks and any other safety devices.
- Completely discharge all high-voltage capacitors.

It should be noted that interlocks and safety devices are normally located only at regular access points, and high voltages may be exposed during dismantling.

NEVER WORK ALONE ON HIGH-VOLTAGE EQUIPMENT!

FIRST AID IN THE EVENT OF ELECTRIC SHOCK

Normally, even a high voltage electric shock will not kill instantly. The victim can still be revived even when his breathing and heart-beat have ceased.

Could **YOU** save someone's life? In the event of electric shock, the correct actions, performed quickly may well save the victim's life. **Make sure you know what to do!**

Immediate action

While shouting for help, remove the source of power from the victim. Switch off the supply if possible, or using a dry, non-conductive material (rubber gloves, broom handle etc.) to insulate yourself, separate the victim from the source. If the voltage exceeds 1000 volts, switch off the supply and be ready to catch the victim. Take care- do not become a victim yourself.

Commence first aid on the spot. Continue to shout for assistance till someone arrives.

- 1 Lay the victim flat on his back and loosen any tight clothing (collar, tie, belt etc.).
- 2 Open his mouth and check for and remove any false teeth, chewing gum etc.
- 3 Check if the victim is breathing. If not, check if his heart is beating. The pulse is normally easily found in the main arteries of the neck, either side of the throat, up under the chin.

If his heart is beating but he is not breathing, commence **ARTIFICIAL RESPIRATION**. If the victim's heart is not beating, commence **EXTERNAL CARDIAC MASSAGE (ECM)**. Continue to shout for assistance till someone arrives.

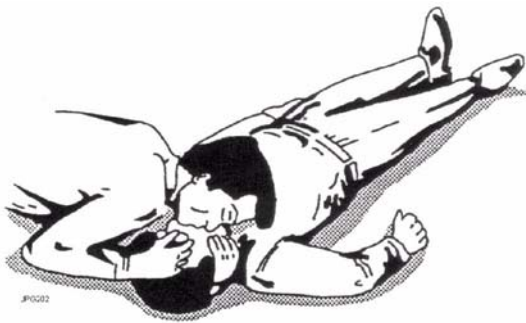
EXTERNAL CARDIAC MASSAGE

- 1 Kneel beside the victim. Place the heel of one hand in the centre of his chest, at a position half way between the notch between the collar-bones at the top of his chest, and the dip in the breast-bone at the base of his rib cage. Place the other hand on top of the first.
- 2 Keeping the arms straight and using your entire weight, press down rapidly so that the breast bone is depressed four- five cm, then release the pressure. Repeat rhythmically at a rate of one cycle per second. This will be hard work, but keep going. His life depends on **YOU**. Do not worry about breaking his ribs - these will heal if he survives.



ARTIFICIAL RESPIRATION

- 1** Kneel beside the victim's head. Place one hand under his neck and lift, allowing his head to fall back. This will lift his tongue and open the air passage in his throat.
- 2** Place the palm of the hand on his forehead to maintain the "chin-up" position.
- 3** Using the index finger and thumb of the same hand, pinch the victim's nostrils closed. Open his mouth.
- 4** Take a deep breath and cover his mouth with yours. Blow steadily into his lungs to expand his chest. Remove your mouth from his to allow the air to escape from his chest. You should be able to see his chest deflate.
- 5** Repeat the "inflation-deflation" cycle at a rate of about 12 cycles per minute till the victim begins to breath normally again.



COMBINING EMC AND ARTIFICIAL RESPIRATION

If you are alone, perform **ONE** cycle of artificial respiration for every **FIVE** cycles of EMC. This will be hard work, but keep going. His life depends on **YOU**!

If there are other people available to help, one should perform the EMC while one performs the artificial respiration for every five cycles of EMC. It will be much more efficient with two people.

Once the victim's heart is beating and he is breathing, roll him onto his side and support him in that position. As consciousness returns he may vomit, and this will allow any liquid to drain out of his mouth.

Remove the victim to a hospital as soon as possible, but do not interrupt the artificial respiration and EMC cycles till his heart beat and breathing returns.

If started quickly and performed correctly, the resuscitation methods described will keep a sufficient volume of oxygenated blood flowing through the victim's body to allow full recovery.

Proficiency in the resuscitation methods can only be achieved through training. All personnel concerned should attend courses on a regular basis. Remember, someone's life could depend on you.



DO YOU KNOW WHAT TO DO?

1 INTRODUCTION

1.1 Overview

This is the maintenance manual for the EM 3000 multibeam echo sounder system.

Note

This manual is common for the AUV Processing Unit and the Standard Processing Unit.

The manual contains detailed descriptions of each of the units in the system. Each circuit board and mechanical assembly is described. The manual also describes the troubleshooting process based on the Built-In Self test (BIST) software, and it includes procedures for disassembly and reassembly of the replaceable items.

This manual does not describe the maintenance of the Operator Station and the peripheral devices (printers, plotters and sensors). For information about these items, refer to the applicable manufacturer's documentation.

1.2 Maintenance philosophy

Kongsberg Maritime AS defines three levels for maintenance manuals:

Organizational - You will only perform limited preventive and corrective maintenance on the system. There is no need for technical education or training, and no need for any instruments. Typical tasks are exterior cleaning, or changing fuses.

Intermediate - You will perform overall preventive and corrective maintenance on the system. It is recommended that you are an educated engineer with experience from computerized design and mechanical systems. It is further expected that you can use standard electronic instruments, such as an oscilloscope. You should be trained by Kongsberg Maritime to perform maintenance on the system. Typical tasks may include troubleshooting, testing and circuit board replacement.

Depot - You will perform detailed maintenance on the system and on the circuit boards and modules. You must be an educated engineer with experience of computerized design and mechanical systems. It is further expected that you can use standard electronic instruments, such as an oscilloscope. You should be trained by Kongsberg Maritime to perform maintenance on the system. Typical tasks are circuit board repair.

Note

This maintenance manual is prepared for the intermediate level.

1.3 Overview

The EM 3000 multibeam echo sounder is the ultimate shallow water mapping and inspection system with respect to high accuracy and resolution.

The minimum operating depth is from less than 1 m below its transducers, and in typical sea water conditions the system operates to more than 150 m depth (less in warm water and more in fresh water). Small dimensions and low weight makes the system portable and easy to install allowing use both on survey launches and subsea vehicles to 1500 m water depth.

The EM 3000 system has a very high ping rate of up to 40 Hz, a large number of measurements per ping (typically about 120), 1.5° beamwidth, and electronic pitch stabilization. 100% coverage of the bottom is achievable at vessel speeds of about 10 knots in shallow waters with across-track coverage of up to four times depth beneath the transducers with a basic system. In deeper waters the achievable coverage may be up to 200 m, and 100% coverage is achievable with vessel speeds up to 20 knots.

The EM 3000 may be configured to use two sets of transducers (Sonar Heads). This increases the shallow water coverage to up to ten times the depth, and the number of measurements per ping to typically 220. With an angular coverage sector of nominally 200° the dual system also allows surveying to the water surface along shorelines, river banks and man-made structures.

The system sonar frequency is 300 kHz allowing small dimensions, good range capability and high tolerance to turbid waters.

Integrated seabed acoustical imaging capability (sidescan) is included as standard as is a nearfield mode for increased resolution in very shallow areas. A combination of phase and amplitude detection is used, resulting in a measurement accuracy of 5 cm RMS being achievable practically independent of beam pointing angle.

The EM 3000 is a complete system with all necessary sensor interfaces, real-time compensation for vessel motion and ray-bending, data displays for quality control including sensor calibration, and data logging included as standard.

Postprocessing software for the EM 3000 is available from both Kongsberg Maritime and third-party suppliers. A world-wide marketing and service organization, having many years of multibeam experience, is available for supporting the EM 3000.

→ A system overview is shown in figure 1.

1.4 Processing Unit hardware overview

The EM 3000 is delivered in different versions. Below is a list of what the different versions are called and what the differences between them are.

* PU = Processing Unit

“New” PU*

The EM 3000 Processing Unit hardware was upgraded summer 2002. The new PU is available as standard rack or desk mount unit and as a unit intended for AUV use.

Registrations numbers:

- 299-218014 (AUV single)
- 125-218079 (single)
- 125-218084 (dual)

Software release 5.1u30A or newer is required to run this hardware.

The CPU board and the serial interface boards are upgraded.

The AUV Processing Unit has all serial interfaces on the CPU board. The number of external serial lines is three, compared to four on the Standard Processing Unit.

The ethernet interface on the new Processing Unit is only available with RJ45 connector.

“Old” PU*

This manual also supports information for the older version of the Processing Unit.

The software release 5.1u30A **will not** run on this hardware.

Registration numbers:

- 125-133927 (single)
- 125-134252 (dual)

General

All Processing Units are clearly labeled with their registration numbers.

The new Processing Unit has a ping rate of up to 40 Hz, while the old Processing Unit is limited to maximum 25 Hz.

Note

*It is **VERY** important that the correct software is installed.*

Note

The appearance of the AUV Processing Unit and the AUV Operating Station is different.

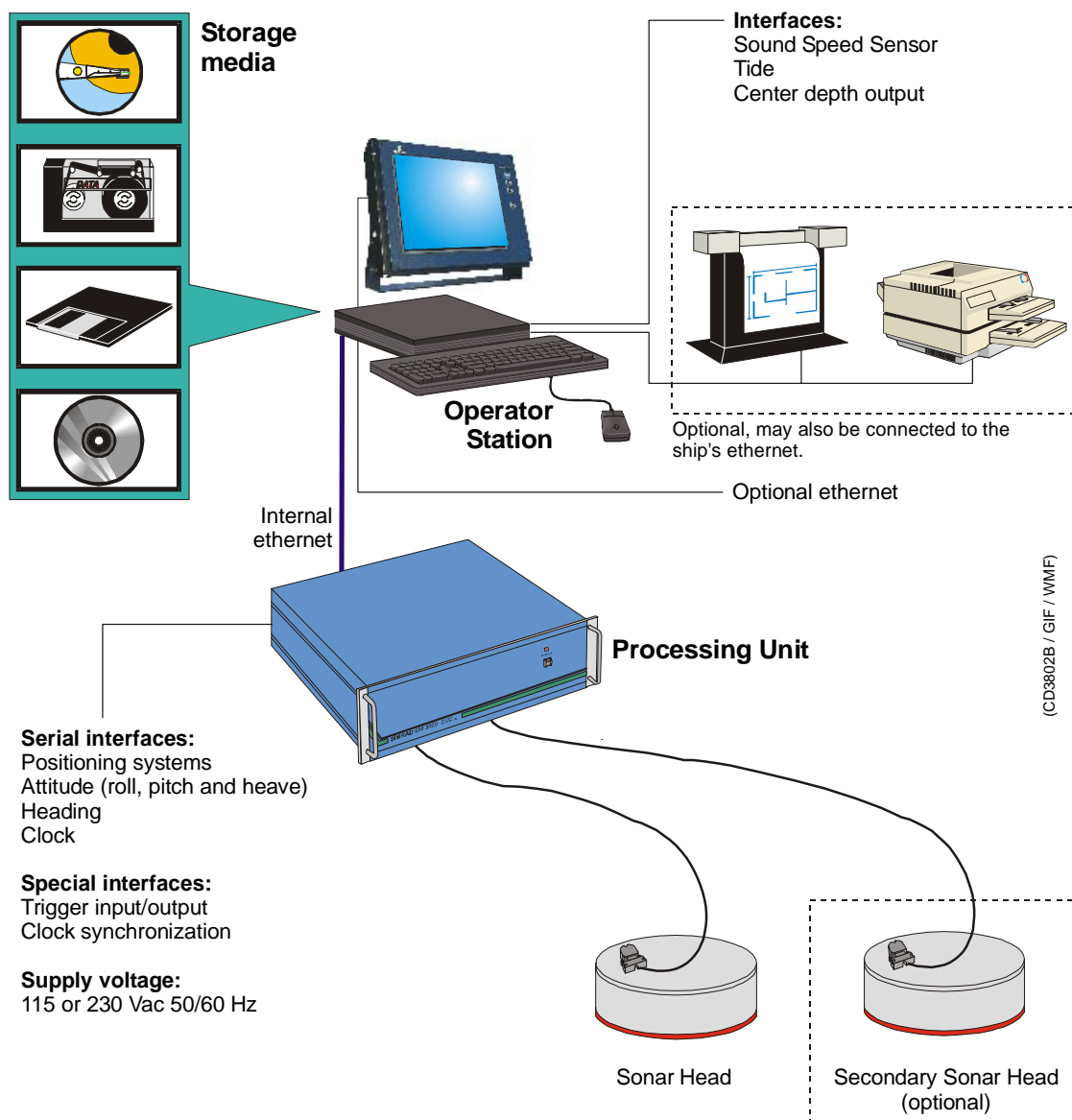


Figure 1 EM 3000 System overview

2 TECHNICAL SPECIFICATIONS

Please note that Kongsberg Maritime is engaged in continuous developments of its products and reserves the right to alter the system specifications without prior notice.

Overall specifications per Sonar Head

Maximum ping rate	40 Hz
Number of beams per ping	max 125
Beamwidth	1.5° x 1.5°
Beamspacing	0.9°
Coverage sector	130°
Transmit beam steering	± 25° in 0.5° steps
Depth resolution	1 cm
Pulse length	150 µS
Range sampling rate	15 kHz (5 cm)
Beamforming method	FFT
Depth range from Sonar Head	< 1m to > 150m (depending upon conditions)
Maximum swath width	> 200m (depending upon conditions)
Depth accuracy	better than 5cm RMS (excluding external sensors)
Data storage rate	40 to 300 MB/h (max at about 10m depth)
Frequency	300 kHz

Note

Frequencies of 293 and 307 kHz are also available, and are used in dual Sonar Head systems.

Both beam width and beam spacing are inversely proportional with the cosine of the beam pointing angle with respect to the Sonar Head (i.e. beam width is 2.1° at ±45° beam pointing angle and 3.0° at ±60°, and beam spacing is 1.3° at ±45° and 1.8° at ±60°)

Transmitter

Alongtrack beamwidth: 1.5° (4° in nearfield mode)

Number of elements in array: 56

Source level: 214 dB/µPa at 1 meter

Sidelobes: < -22 dB

Receiver and beamformer

Acrosstrack beamwidth: 1.5° (4° in nearfield mode)

Beam spacing: 0.9°

Alongtrack beamwidth: 30° (usable to 45°)

Sidelobes: < -20 dB

Range sampling distance: 15 kHz

Number of elements in array: 80 x 3

Bandwidth: 8 kHz

Maximum analog gain: 100 dB

TVG dynamic range: 85 dB

ADC resolution: 12 bits

Interfaces

- Serial lines with operator selectable baud rate, parity, data and stop bit length for:
 - Motion sensor (roll, pitch, heave and optionally heading) in format supported by sensors from Applied Analytics, Seatex and TSS
 - Gyrocompass in either NMEA 0183 HDT or SKR82/LR60 format
 - Positions in either Simrad 90, NMEA 0183 GGA or GPK format
 - Sonar head depth in Digiquartz compatible format
 - External clock in NMEA 0183 ZDA format
 - Sound speed profile
 - Sound speed at transducer
 - Sea level height (tide)
 - Datum height(s)
 - Output of depth straight down in NMEA 0183 DPT format
- Interface for a 1 PPS (pulse per second) clock sync signal
- SCSI interface for tape drive (DAT or Exabyte), additional disk drives, and optional greyscale recorder for seabed imagery.
- Parallel interface for Postscript color graphic printer or plotter.
- Optional Ethernet interface for input of sound speed data and output of all data normally logged to disk and/or tape.

Physical specifications

Sonar Head	
Diameter	332 mm

Height	119 mm (+ 27 mm for connector)
Weight	25 kg (15 kg in water)
Diameter of cable to Sonar Head	17 mm
Connector	Subconn LPBH9F
Material	Titanium
Power	24 Vdc, 1 A (available from the Processing Unit)
Pressure rating	500 m water depth

Note

A Sonar Head with pressure rating of 1500 m water depth is available with the same specifications except for height (121 mm) and a restriction in maximum swath width to 3.5 times depth (120° angular coverage sector).

Standard Processing Unit	
Height	178 mm
Width	448 mm (excluding rack fixing brackets)
Depth	370 mm (excluding handles and connectors)
Weight	10 kg
Power	100 to 240 Vac, < 100 W, 47 to 63 Hz
AUV Processing Unit*	
* external hddisk not included (optional)	
Height	182 mm (including top cover)
Width	140 mm
Depth	421 mm (excluding handles and connectors)
Weight	4.5 kg
Power**	24 - 32 Vdc, 1 A 5 Vdc, 8 A

**** These power measurements are at normal operation. Startup values may be higher. The external power supply must be rated for higher, inrush current. The 5 Vdc power should be rated for minimum 12 A and 24 Vdc for minimum 1.5 A.**

Operator Station

(Dimensions will depend upon choice of workstation model and peripherals. The following figures must serve as a guideline only).

External storage unit height	68 mm
External storage unit width	190 mm
External storage unit depth	310 mm
External storage unit weight	3 kg
Chassis height	103 mm
Chassis width	418 mm
Chassis depth	443 mm
Chassis weight	10 kg
CRT-monitor	
Height	487 mm
Width	475 mm
Depth	506 mm
Weight	31 kg
LCD-monitor	
May vary in size.	
Power	100 to 240 Vac, < 300 W, 47 to 63 Hz

3 CABLE LAYOUT & INTERCONNECTIONS

3.1 Introduction

The standard cables used between the EM 3000 system units and between the units and their external devices are shown here. For larger installations where the EM 3000 is a subsystem, the cables will also be shown in the cable layout plan and interconnection diagram specific for the vessel into which the system is installed.

Note

All cable connections may have to be made in accordance with the guidelines laid down by the vessel's classification society.

If no such guidelines exist, Kongsberg Maritime AS recommends that Det norske Veritas (DnV) Report No. 80-P008 «Guidelines for Installation and Proposal for Test of Equipment» be used as a guide.

3.2 System cabling

Cable layout

The interconnection cables are identified on the cable layout drawings. Each cable is then listed in the corresponding list, which contains the required cable specifications. On the following pages, each cable is identified with the appropriate terminations.

Refer to the Cable layout plan and interconnection diagram on page 12 and to the Processing Unit cable connections diagram on page 19.

Cable specifications

General

Each individual cable is identified on the cable plan. The cables fall into two categories:

- Cables provided by the installation shipyard or owner
- System cables supplied with the delivery

Shipyard cables

The cables that must be provided by the shipyard or owner are identified as such in the tables. Note that the cable specifications given are the *minimum* specifications.

For each cable, the following information is provided:

- Connection to be made on each end of the cable (including system unit, terminal board identification and plug/socket to be used)
- Number of cores
- Recommended cable type
- Minimum cable specifications

The necessary considerations must be taken to suit special requirements. Kongsberg Maritime accepts no responsibility for damage to the system or reduced operational performance if this is caused by improper cabling.

System cables

Several cables will be supplied with the system. Such cables normally comprise power cables for peripheral equipment, and interconnection cables for computers and/or workstations. These cables will normally be delivered with the units.

HWS 10 Operator Station cables

The illustration and the list below specifies each cable used on the EM 3000 Operator Station. References are made to detailed cable drawings.

Note that this information includes several cables that may not be in use on all installations.

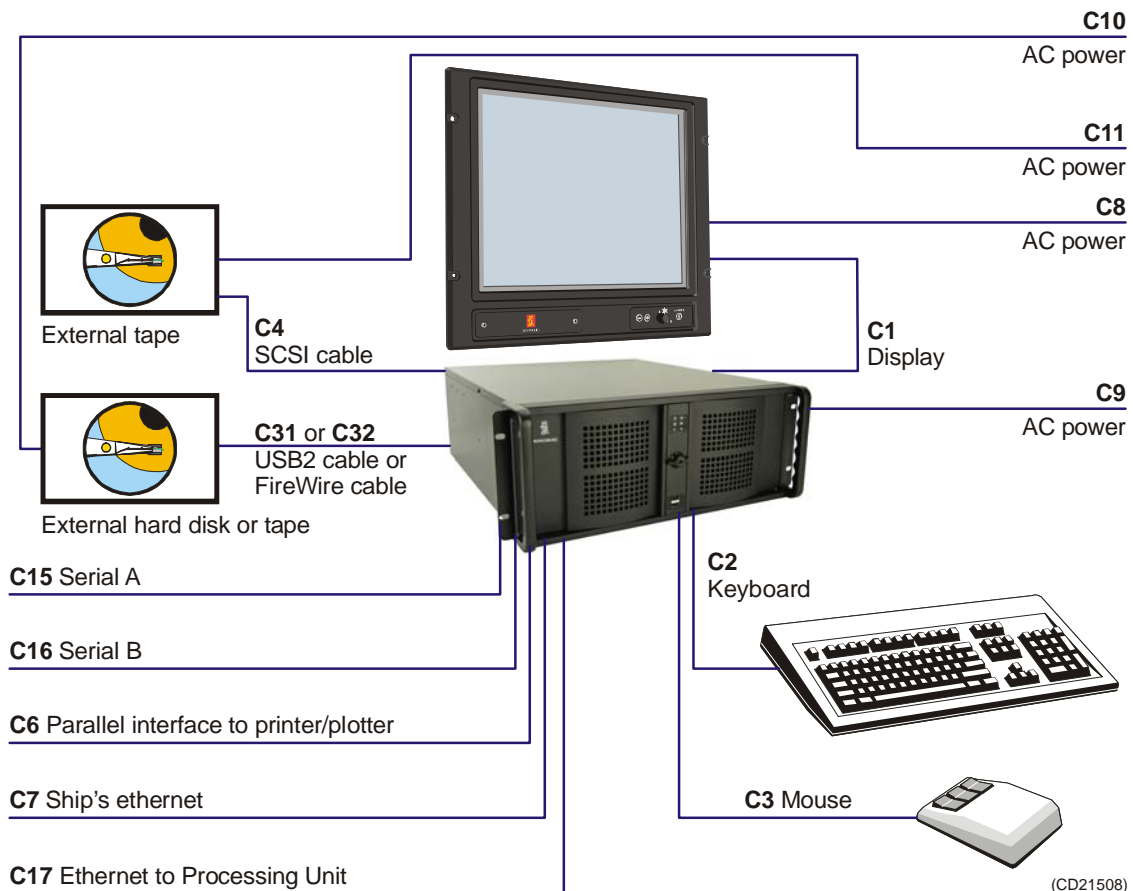


Figure 2 EM 3000 Operator Station - Cable plan

C1 - Display

This is a standard DVI cable. It is normally supplied with the display unit.

→ Cable details on page 43.

Specific installations may include multiple display configurations with video splitters and/or switches.

C2 - Keyboard

This is a standard keyboard cable.

→ Cable details on page 40.

C3 - Mouse or pointing device

This is a standard mouse cable.

→ *Cable details on page 41.*

C4 - SCSI cable

This cable is used only if the Operator Station is used with external SCSI storage devices.

When applicable, the cable is provided by the user.

C6 - Centronics printer

The Operator Station only provides one parallel interface to plotter or printer. In most cases, plotters and printers are connected directly to the ship's ethernet network.

→ *Cable details on page 42.*

When applicable, the cable is provided by the manufacturer.

C7 / C17 - Ethernet

The Operator Station is equipped with two Ethernet ports interface boards, one is used to communicate with the ship's Ethernet (C7) while the other (C17) is used to communicate with the Processing Unit.

→ *Cable details on page 36.*

The Ethernet cable must be provided by the installation shipyard.

C8 / C9 / C10 / C11 - AC power

These are AC mains cables. Note that C10 and C11 are only required if external SCSI storage devices are implemented.

→ *Cable details on page 34.*

All AC mains cables are normally supplied by the manufacturer.

C15 - Serial A

This serial line is intended for a sound speed probe, which is normally interfaced by means of a small junction box and a power supply.

If a sound speed probe is not used, the serial line may be used for other purposes.

→ *Sound speed probe cable details on page 29.*

→ *Standard 9-pin RS-232 serial line details on page 28.*

The cables must be provided by the installation shipyard.

C16 - Serial B

This serial line is intended for a tide sensor. If such a sensor is not used, the serial line may be used for other purposes.

→ *Standard 9-pin RS-232 serial line details on page 28.*

The cable must be provided by the installation shipyard.

C31 - USB cable

This is a standard USB2 cable for connecting external storage devices.

There are four USB ports in the back of the Processing Unit and two USB ports in front. The two USB in front are normally blanked to allow for IP22.

One USB port is used for a software protection dongle.

→ *Cable details on page 38.*

The cable(s) must be provided by the user.

C32 - FireWire cable

This is a standard FireWire cable, connecting a storage device.

There is one FireWire port in the back of the Processing Unit.

The cable must be provided by the user.

Ordinary Operator Station cables

The illustration and the list below specifies each cable used on the EM 3000 Operator Station. References are made to detailed cable drawings.

Note that this information includes several cables that may not be in use on all installations.

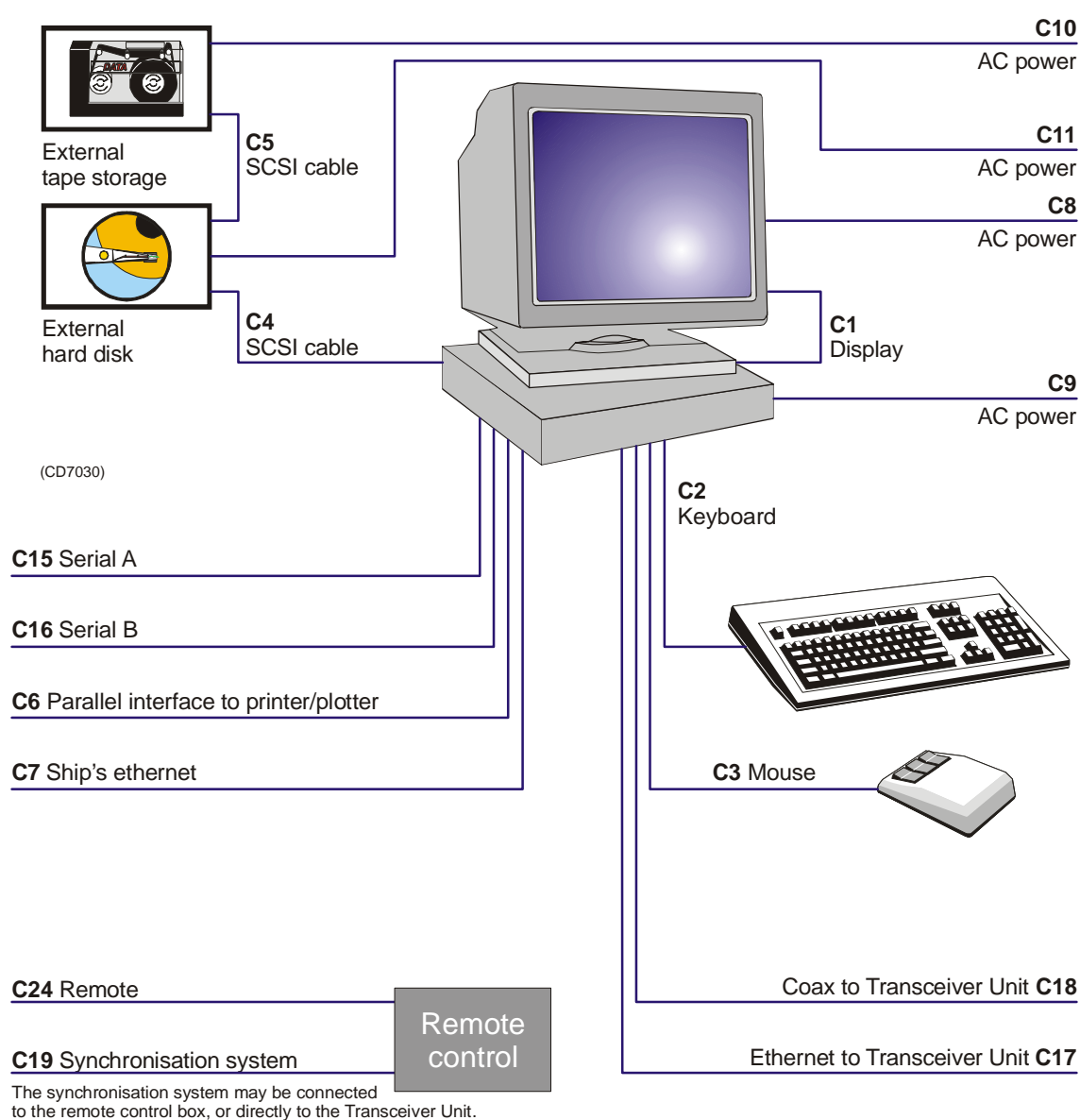


Figure 3 EM 300 Operator Station - Cable plan

C1 - Display

This is a standard VGA cable. It is normally supplied with the display unit.

→ *Cable details on page NO TAG.*

Specific installations may include multiple display configurations with video splitters and/or switches.

C2 - Keyboard

This is a standard keyboard cable. It is normally supplied with the keyboard.

→ *Cable details on page 40.*

C3 - Mouse or pointing device

This is a standard mouse cable. It is normally supplied with the keyboard. Note that different workstation types allow for different mouse connections. On Unix workstations, the mouse is often connected to the keyboard, while most PCs provide a socket on the computer assembly.

→ *Cable details on page 41.*

C4 / C5 - SCSI cables

These cables are used only if the Operator Station is supplied with external SCSI storage devices.

When applicable, the cables are provided by the manufacturer.

C6 - Centronics printer

The Operator Station only provides one parallel interface to plotter or printer. In most cases, plotters and printers are connected directly to the ship's ethernet network.

→ *Cable details on page 42.*

When applicable, the cable is provided by the manufacturer.

C7 - Ship's ethernet

The Operator Station may be equipped with one or two ethernet interface boards. When two -2- boards are provided, one is used to communicate with the ship's ethernet while the other (C17) is used to communicate with the Transceiver Unit.

→ *Cable details on page 36.*

The ethernet cable must be provided by the installation shipyard.

C8 / C9 / C10 / C11 - AC power

These are AC mains cables. Note that C10 and C11 are only required if external SCSI storage devices are implemented.

→ *Cable details on page 34.*

All AC mains cables are normally supplied by the manufacturer.

C12 / C13 / C14 - Not used

For future expansion.

C15 - Serial A

This serial line is intended for a sound speed probe, which is normally interfaced by means of a small junction box and a power supply.

If a sound speed probe is not used, the serial line may be used for other purposes.

→ *Sound speed probe cable details on page 29.*

→ *Standard 9-pin RS-232 serial line details on page 28.*

The cables must be provided by the installation shipyard.

C16 - Serial B

This serial line is intended for a tide/depth sensor. If such a sensor is not used, the serial line may be used for other purposes.

→ *Standard 25-pin RS-232 serial line details on page 25.*

→ *Standard 9-pin RS-232 serial line details on page 28.*

The cable must be provided by the installation shipyard.

C17 - Transceiver Unit RJ-45 interface

The Operator Station may be equipped with one or two ethernet interface boards. When two -2- boards are provided, one is used to communicate with the ship's ethernet (**C7**) while the other (**C17**) is used to communicate with the Transceiver Unit.

The interface between the Operator Station and the Transceiver Unit is made with either C17 or C18. In some cases two parallel ethernet cables may be used. These are then normally identified as C17A and C17B.

→ *Cable details on page 36.*

The cable must be provided by the installation shipyard.

C18 - Transceiver Unit Coax interface

The interface between the Operator Station and the Transceiver Unit is made with either C17 or C18.

→ *Cable details on page 27.*

When applicable, the cable must be provided by the installation shipyard.

C19 - Synchronisation system

Refer to the Processing Unit cabling.

C24 - Remote

Refer to the Processing Unit cabling.

Processing Unit cables

The illustration and the list below specifies each cable used on the EM 3000 Transceiver Unit. References are made to detailed cable drawings.

Note that this information includes several cables that may not be in use on all installations.

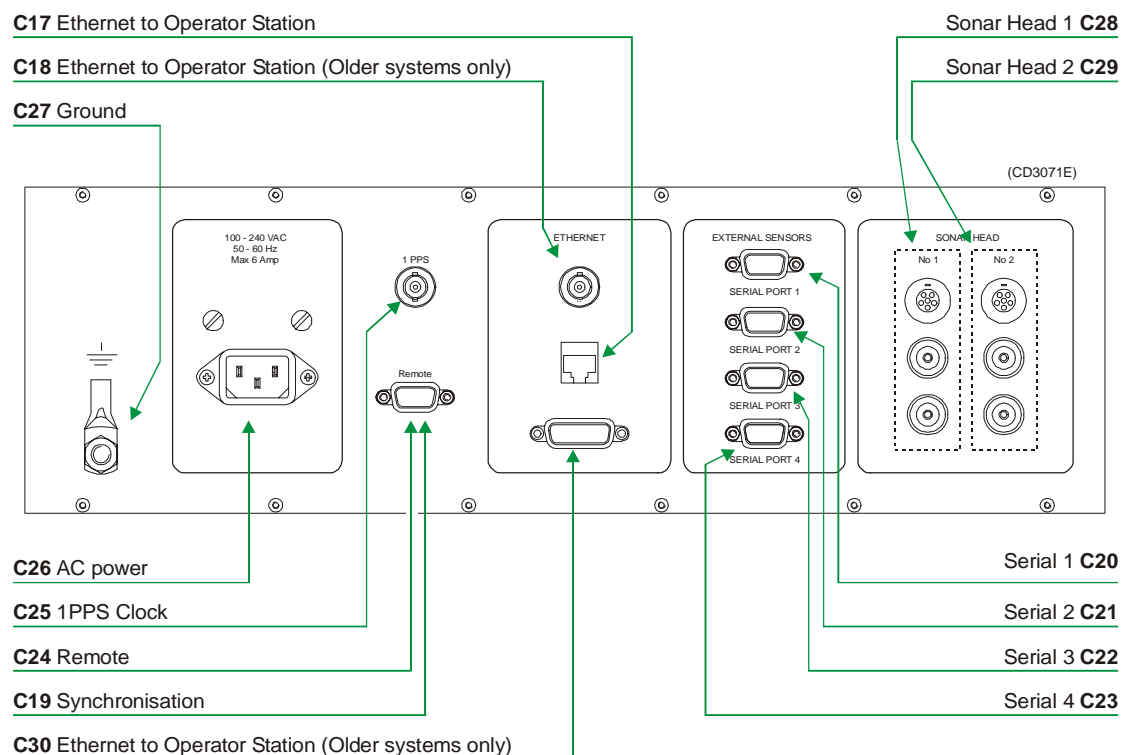


Figure 4 EM 3000 Processing Unit - Cable plan

C17 - Transceiver Unit RJ-45 interface

Refer to the Operator Station cabling.

C18 - Transceiver Unit Coax interface

Refer to the Operator Station cabling.

C19 - Synchronisation

An external system may be used to synchronise the echo sounder's transmissions. This system is connected to the **Remote** plug on the Processing Unit.

In most cases, an external junction box is located in the vicinity of the Operator Station to facilitate on/off control. The synchronisation system may then be connected to this junction box, or directly to the **Remote** plug.

→ *Cable details on page 33.*

The cable must be provided by the installation shipyard.

C20 / C21 / C22 / C23 - Serial lines 1 - 4

The Transceiver Unit is equipped with four serial lines. All connectors are 9-pin male D-connectors. The serial lines are normally set up as follows:

Serial Port 1 - Positioning systems

Serial Port 2 - Motion sensor

Serial Port 3 - Auxiliary 1

Serial Port 4 - Auxiliary 2

→ *RS-232 cable details on page 28.*

The cables must be provided by the installation shipyard.

C24 - Remote

In most cases, an external junction box is located in the vicinity of the Operator Station to facilitate on/off control. The cable from this box is connected to the **Remote** plug on the Processing Unit.

→ *Cable details on page 33.*

The cable must be provided by the installation shipyard.

C25 - 1PPS

This is a timing signal terminated in a coax connector.

→ *Cable details on page 27.*

The cable must be provided by the installation shipyard.

C26 - AC power

This is the AC mains cable to the Processing Unit.

→ *Cable details on page 34.*

The cable is provided by the manufacturer.

C27 - Ground

This is a standard ground cable.

→ *Cable details on page 35.*

The cable must be provided by the installation shipyard.

C28 / C29 - Sonar Head cable(s)

The Sonar Head cable is a special cable. There is one cable for each Sonar Head, and it is terminated in three plugs. These are colour coded.

→ *Cable details on page 45.*

The Sonar Head cable is provided by the manufacturer.

C30 - Operator Station interface

This interface is made using an AUI connector. It is only used on older EM 3000 system.

→ *Cable details on page 37.*

When applicable, the cable must be provided by the installation shipyard.

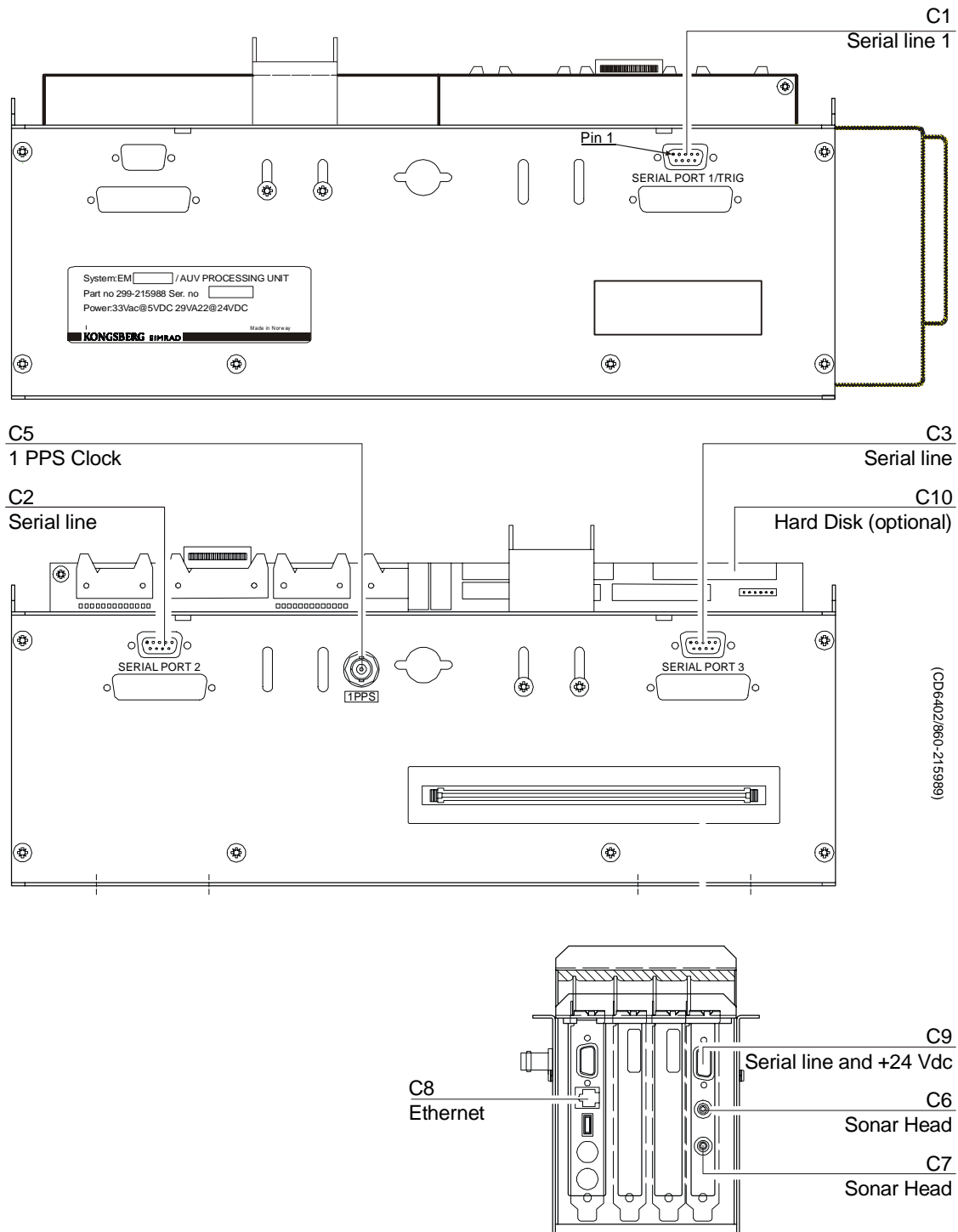


Figure 5 Cable plan - AUV Processing Unit

3.3 AUV Processing Unit Cable specifications

The cables identified in the cable plan are listed here. Each cable is identified with a cable identifier (Cxx). References are made to dedicated specification sheets with cable details and connections.

MFS = Manufacturer supply

ID	Specifications	From/To	MFS
C1	Page 30	Serial line 1, trigger	
C2	Page 26 (Note 3)	Serial line 2	
C3	Page 26 (Note 3)	Serial line 3	
C5	Page 27	1 PPS clock	
C6	Page 32 (Note 2)	Transducer cable to Sonar Head	
C7	Page 32 (Note 2)	Transducer cable to Sonar Head	
C8	Page 36	Ethernet, RJ45	
C9	Page 31 (Note 2)	Serial line and +24Vdc to Sonar Head	
Optional cables			
C10	(Note 1)	External hard disk	

Note 1 - This is a standard hard disk cable. The physical properties of these cables are not specified in this documentation.

Note 2 - The connection is described below and on page 48. These signals must be connected to a watertight plug. The Sonar Head cable delivered with the system must be modified with a new connector to fit this plug.

Note 3 - Some sensors may require RTS and CTS.

→ Refer to cable description on page 28.

Power cables

The AUV Processing Unit uses +5Vdc and +24Vdc for the Sonar Head. These cables are delivered without connectors.

100 cm cables are supplied by Kongsberg Maritime. They should be shortened as much as possible to minimize voltage drop.

The power cables are brown for +5V and red for +24V. Both use black as ground.

The 5V ground and the 24V ground must be connected together externally.

Note

The 5V power measured at the motherboard terminals should be minimum 5.0Vdc. The 5V power should be rated for minimum 12A and 24V power should be rated for minimum 1.5A.

3.4 Sonar Head connection to AUV Processing Unit

Sonar Head cable

The standard Sonar Head cable delivered by Kongsberg Maritime has three plugs for connection to the standard Processing Unit. These plugs must be substituted by one underwater plug with minimum 10 pins.

A 4 meter cable without connectors in the “Processing Unit end” is available from Kongsberg Simrad.

This can be ordered on registration number:

- 380-212989

Internal wiring inside the bottle

Cabling from the underwater plug to the AUV Processing Unit BIFB board:

- Two mini coax cables must be used for the TAXI high speed up-link.
- A multi wire cable must be used to connect 24 V, RS485 serial line.

Plug and cable specifications (not supplied by Kongsberg Maritime):

- 2 mini coax connectors to plug into the BIFB board.
- 2 mini coax cable for the TAXI link.
- Plug for power and serial link for connection to the BIFB board: standard 9 pins delta plug.
 - Minimums cable dimensions: 0.5 mm².

→ *For more details, refer to figure on page 48.*

3.5 Cable terminations

The termination of all the cables into plugs or terminal blocks are shown on the referenced pages.

Generic RS-232 serial line (DCE)

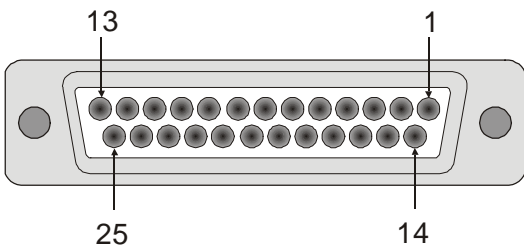
This cable described the pin configuration for an RS-232 interface. The Data Circuit terminating Equipment (DCE) end is shown.

1	Shield
2	Received data (Rx)
3	Transmitted data (Tx)
4	Clear to send (CTS)
5	Request to send (RTS)
6	DCE Ready
7	Signal ground
8	Received line signal detect
9	<i>Reserved for testing</i>
10	<i>Reserved for testing</i>
11	<i>Unassigned</i>
12	Sec. Rx line signal detect
13	Sec. Request to send
14	Sec. Rx data
15	Transmitter signal timing
16	Sec. Tx data
17	Rx signal timing (DCE source)
18	Local loopback
19	Sec. Clear to send
20	DTE Ready
21	Remote loopback
22	Ring indicator
23	Data signal rate selector
24	Tx signal timing (DTE Source)
25	Test mode

25-pin D-sub connector

Original and complete RS-232 signal definition shown. The most commonly used signals are shown in bold.

(DCE = Data Circuit terminating equipment)



Looking into a female 25-pin D-pin connector

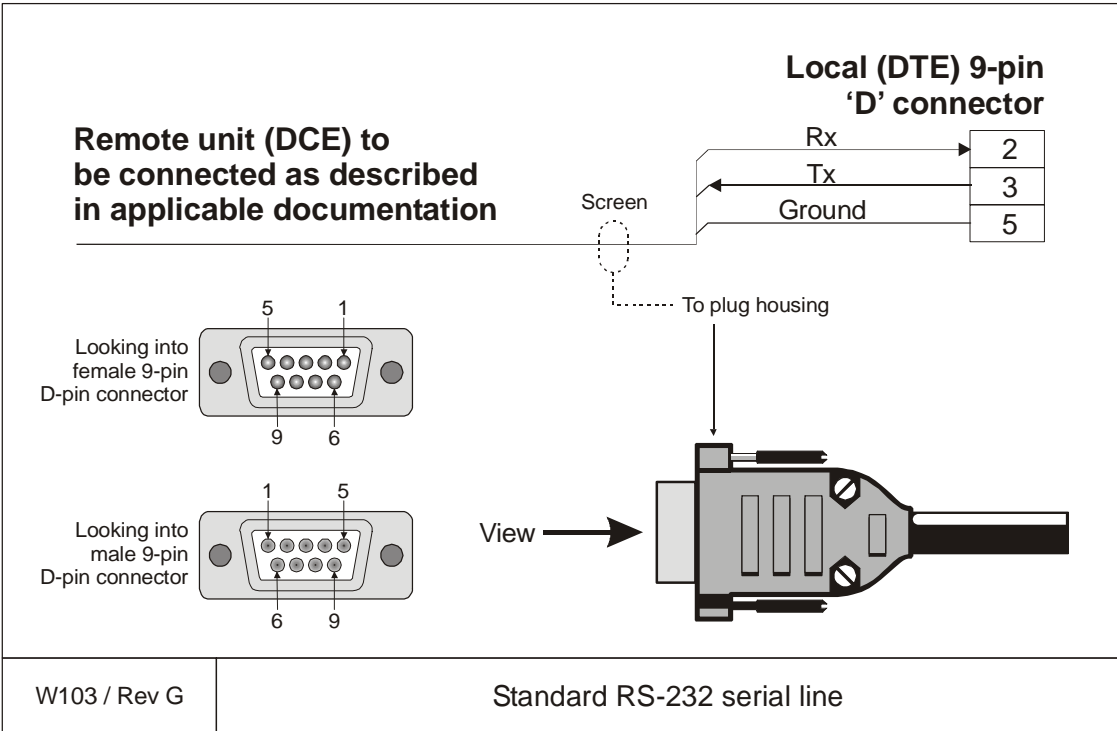
W102 / Rev. B	RS-232 serial line (DCE)
---------------	---------------------------

Conductors	25 x 1 x 0.5 mm ²
Screen	Overall braided
Voltage	60V
Max.diameter	Set by the plugs

Generic RS-232 Serial line

This cable comprises a multi-purpose serial line. It provides interface with any peripheral unit. One end of the cable connects to the local unit (DTE) with a 9-pin 'D' connector, while the other connects to the peripheral (DCE) as described in the peripheral unit's documentation.

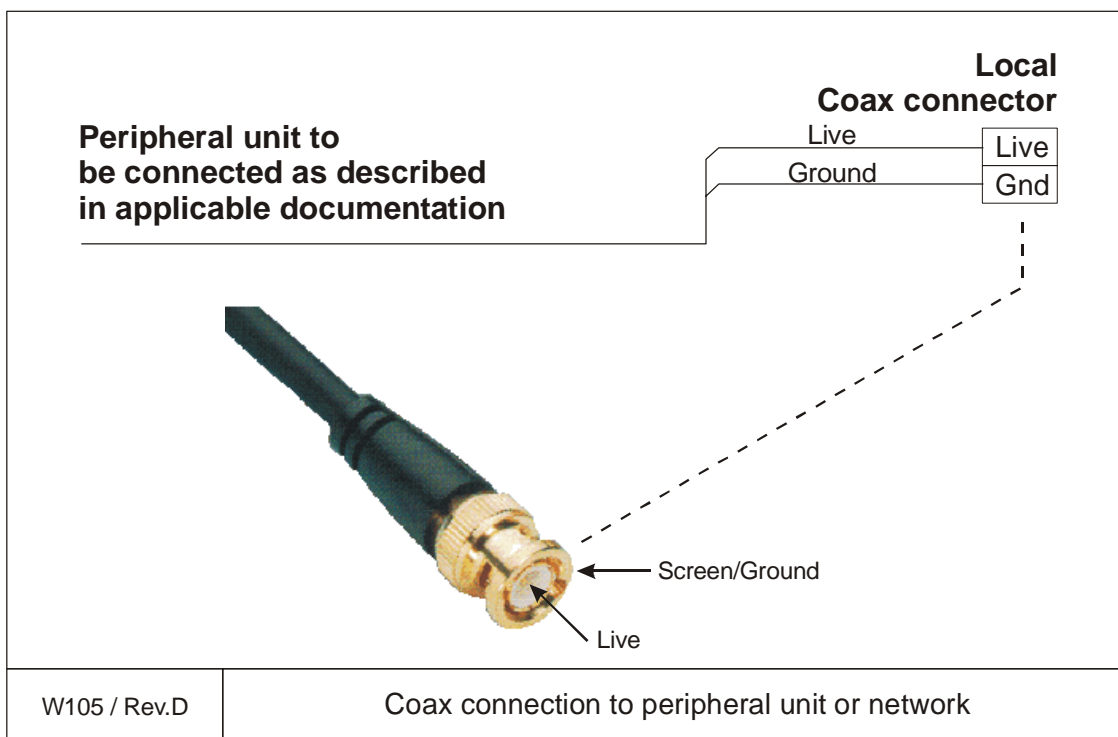
Note that this cable does not support all the signals in the standard RS-232 specification.



Conductors	3 x 2 x 0.5 mm2
Screen	Overall braided
Voltage	60V
Max.diameter	Set by the plugs

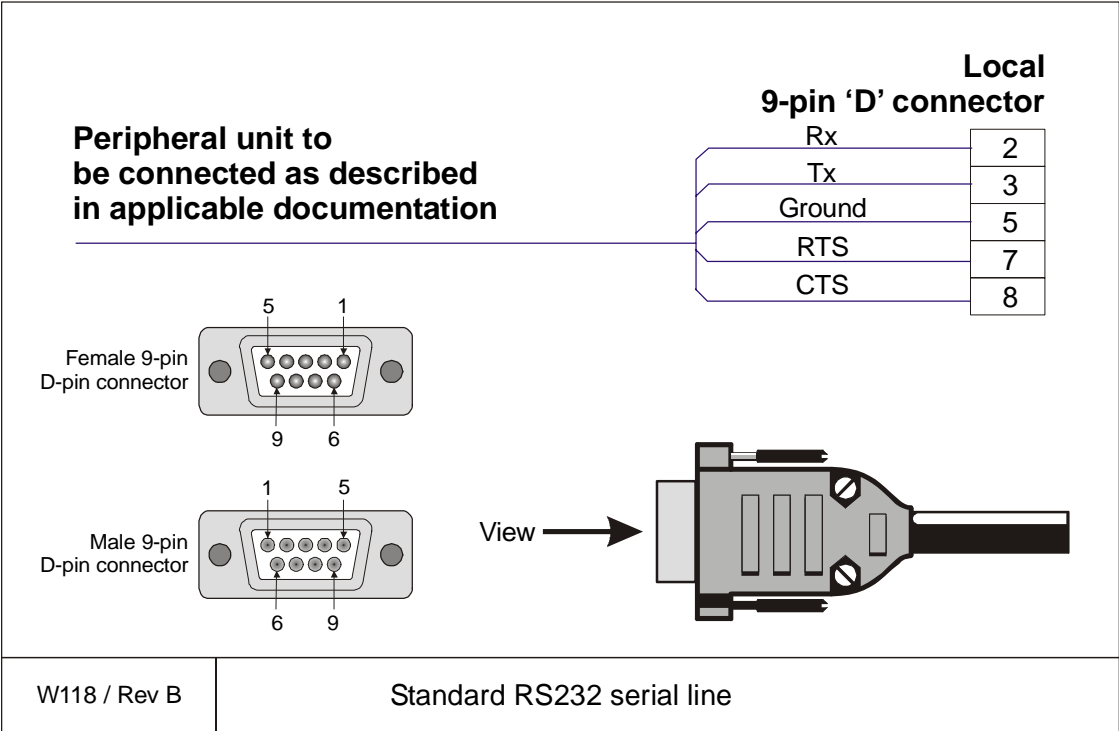
Generic coax cable

This cable is used for connections to peripheral units or networks.



Generic RS-232 with CTS and RTS

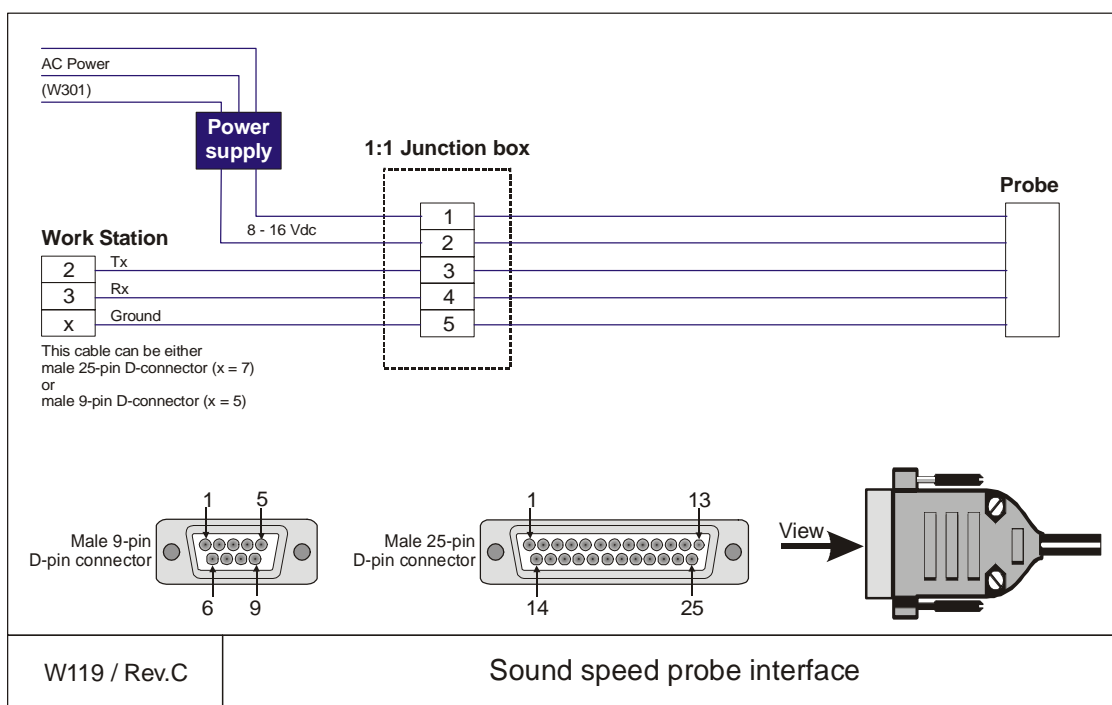
This is a standard serial cable terminated into a 9-pin D-connector.



Conductors	6 x 0.5 mm2
Screen	Overall braided
Voltage	60 V
Max.diameter	Limited by the plugs

Sound speed probe interface

This cable provides the interconnection between the Processor Unit work station and the sound speed probe. This connection is normally made through a small junction box and with a power supply as indicated in the drawing.

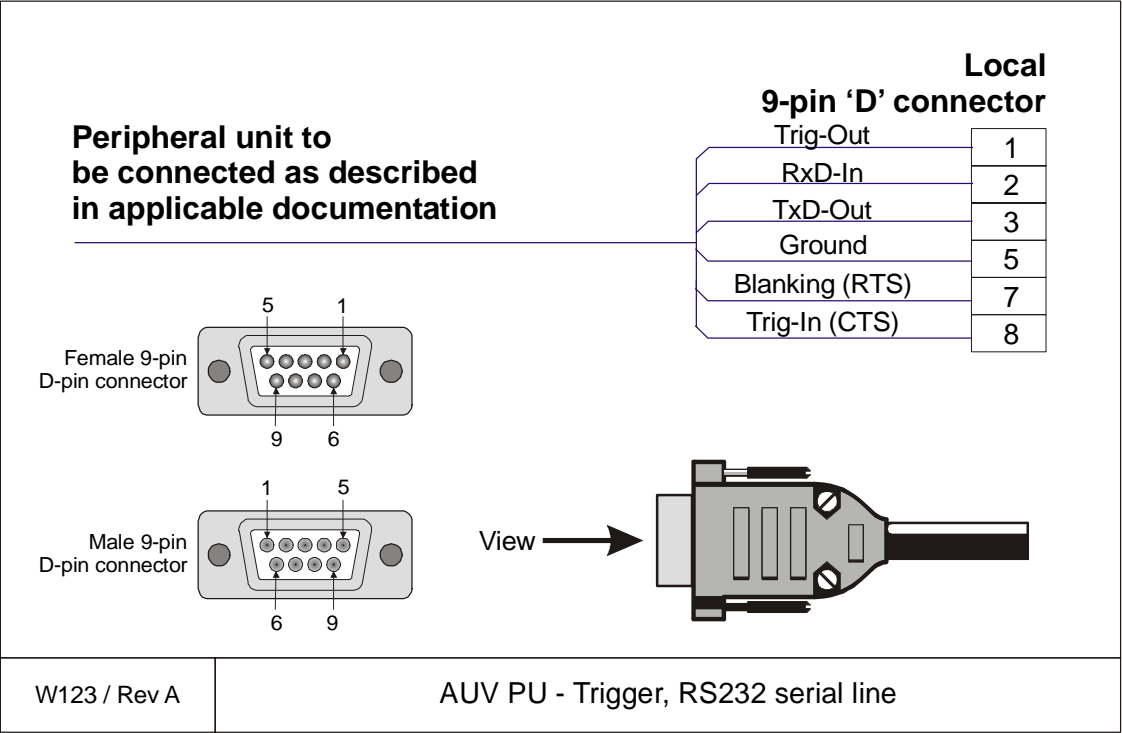


The cable between the junction box and the probe is supplied by the probe manufacturer.

Conductors	2 x 2 x 0.5 mm2
Screen	Overall braided
Voltage	60V
Max.diameter	Set by the plugs

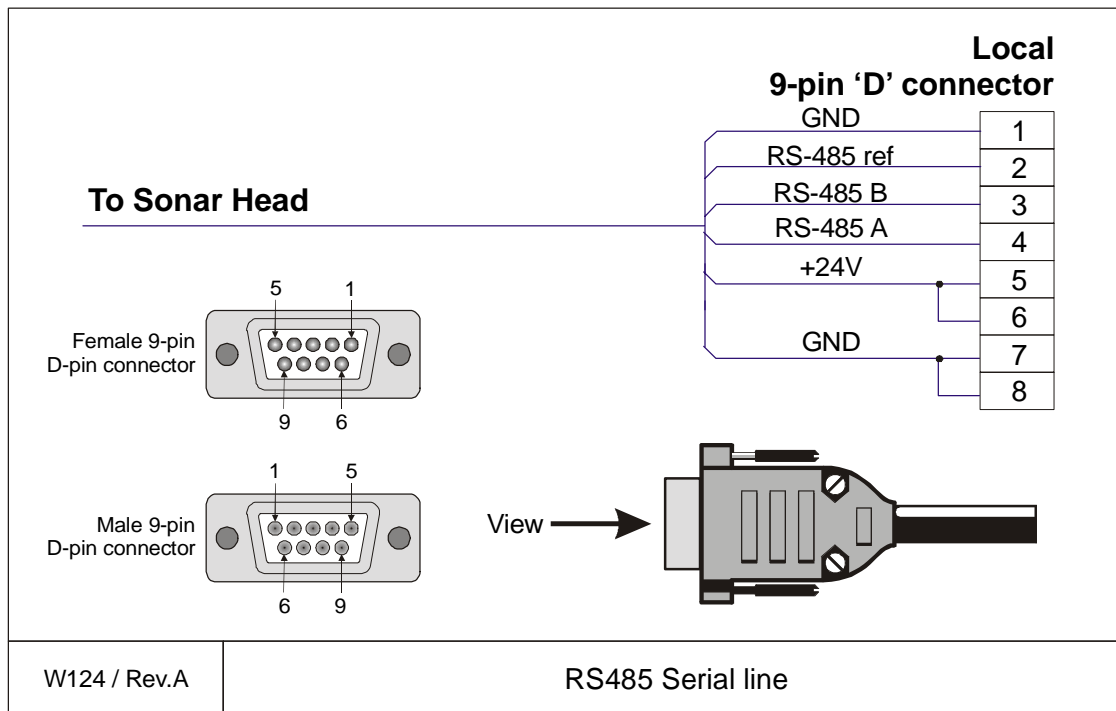
RS-232 Serial line with Trigger signals

This cable is used by the AUV Processing Unit.



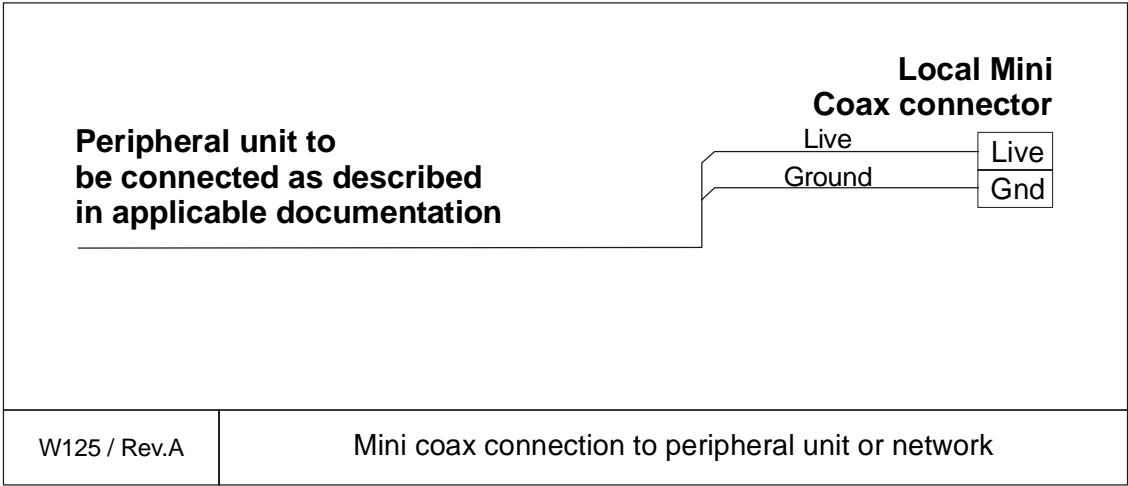
Conductors	6 x 0.5 mm2
Screen	Overall braided
Voltage	60 V
Max.diameter	Limited by the plugs

RS-485 Serial line and power



Conductors	6 x 0.5 mm ²
Voltage	60 V

Mini Coax

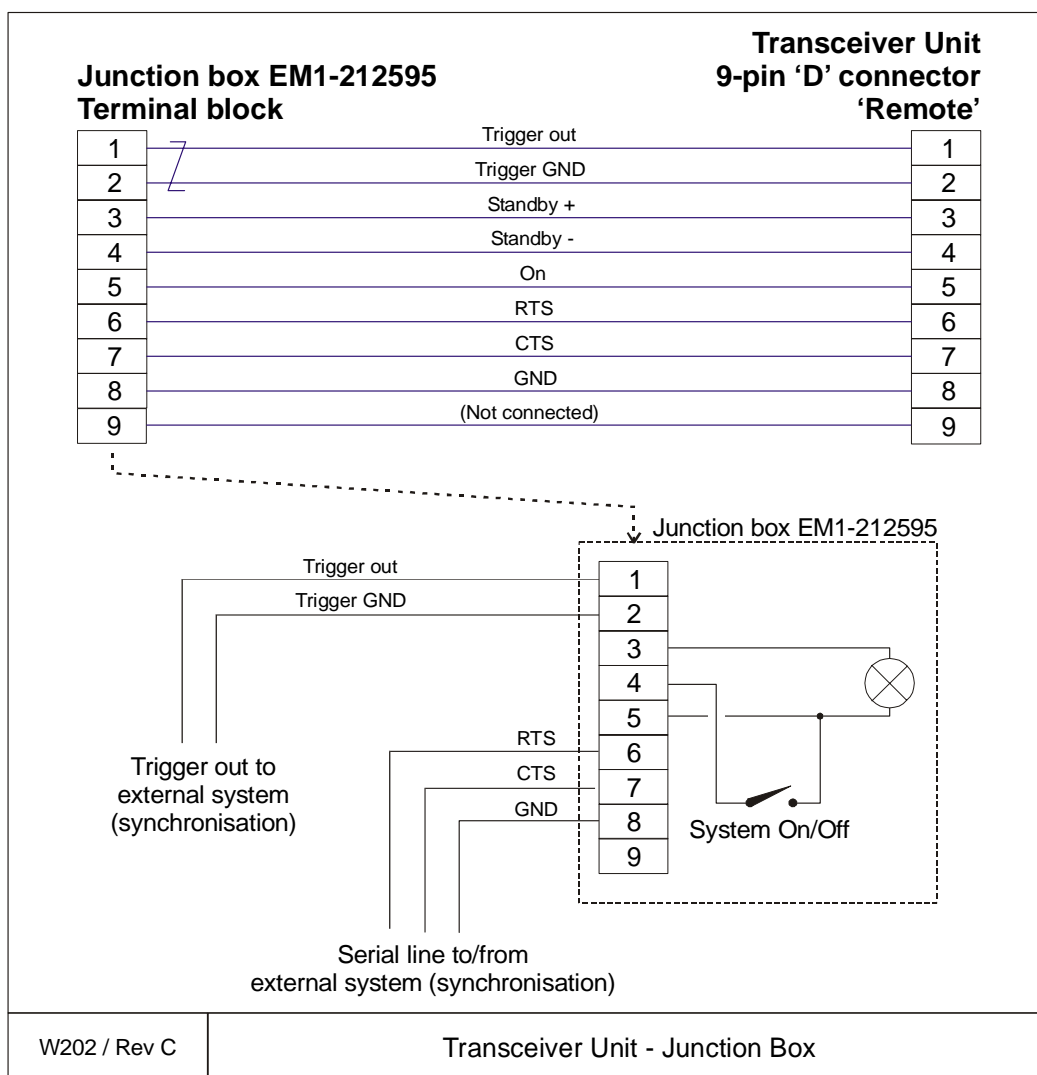


EM Remote synchronisation and On/Off

This cable connects the Transceiver Unit to a remote On/Off switch located in a Remote Control junction box (type EM1-212595). The same connection allows trigger output and remote control (synchronisation) with a serial line.

Note

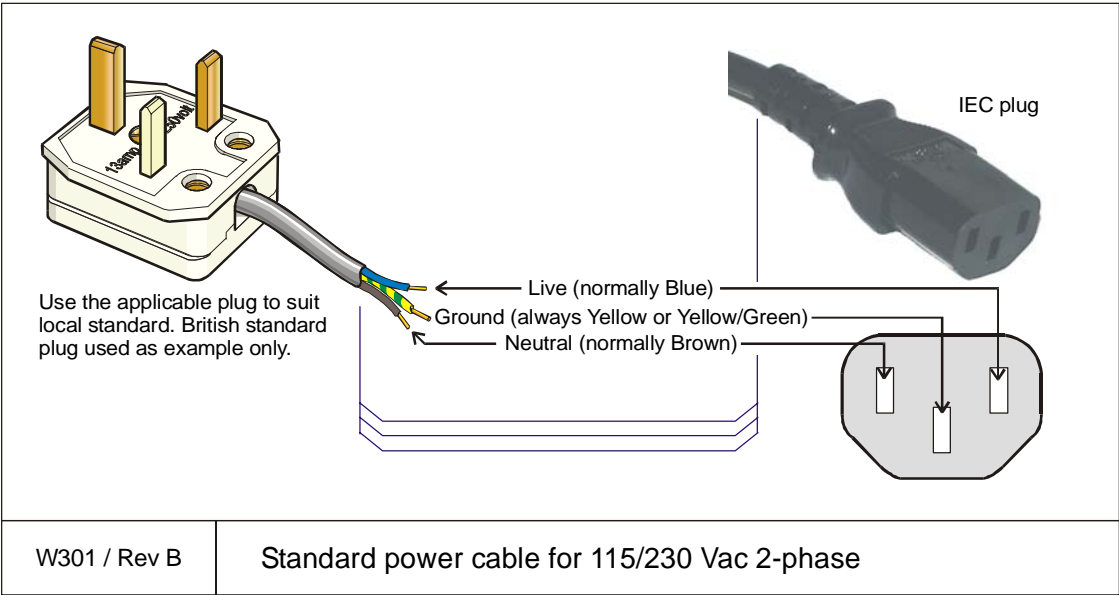
This information is also valid for Remote Control junction box 108-212591.



Conductors	5 x 2 x 0.5 mm ²
Screen	Overall braided
Voltage	60V
Max.diameter	Set by the plugs

Standard AC power cable

This cable is a standard three-wire power cable. It is commercially available in standard lengths, or may be produced locally to suit the specific installation needs. The instrument end is terminated in a standard IEC female socket, while the other end is terminated in a plug suitable for the local standard.



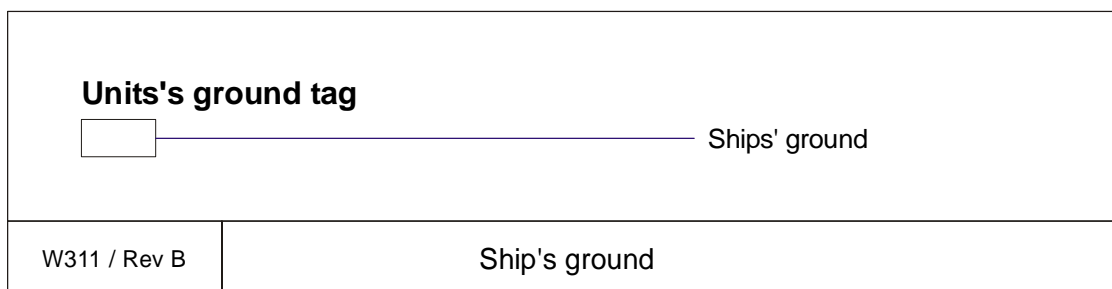
Note *Different cable colours may be used for the “live” and “neutral” wires. Ground is however always on green/yellow.*

Conductors	2 x 1.5 mm ² + GND
Screen	None
Voltage	750 V
Max. diameter	Set by the plugs

EMC ground

This cable is used to connect the system unit to the ship's ground.

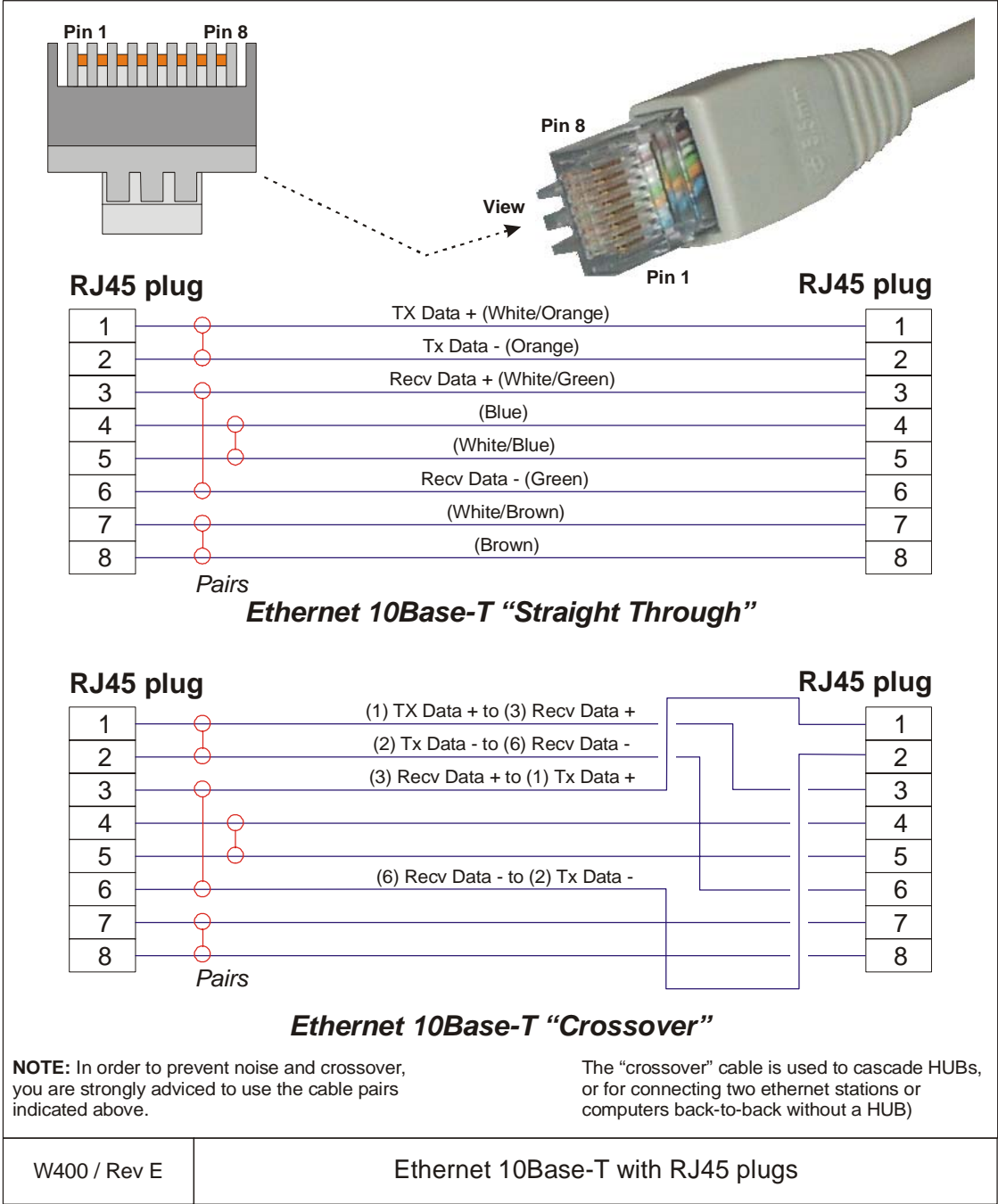
Note that this cable must be as short as possible.



Conductors	1 x 6 mm2
Screen	None
Voltage	60 V
Max.diameter	N/A

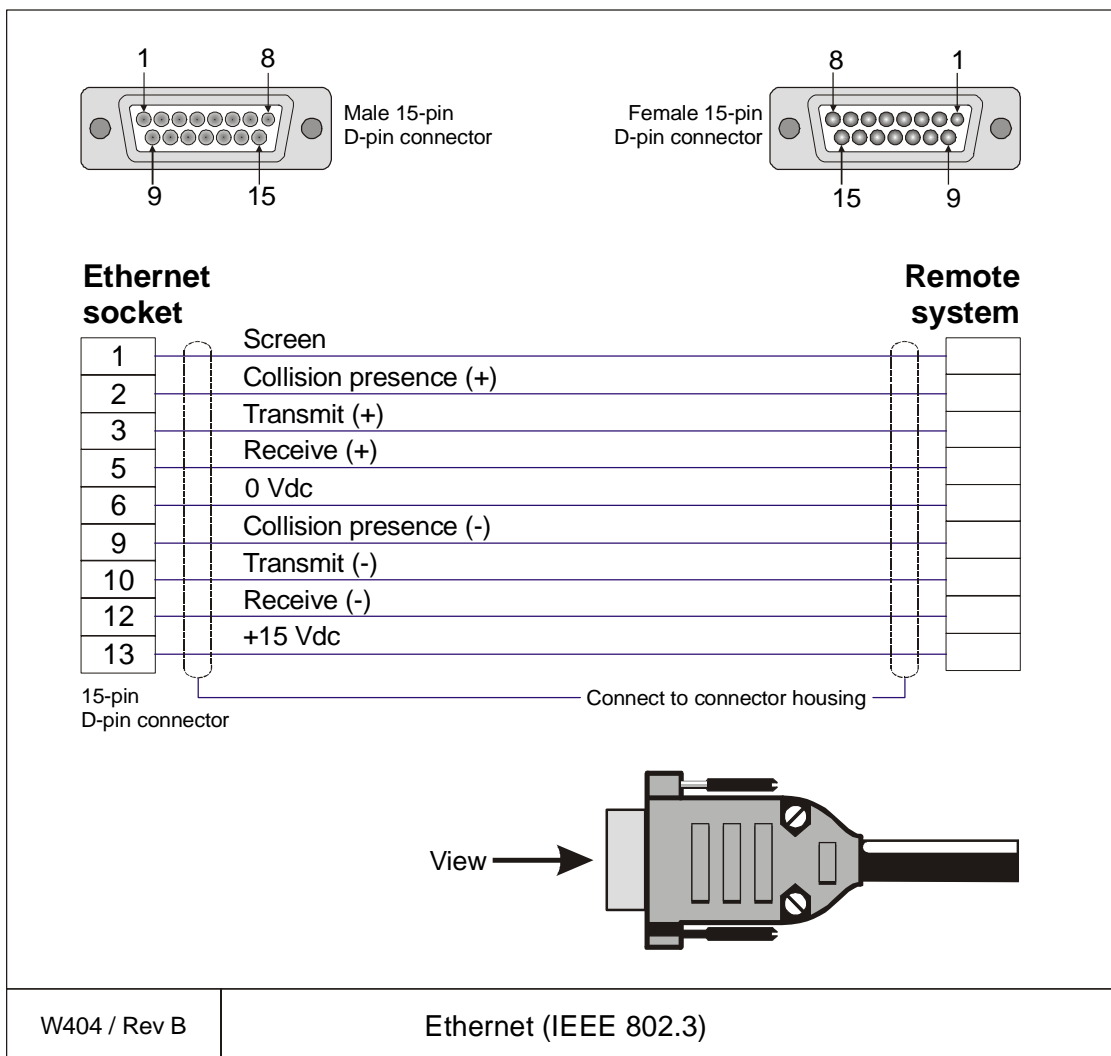
Ethernet with RJ-45

This cable contains the Ethernet connection. RJ-45 plugs are used to terminate the cable. Note that these plugs must be screened to comply to EC rules.



Ethernet with IEEE 802.3

This is a standard ethernet connection. It complies to IEEE 802.3.




Conductors	6 x 0.5 mm ²
Screen	Overall braided
Voltage	60 V
Max.diameter	Limited by the plugs

Standard USB cable

This is a standard commercial USB cable terminated with **A** and **B** plugs in either ends. The cable can be used for most kind of external devices.

The order number provided is for a 4.5 m cable.

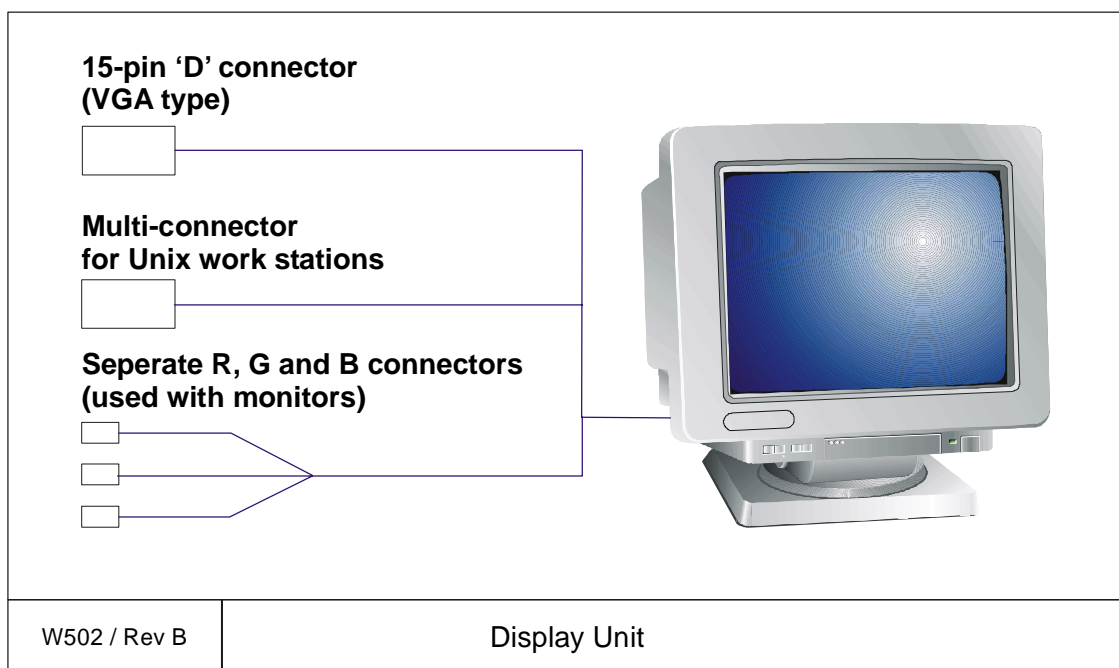
<div><p>Universal Serial Bus (USB) cable terminated with an A-plug in one end and a B-plug in the other.</p><p>Internal cables:</p><p><u>Pair 1:</u> 28 AWG twisted pair (data, green, white)</p><p><u>Pair 2:</u> 20 AWG twisted pair (Power, red, black)</p><p><u>Shield:</u> Foil and braid</p><p>Length: 4.5 m Order no: 719-078524</p></div> <div></div>	
W501 / Rev.A	Commercial USB cable

VGA Display cable

This is a standard display cable used to connect the video signals. Depending on the computer type, the cable may be terminated in:

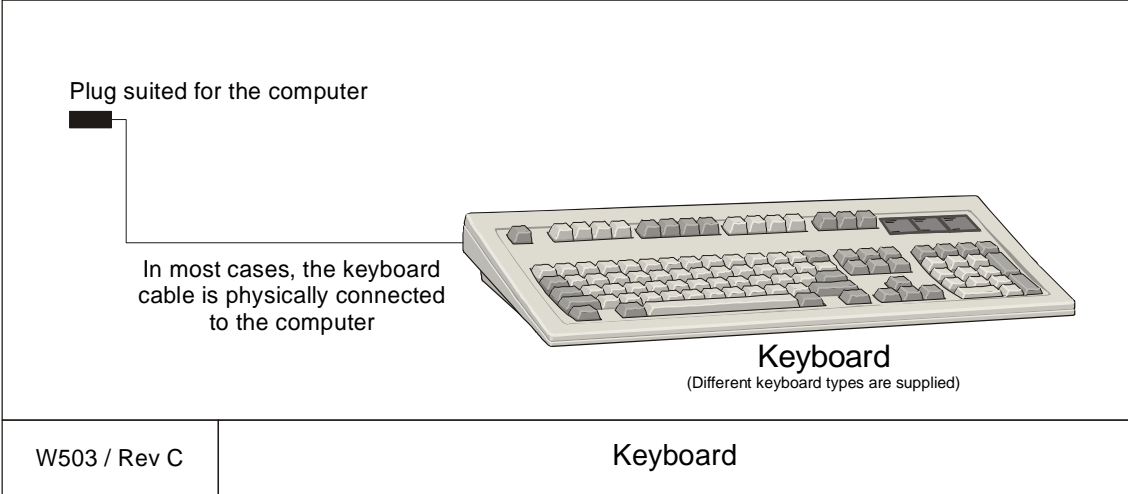
- Standard VGA plug (typical on most commercial computers)
- Multiconnector for Unix work stations
- Seperate RGB connectors (used on high-quality monitors)

The cable is normally physically fastened to the display unit, and it is provided with the plug(s) readily attached.



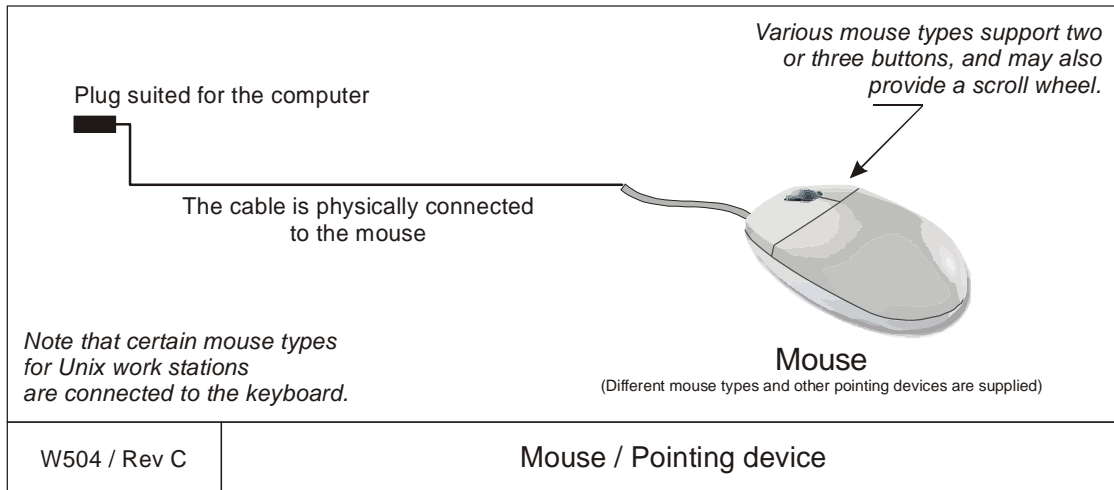
Keyboard cable

This is a standard keyboard cable. In most cases, the cable is physically connected to the keyboard. It is terminated in a plug suited to fit the computer.



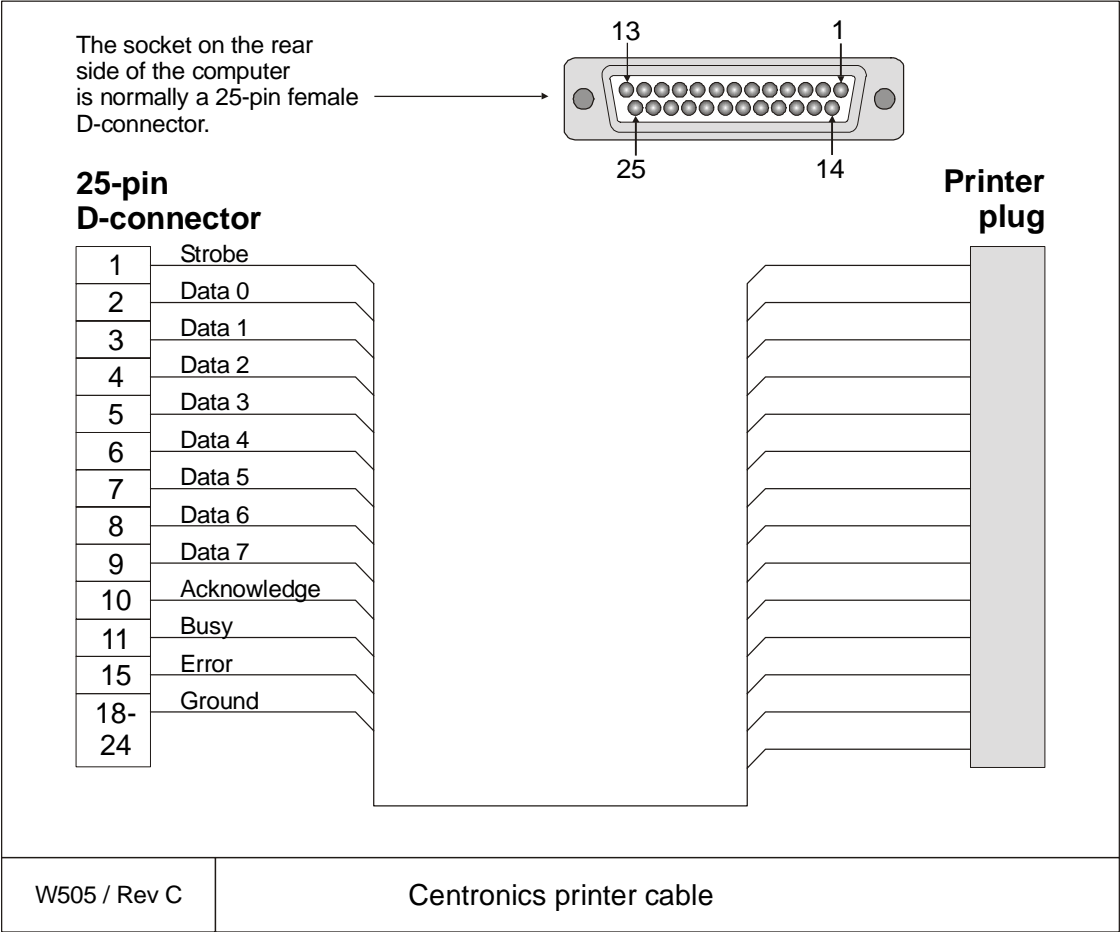
Mouse or pointing device cable

This is a standard mouse cable. It is physically connected to the mouse. It is terminated in a plug suited to fit the computer.



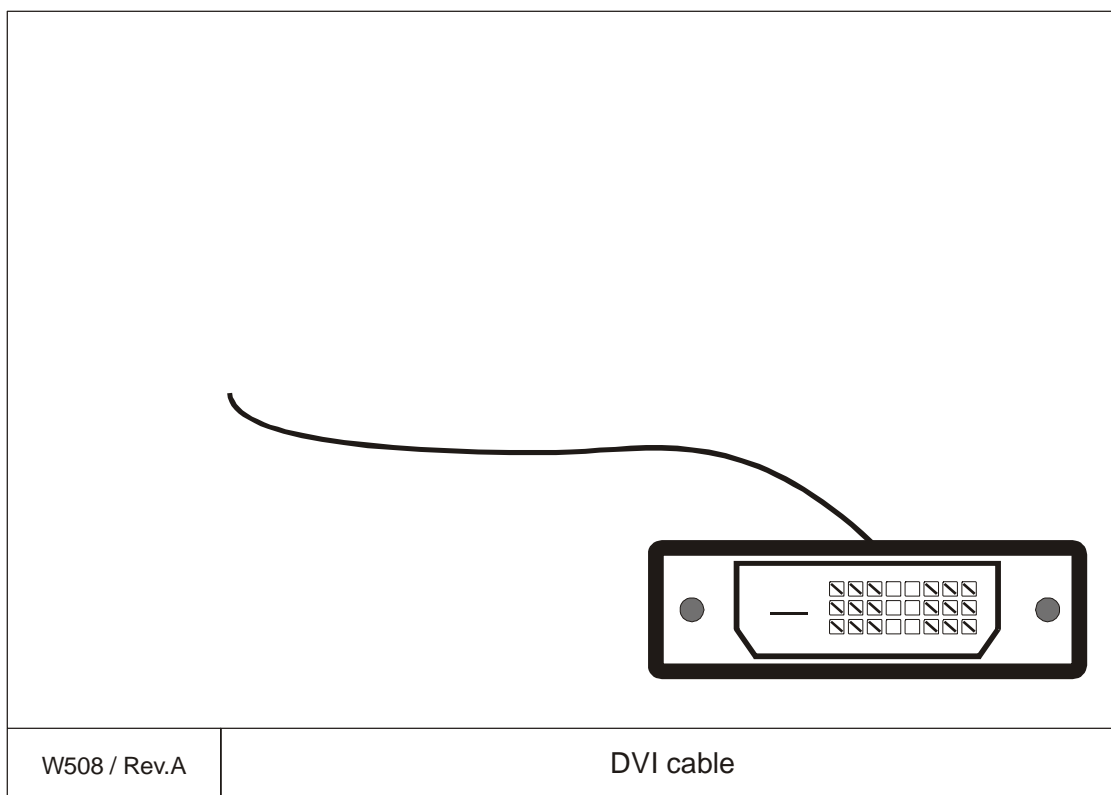
Centronics printer cable

This is a standard Centronics printer cable.



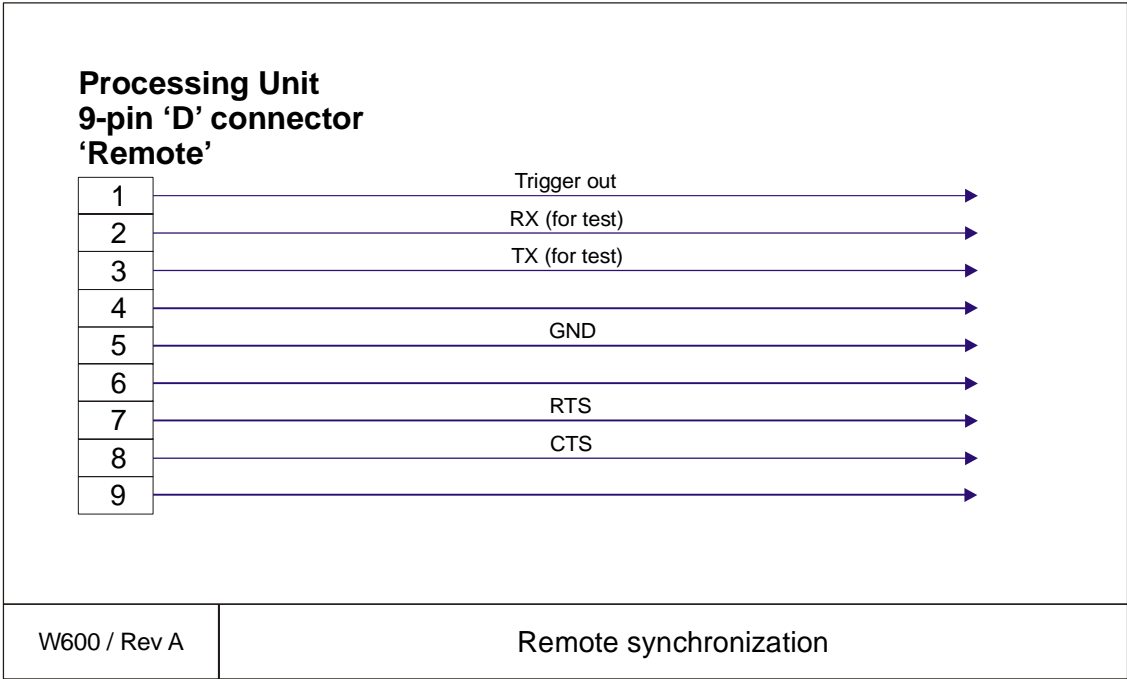
Digital Video Interface (DVI) display cable

This cable is a standard DVI-I cable. It is connected to the LCD display.



W600 - Remote synchronization

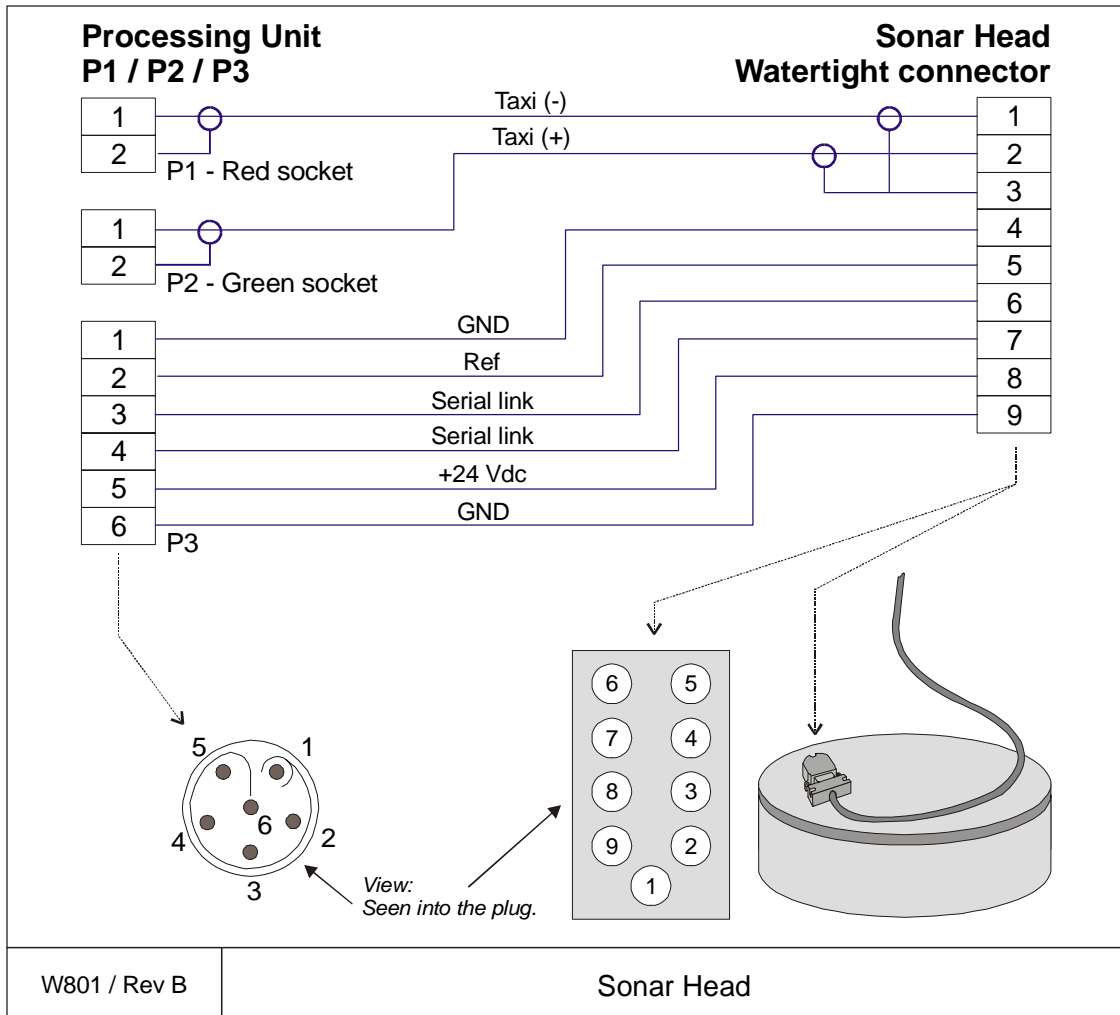
The cable is supplied by the manufacturer.



Conductors	5 x 2 x 0.5 mm2
Screen	Overall braided
Voltage	60 V
Max.diameter	Limited by the plugs

W801 - Sonar Head cable

This is the cable from the EM 3000 Processing Unit to the Sonar Head(s). The cable is supplied by the manufacturer.



3.6 Sonar Head cable drawings

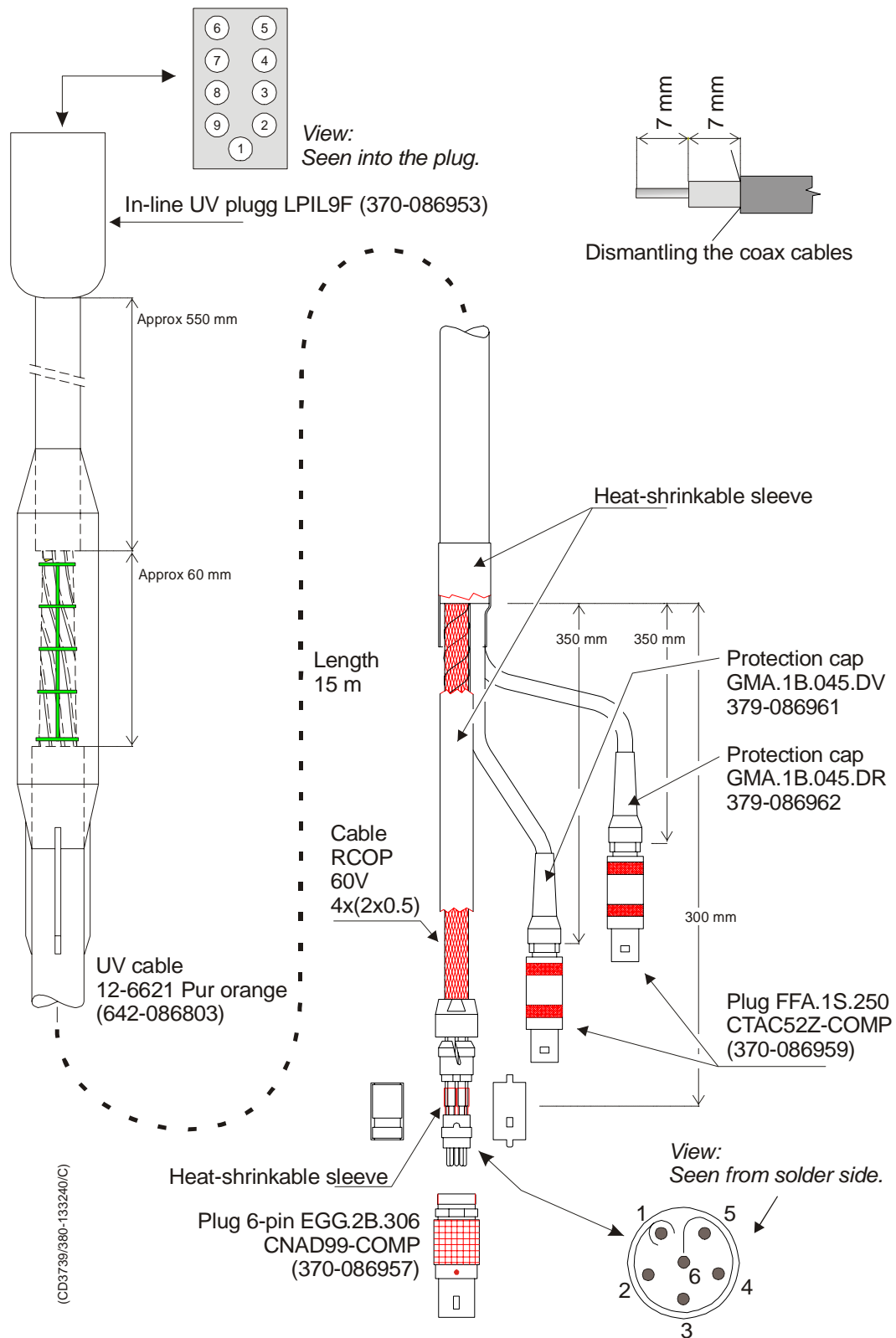


Figure 6 Sonar Head cable, assembly drawing

Standard Sonar Head cable

Note

On newer BIF boards the TAXI interface is the same as in figure 8.

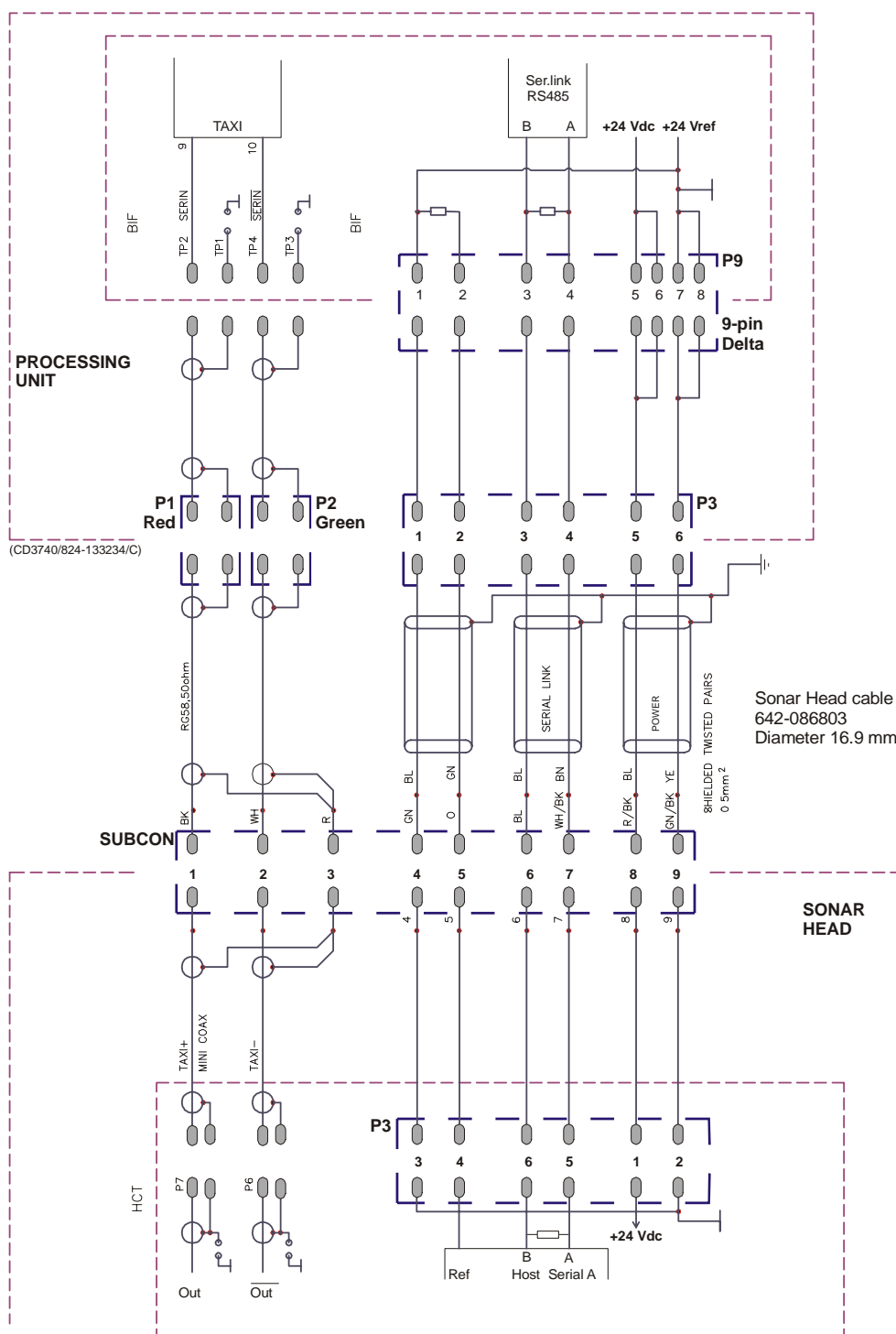


Figure 7 Sonar Head cable; connection diagram for Standard Processing Unit.

AUV Sonar Head cable

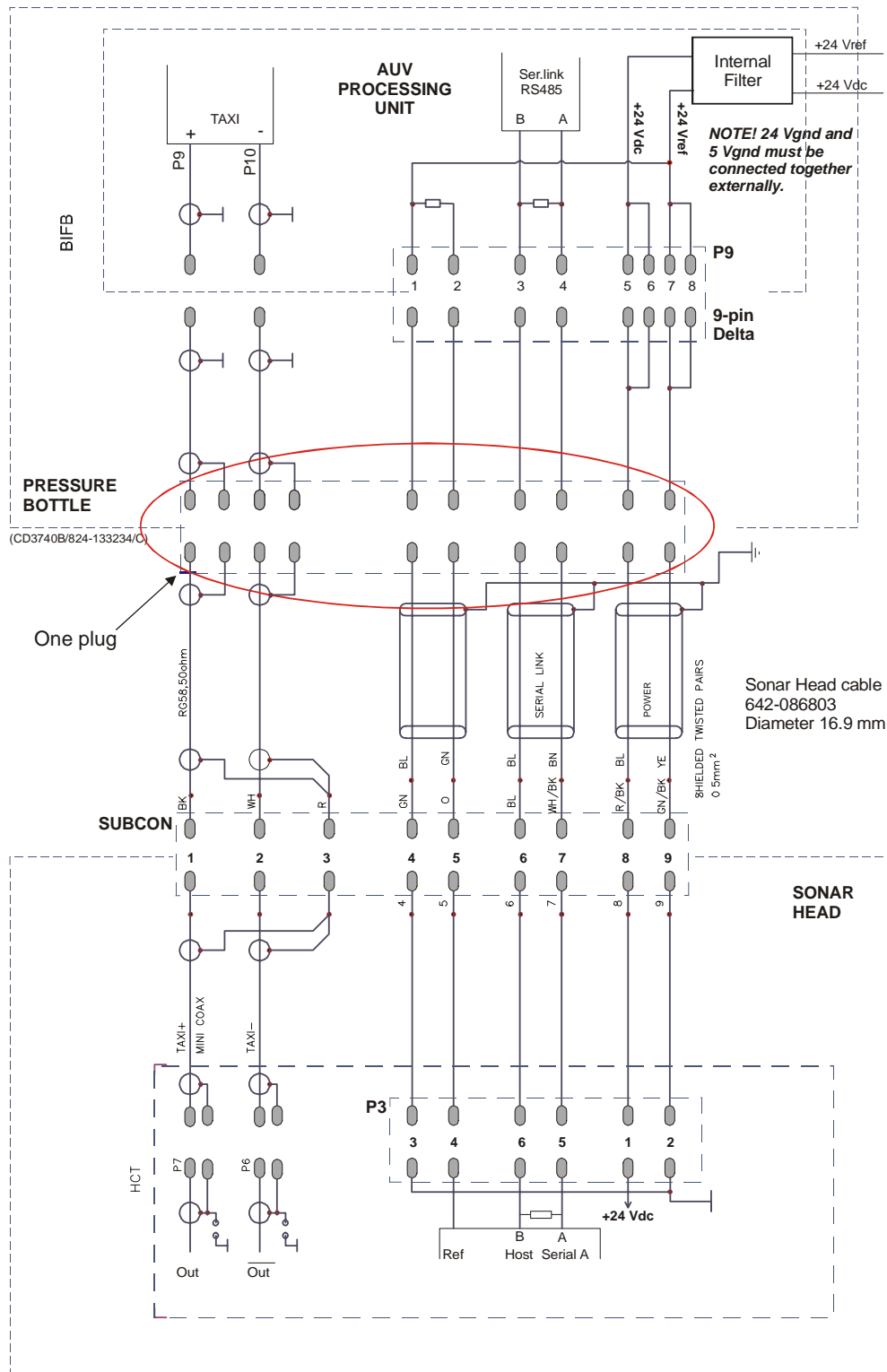


Figure 8 Sonar Head cable; connection diagram for AUV Processing Unit.

4 OPERATOR STATION HWS 10

4.1 Description and main functions

Overview

The HWS 10 is normally the Operator Station used by the EM 3000. UNIX work stations may also be used.

All components making up the HWS 10 are standard PC parts.

This chapter provides the following information:

- *Description and main functions, page 49.*
- *Operator Station outline, page 50.*
- *Theory of operation, page 51.*
- *Operator Station installation, page 52.*



Figure 9 HWS 10 - outline dimensions

4.2 Theory of operation

Overview

The HWS 10 is equipped to handle the heavy processing requirements and high-speed, large volume data storage demands of today's hydrographic systems. It has been specifically designed as the optimal platform for running the Seafloor Information System (SIS) real-time operating software used on the Kongsberg EM multibeam echo sounders. Special features of SIS include real-time:

- Gridding of sounding data.
- Filtering of sounding data.
- 3-D visualization of sounding data.
- Storage and visualization of high resolution backscatter data from the seabed and the water column.

Software

The partitioned system disk is dual bootable with Linux® and Microsoft Windows XP® respectively. SIS software is factory installed and tested on both operating systems.

Data storage

The primary task of the HWS 10 is to safeguard the collected data and to visualize it for quality control. All data is initially stored on a pair of high performance SerialATA disks. These disks are run in a RAID1 configuration, thus ensuring against loss of data even if one disk should fail. They are mounted in hot swappable enclosures, so that the collected data may be transported on the disk. An 8x DVD recorder is the standard means for permanent archiving of the collected data. For users having preferences for other storage devices or media, the HWS 10 includes USB 2.0, Firewire (IEEE 1394) and SCSI interfaces. Gigabit Ethernet is available for transfer of the data to another network computer. For temporary storage data may also be backed up to the system drive.

4.3 Installation

The HWS 10 is prepared for mounting in a 19" rack. The system's 17.4" Industrial LCD monitor is also rack mountable, and a universal bracket is supplied for tabletop, overhead or bulkhead mounting. Both the workstation and the monitor are IP22 rated. A spill-proof US keyboard and a standard optical mouse is included, but a small IP65 keyboard with integrated track stick is optionally available. A 5.25" externally accessible drive bay is available for customer use. The system supports the use of a second LCD monitor, this may be a 15" unit for use as a helmsman display.

Note

The IP22 rating requires that the two front USB ports (of a total of six) are covered. If the IP22 rating is not required, and the two front USB ports are needed, this cover may be removed.

5 PROCESSING UNIT

5.1 Description and main functions

Overview

The EM 3000 Processing Unit performs the data acquisition, signal processing and function control.

This chapter provides the following information:

- *Description and main functions, page 53.*
- *Processing Unit outline, page 54.*
- *Theory of operation, page 59.*
- *Circuit board descriptions, page 63.*

5.2 Standard Processing Unit drawing

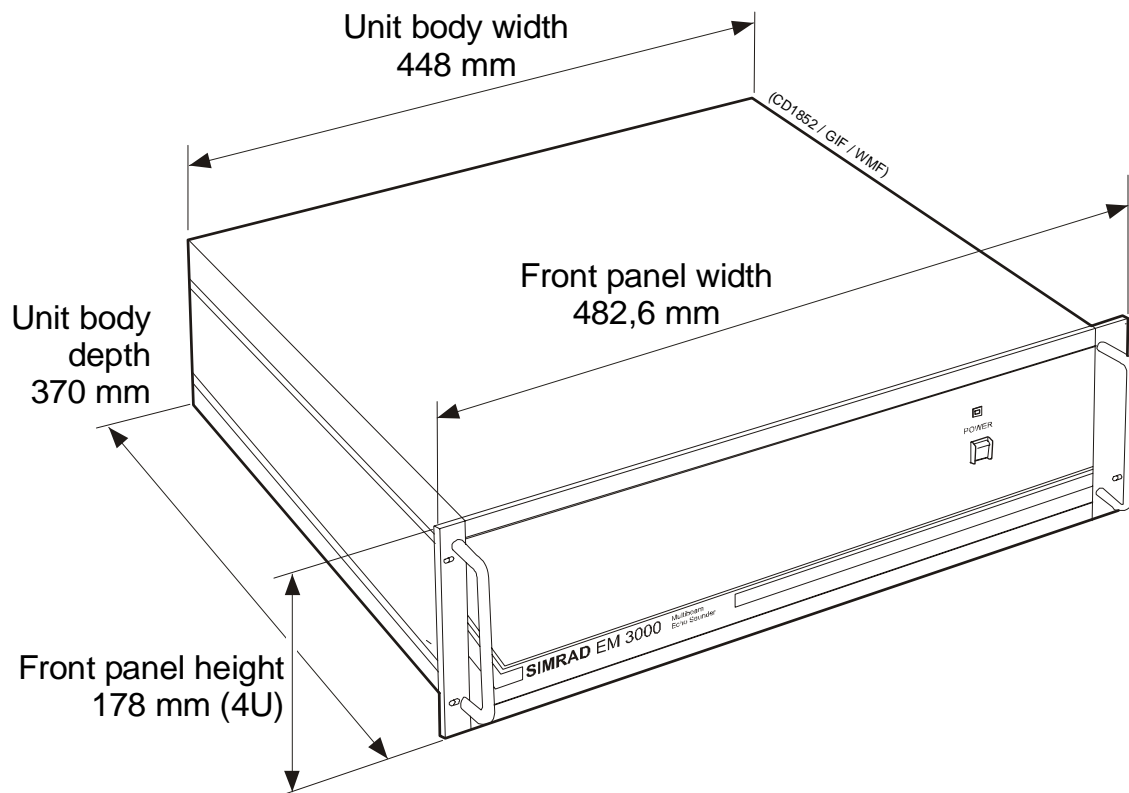


Figure 10 Processing Unit - Outline dimensions

5.3 AUV Processing Unit drawing

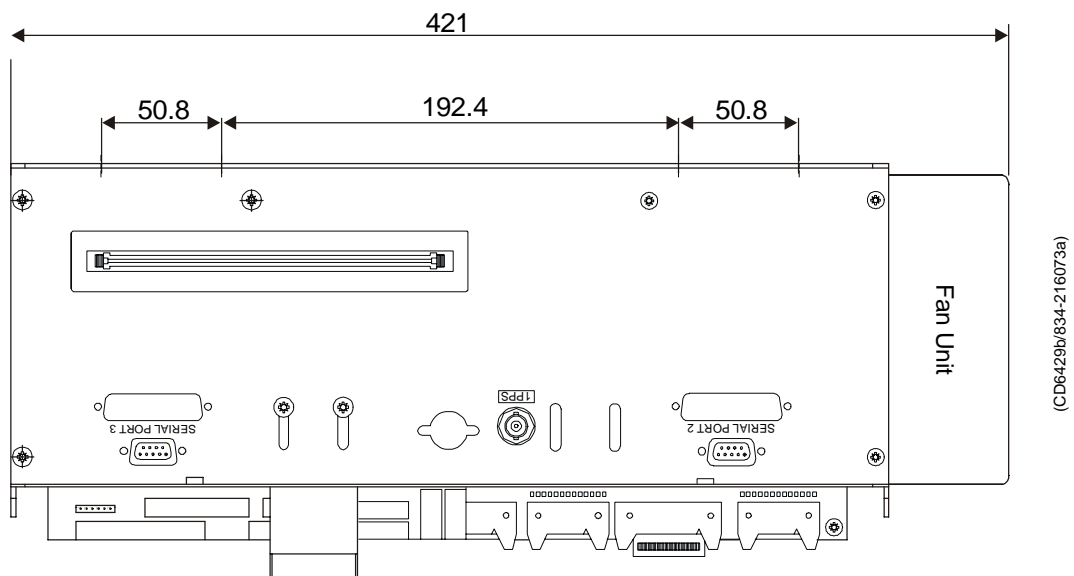
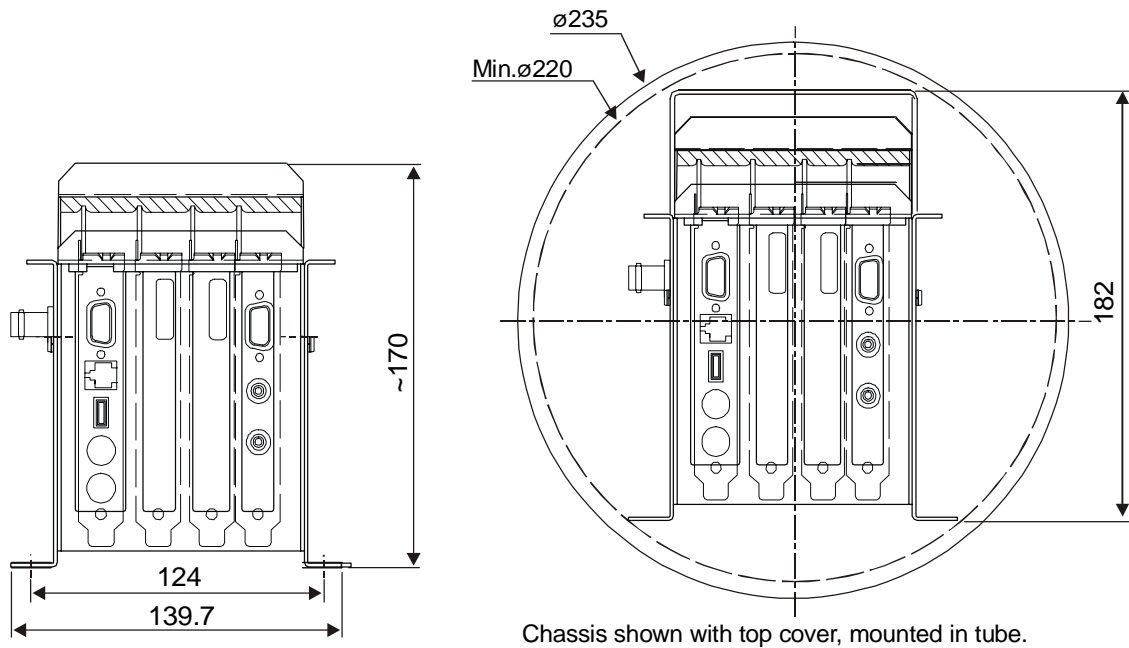


Figure 11 AUV Processing Unit - Outline dimensions
(shown with Fan Unit and cover).

Circuit boards and modules

The Processing Unit holds several circuit boards, fans and a power supply. All connections are made on the rear panel.

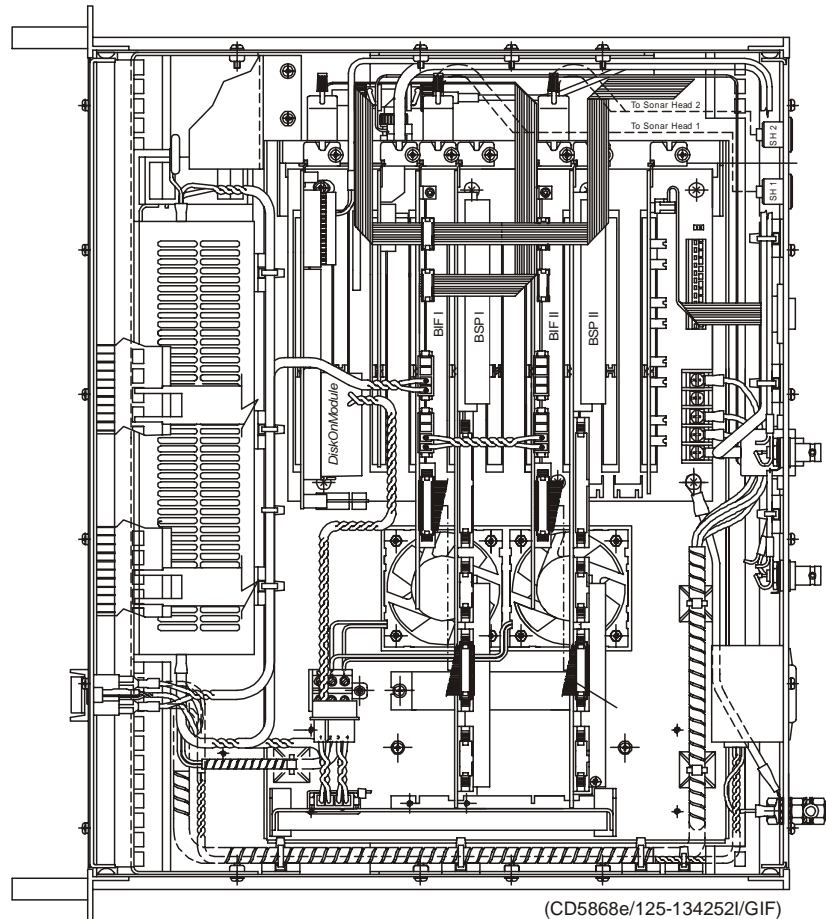


Figure 12 Processing Unit, wired

The unit holds the following circuit boards and modules:

- 4-Ports Serial Line board

The different versions of the EM 3000 has different serial line boards:

- “Old” PU: C114P (Reg.no: 719-087002)
- “New” PU: CI-104JS (Reg.no: 719-098382)

- Beamformer & Signal Processor (BSP1 and BSP2)

The BSP has two different versions of the U16 EPLD to interface to the actual CPU board:

- “Old” PU: Reg.no: 382-215990,
EPLD version 1.33
- “New” PU / AUV PU: Reg.no: 382-218016,
EPLD version 7.0

Note

- Beamformer Interface (BIF1 and BIF2)

If the EM 3000 has a single head, the system uses one BSP board and one BIF board. If the system has a dual head, it uses two BSP boards and two BIF boards.

- Ethernet Adapter
 - The Old PU may have a separate ethernet interface board.
- ROM board

On newer systems, made after summer 2001, the ROM board has been replaced with a DiskOnModule flash disk mounted on the Control Processing Unit board. The ROM board will be replaced on older systems too.

- Passive Backplane
- Control Processing Unit board

The different versions of the EM 3000 Transceiver Unit has different CPU boards:

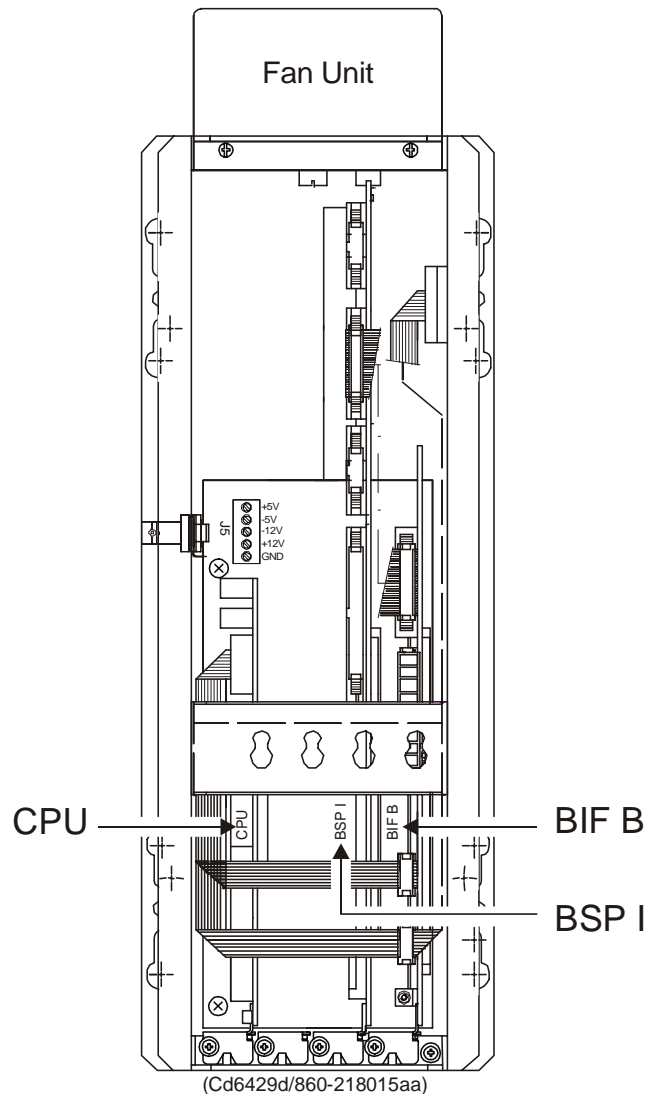
- **“Old” PU:** SSC-486H / SSC-5x86H
- **“New” PU:** VIPer 629
- **AUV PU:** CoolMonster

- Power supply
- Fan

→ *A more detailed description of all the circuit boards and modules is found on page NO TAG.*

AUV Processing Unit Circuit boards and modules

The Processing Unit holds several circuit boards and a fan. The power must be supplied by the customer.



The unit holds the following circuit boards and modules:

- Beamformer & Signal Processor (BSP1)
- Beamformer Interface (BIFB)
- Passive Backplane (made by Kongsberg Simrad)
- Control Processing Unit board

Optional:

- External harddisk

Power for external hard disk must be supplied by the customer.

The fan is supplied internally by 5 Vdc.

5.4 Theory of operation

Overview

This chapter presents a functional description of the Processing Unit.

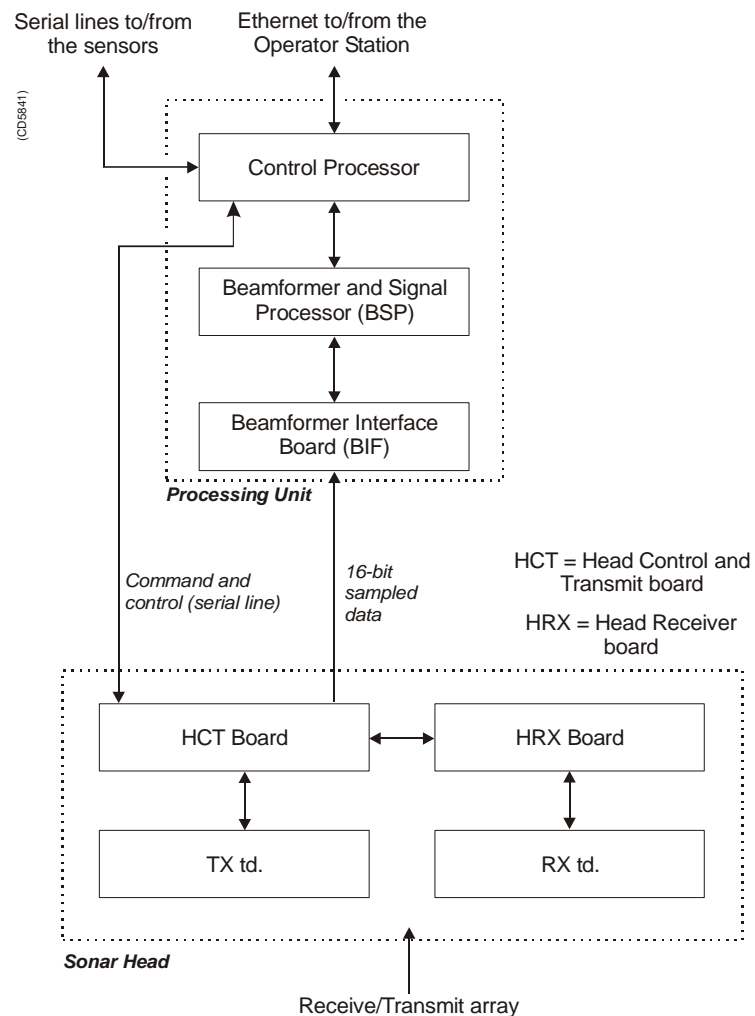


Figure 13 EM 3000, simplified block diagram

Simplified block diagram

The simplified block diagram for the Processing Unit presents the following main functions:

- Transmission
- Reception
- Processing

→ Refer to figure 13.

The various parameter settings made on the Operator Station are sent to the Control Processor in the Processing Unit. The information is interpreted, and passed on to the Head Control and Transmit board. After the transmission, the Head Control and Transmit board read data from 80 channels on the Head Receiver board, and pass these to the two Signal Processors in the Processing Unit.

Control functions

The control functions in the Processing Unit are mainly handled by the control processor board, but additional boards are also used.

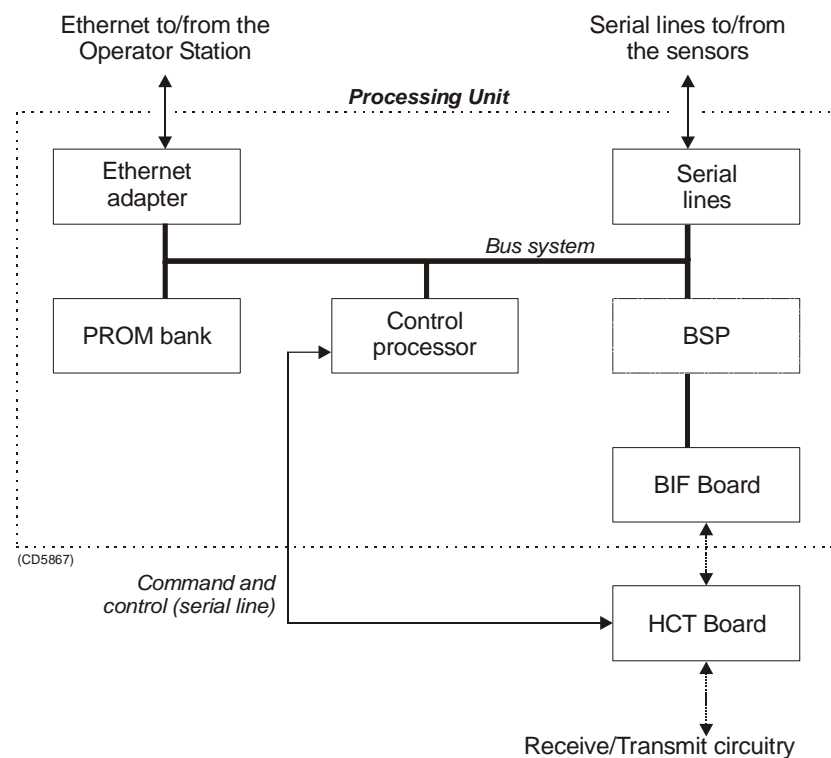


Figure 14 The control functions

The Control Processor in the Old PU is not equipped with interface capabilities, and thus requires external boards to handle ethernet and serial lines interface.

The New PU CPU is equipped with ethernet interface.

The AUV PU CPU has all serial lines internally on the board.

It also relies on a memory disk for the software contained in the DOM (DiskOnModule) device. This is located on the Control Processing Unit Board.

Note

On older systems there is no DiskOnModule, but a ROM (Read Only Memory). This is an external memory board for the software.

All the peripheral boards used here are commercial.

One serial line, on the Control Processor board, is used to interface the command and control signals to and from the Sonar Head. The RS-232 line is converted to RS-485 on the BIF-board.

External synchronization

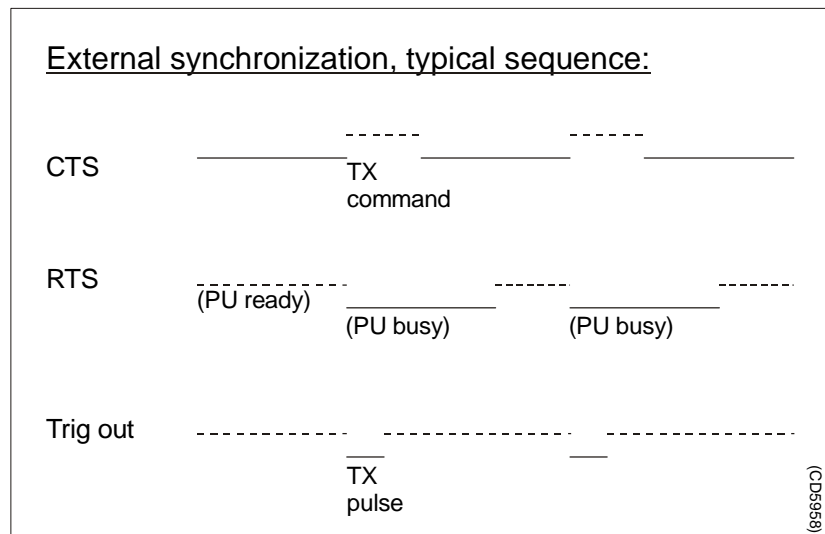
The serial lines RTS (Request To Send) and CTS (Cleared To Send) signals are used for external synchronization. In addition a Trig out signal is issued by the BIF (Beamformer Interface) board.

Levels	
RTS, CTS = high	+3 to +15 V
RTS, CTS = low	-3 to -15 V
Trig out	TTL level

Outputs from PU	
Trig out = 1	TX is off (high TTL level)
Trig out = 0	TX is active (low TTL level)
RTS = high	PU is ready for a new ping
RTS = low	PU is not ready
RTS is pin 7	

Inputs to PU	
CTS = high	Ping command
CTS = low	Wait
CTS is pin 8	The CTS pulse length must be minimum 30 milliseconds
GND (ground) is pin 5	

When the Processing Unit is ready for a new ping, RTS is set to high. When the external device is ready for a new ping, CTS is changed into high. The Processing Unit will then start a ping, change RTS to low (busy), and the Trig out will be low for 10 - 30 μ S, when the transmit pulse starts. After the Trig out is received, the external device should turn CTS to low, or at least keep it high for 30 milliseconds.



When the received period is finished and the Processing Unit is ready for a new ping, the RTS will be changed to high, and the Processing Unit will wait for a new trigger (a high level on CTS).

If CTS is high at all times, or if external synchronization in the installation menu is switched off, the Processing Unit will ping at its maximum rate.

1PPS

The 1PPS input signal is normally “resting” at a high level. Each second, a pulse (100µS-1000µS) adjusts the second counter in the Processing Unit. Since 1PPS is a TTL-signal, a high level at the input connector must be higher than 2,7 Vdc (margin is 0.3 Vdc) and a low level (during the pulse) must not exceed 0.6 Vdc (margin is 0.2 Vdc).

5.5 Circuit board descriptions

Overview

This chapter describes all the circuit boards and modules in the EM 3000 Processing Unit. A functional description with a block diagram is provided, as well as the facilities provided for maintenance.

Serial Line Board (CI-104JS)

If more information is needed, refer to webpage
www.moxa.com.

Purpose and description

This is a commercial circuit board designed and produced by Moxa Technologies. It is located in the Processing Unit.

The board is a cabling space saver that features a built-in RJ45 bracket to save cable layout space and reduce cost.

It has surge protection and ISA bus.

Note

A software setup has been done at Kongsberg Maritime to configure the board.

How it works

The Smartio CI-104JS Series provides 4 RJ-45 sockets for connection, which save a lot of cable space.

Surge Protection

To prevent the board from damage caused by lightning or high potential voltage, TVSS (Transient Voltage Surge Suppressor) technology is introduced in Smartio CI-104JS to protect the board. This is critical to harsh environment such as factory.

Specifications

Connector type	RJ-45
Bus	ISA (16 bit)
Serial	RS-232
Ports (interface)	4
Power requirements	83 mA max. (-12V), 57 mA max. (+12V), 100 mA max. (+5V)
Operating temperature	0° - 55°C
Dimensions	157 x 83 mm (width x depth)
Surge protection	25 KV ESD, 2 KV EFT

Facilities

No switches.

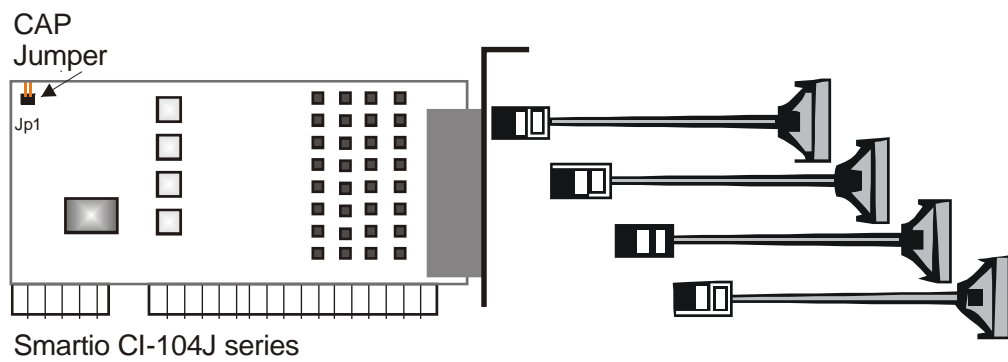


Figure 15 Illustration of the Serial Line Board.

4-Ports Serial Line Board (C114P)

Purpose and description

This is a commercial circuit board designed and produced by Moxa Technologies. This is identified as C114P, and is located in the Processing Unit.

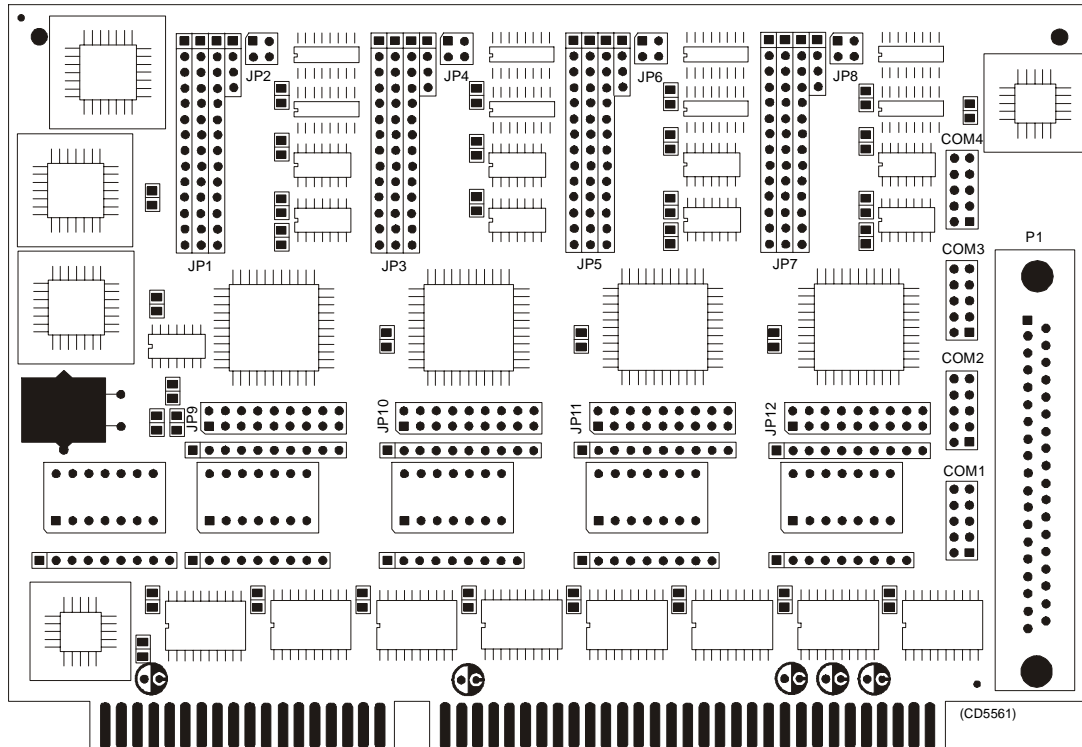


Figure 16 The C114P layout

How it works

Each of the 4 ports can be configured to RS-232, RS-422, or RS-485 interface individually, but only RS-232 will work on the EM 3000 system.

Facilities

LEDs

None.

Jumpers

The C114 is set up with IRQ 11 on the jumpers JP9, JP10, JP11 and JP12.

Links

Note

The following settings are only valid for new boards. For boards older than spring 2001 the settings will be inverted. The settings that are OFF on these drawings will be ON and vice versa.

The settings of the C114P DIP switches for use in the EM 3000 are listed in the table below:

Switch	1	2	3	4	5	6	7
SW 5	ON	ON	OFF	OFF	OFF	ON	ON
SW 1	ON	ON	ON	ON	OFF	OFF	ON
SW 2	OFF	ON	ON	ON	OFF	OFF	ON
SW 3	ON	OFF	ON	ON	OFF	OFF	ON
SW 4	OFF	OFF	ON	ON	OFF	OFF	ON

Connections

The C114P contains one DB-37 female connector on the rear side of the circuit board. It comes with a cable; one terminal is a 37-pin male D-type and the other terminal is a four 9-pin male D-type connectors. This is not used.

→ Refer to figure 18 and 19 for pin assignments.

→ Refer to figure 17 for pin assignments.

In addition, four 10-pin pin-head connectors corresponds to the DB-37 connector on the board of C114P. These four connectors are called COM1, COM2, COM3 and COM4, and are connected directly to the Processing Unit bottom plate.

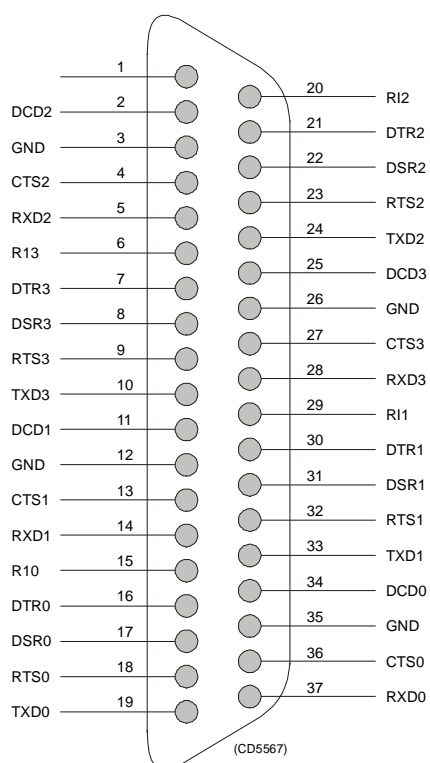


Figure 18 DB-37 pin assignment

Figure 17 10-pin header connector pin assignment

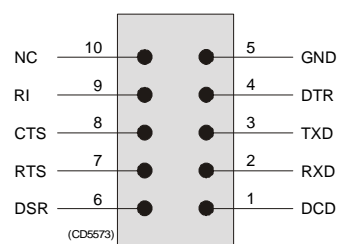
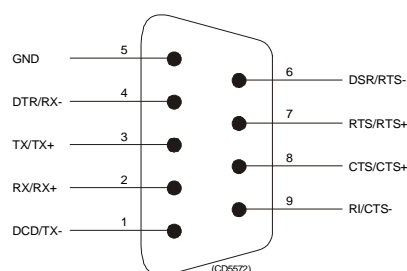


Figure 19 DB-9 pin assignment



Control Processor Unit board

Note

This board is used by the “Old” PU.

Purpose and description

This circuit board is an ISA Half-sized Single Board Computer delivered by ICP. It is equipped with a 486 CPU and advanced high performance multi-mode I/O. There are two variants of the circuit board that might be placed in the system. These are identified as:

- SSC-486H

or

- SSC-5x86H

Both of them are explained in this chapter. The Control Processor Board is located in the Processing rack.

Specifications

The Half-sized Single Board Computers SSC-486H and SSC-5x86H provides the following specifications:

	SSC-486H	SSC-5x86H
CPU	486SX/DX/DX2 or DX4	486SX/DX/DX2/DX4 or Cyrix/AMD 5x86
Bus	PC/104 bus	ISA bus and PC/104 bus
DMA channels	7	7
Interrupt levels	15	15
Chipset	UM8498F and UM8496	M1489 and M1487
Real-time clock/calendar	DS-12887 chip and quartz oscillator, 128B CMOS memory, powered by lithium battery for over 10 years of data retention.	DS-12887 chip and quartz oscillator, 128B CMOS memory, powered by lithium battery for over 10 years of data retention.
RAM memory	1MB to 64MB	1MB to 64MB, EDO and standard DRAM supported.
IDE hard disk drive interface	Up to two IDE hard drives.	Up to two PCI Enhance IDE hard drives.
Floppy disk drive interface	Two 2.88MB, 1.44MB, 1.2MB, 720KB or 360KB floppy disk drives.	Two 2.88MB, 1.44MB, 1.2MB, 720KB or 360KB floppy disk drives.
High speed serial ports	Two NS16C550 compatible UARTs	Two NS16C550 compatible UARTs
Bi-directional Parallel Port	Yes	Yes

	SSC-486H	SSC-5x86H
Watch-dog timer	Can be set by 1, 2, 10, 20, 110 or 220 seconds period. Reset or NMI was generated when CPU did not periodically trigger the timer. Your program use hex 043 and 443 to control the watch-dog and generate a system reset.	Can be set by 1, 2, 10, 20, 110 or 220 seconds period. Reset or NMI was generated when CPU did not periodically trigger the timer. Your program use hex 043 and 443 to control the watch-dog and generate a system reset.
External power connector	Yes	Yes
Keyboard connector	Yes	Yes
Mouse	PS/2 Mouse Port on-board	PS/2 Mouse Port on-board
Power Consumption	+5V @ 2.5A (486DX2-66, 4MB RAM) +/- 12V @ 20mA (for RS-232 only)	+5V @ 1.75A (5x86-133, 4MB RAM)
Operating temperature	0° ~ 60°C (CPU needs cooler)	0° ~ 60°C (CPU needs cooler)

→ The set-up procedures for SSC-486H and SSC-5x86H are described on page 154

Facilities

Jumpers

All the SSC-5x86H- and SSC-486H circuit board's jumpers are preset at the factory. The default settings are listed in the tables.

→ Refer to figure 20 for different jumper settings.

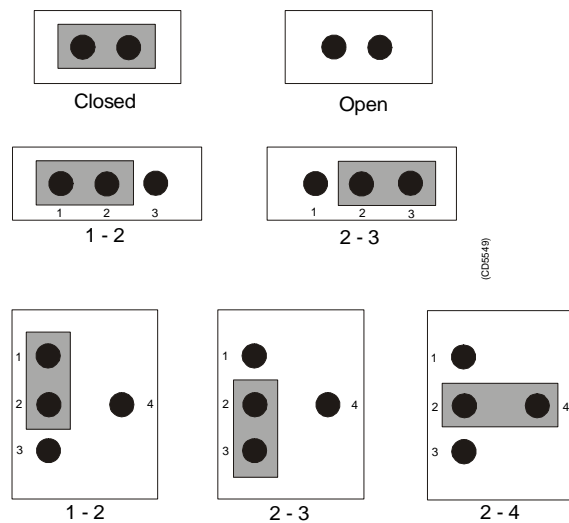


Figure 20 Different applicable jumper settings

The SSC-486H circuit board:

	Jumpers	Settings	Description
SSC-486H CPU	JP1	2 - 3	-
	JP2	1 - 2 3 - 4	-
	JP3	Open	-
	JP4	Open	-
	JP5	1 - 2	-
	JP6	Open	-
	JP7	Open	-
CPU Clock Generator Speed (33 MHz)	JP8	1 - 2 Closed 3 - 4 Closed 5 - 6 Open 7 - 8 Open	-
CPU Voltage (+3.3 V)	JP12	2 - 3	-
	JP24	Open	-
Upgrade the External Cache (128KB, 32K x 8)	JP13	2 - 3	-
	JP14	1 - 2 3 - 4	-
Watch-Dog Timer, Active Type	JP18	1 - 2	Open when WDT time-out
WDT Time-out period (10 sec.)	JP17	1 - 2 Open 3 - 4 Closed 5 - 6 Open 7 - 8 Open	-

	Jumpers	Settings	Description
Parallel Port Interface, Parallel Port Interrupt Setting (IRQ7)	JP22	1 - 2	-
Parallel Port Data Request Setting (DRQ3)	JP20	2 - 3	-
Parallel Data Acknowledge (DACK3)	JP19	2 - 3	-
Serial Port Interface, COM1 Serial Port Interrupt Setting (IRQ4)	JP21	1 - 2	-
COM2 Serial Port Interrupt Setting (IRQ3)	JP23	1 - 2	-
IDE Host Adapter Interface	JP11	Open	IDE IOCHDRY Non-Connected
FDC47C665 Multi-I/O Chipset	JP16	Open	Enable FDC37C665
PS/2 Mouse IRQ Selection (IRQ12)	JP15	Closed	-

The SSC-5x86H circuit board:

	Jumpers	Settings	Description
SSC-5x86H CPU	JP1	2 - 3	-
	JP2	2 - 3	-
	JP3	3 - 4	-
	JP4	3 - 4	-
	JP5	3 - 4	-
	JP6	5 - 6	-
	JP7	2 - 3	-
	JP8	2 - 3	-
	JP9	Closed	-
	JP10	Open	-
CPU Clock (33MHz)	JP11	1 - 2 Closed 3 - 4 Closed	-
	JP12	Open	-
	JP14	1 - 2	-
CPU Voltage (+3.3V)	JP13	2 - 3	-
Watch-Dog Timer, Active Type	JP15	1 - 2	Open when WDT time-out

	Jumpers	Settings	Description
WDT Time-out period (10 sec.)	JP16	1 - 2 Open 3 - 4 Closed 5 - 6 Open 7 - 8 Open	-
DiskOnChip Memory Address	JP17	5 - 6	Address E000
PS/2 Mouse	JP18	Closed	Enable PS/2 Mouse, IRQ12

Connections

COM1 is used for external sync (RTS, CTS). COM1, pin RX/TX, is also connected to the test connector at the Processing Unit bottom plate, for debug purposes and factory production testing.

→ *Refer to description page 61.*

1PPS signal is connected from the parallel port (signal on pin 10, GND (ground) on pin 23) to the bottom plate in the Transceiver Unit.

VIPer 629 Control Processor Board

Note

This board is used by the “New” PU.

Purpose and description

This is a commercial circuit board designed and produced by Kontron.

→ Refer to webpage www.kontron.com for more information.

A DiskOnModule (DOM) or a DiskOnFlash (DOF) module is mounted on this board. This module contains the software needed for this CPU board, and for the BSP boards. It can be upgraded from the release CD.

The LAN / Ethernet to and from the Operator Station is connected here.



Figure 21 VIPer 629

Cool Monster C3/400 Control Processor Board, AUV PU

Purpose and description

This is a commercial circuit board designed and produced by JUMPtec Industrielle Computertechnik AG.

→ Refer to webpage www.jumptec.de for more information.

A DiskOnModule is mounted on this board. This module contains the software needed for this CPU board, and for the BSP boards. It can be upgraded from the release CD.

Cable Position No.	From	To (1)	To (2)
# 7	BIFB-P1	BSP2-P1	BSP1-P1
# 8	CPU-COM1	BIFB-P13	CHASSIS- serial port 1/trig
# 9	CPU-COM2	BIFB-P2	-
# 10 (1)	CPU-COM3	CHASSIS-serial port 2	-
# 10 (2)	CPU-COM4	CHASSIS-serial port 3	-
# 11	CPU-LPT1	CHASSIS-1PPS	-

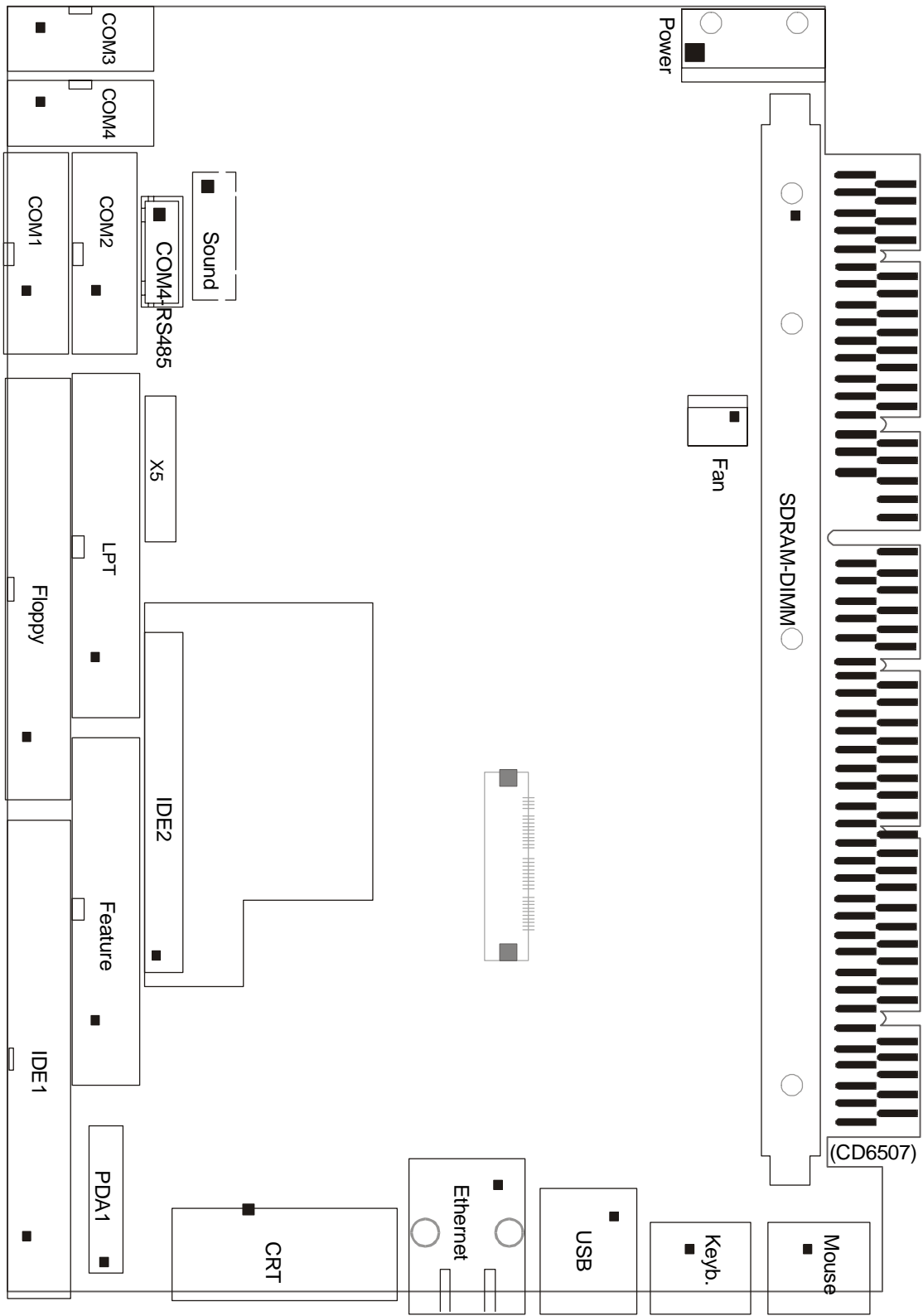


Figure 22 CoolMonster board details

ROM board

Note

This board is used by older systems only.

Purpose and description

The ROM (Read Only Memory) board is an ISA bus card that adds an EPROM socket to a PC motherboard. This is a commercial circuit board designed and produced by Blunk Microsystems. The ROM board is located in the processing rack.

It provides a means of auto-starting embedded applications. If a properly formatted EPROM is installed, the BIOS will recognize the EPROM during its ROM scan and pass control to it after completing the power-up tests. The ROM board uses one 27010, 27020 or 27040, booting applications as large as 128K, 256K or 512K, respectively.

Facilities

LEDs

None

Test points

None

Links

Jumper	Base Address
1-8	CE000
2-7	CE800
3-6	CF000
4-5	CF800

When used in EM 3000, the default settings for the ROM board are jumpers 2-7, and base address CE800.

Beamformer & Signal Processor (BSP)

Purpose and description

The Beamforming & Signal Processing (BSP) board is a multi digital signal processor (DSP) board. It is designed to perform the beamforming and signal processing in sonars and multibeam echo sounders. It is controlled from a host processor.

The processing power in the Beamforming & Signal Processing (BSP) board is based on eight Texas TMS320C50 fixed point digital signal processors working in parallel while beamforming the data. Next, there are four Texas TMS320C44 floating point digital signal processors interconnected to use both parallel and sequential processing of the beamformed data from the fixed point processors.

The Beamforming & Signal Processing (BSP) board is a single slot full length standard ISA format circuit board made to fit into a personal computer.

How it works

The Beamforming & Signal Processing (BSP) board contains four main sections:

- Sonar Input Data
- Beamforming
- Signal Processing
- Host Interface

The **Sonar Input Data** interfaces an 18-bit wide and 1k deep Input FIFO (First-In-First-Out) register. This input FIFO holds the data received from the transducer array through the receiver processing circuitry. A dedicated digital signal processor reads the input FIFO.

There are two identical **Beamforming** digital signal processing branches. Each consists of four digital signal processors and a 16-bit wide and 8k deep dual port memory (DPRAM). The two branches are exchanging data by means of this DPRAM.

The **Signal Processing** section comprises three digital signal processors dedicated to do further processing of the beamformed data.

The **Host Interface** function is maintained by the master processor on the Beamforming & Signal Processing (BSP) board. It exchanges data with the host processor via a 16-bit wide and 8k deep dual port memory (DPRAM) on the ISA bus.

Facilities

LEDs

D1 (LED): C44 D

Test points

There is one test point for each C50 digital signal processor (eight total). These testpoints are all connected to the XF/ signal which is active while that particular C50 access the shared DPRAM.

There is also one test point for each C44 digital signal processor (four total). These test points are connected to the IIOF2/ signal, which is a general purpose I/O port bit that can be controlled by the software.

The C44-D testpoint is also connected to a light emitting diode (D1) for visual observation. The LED will be activated during each ping.

TP1	C50 E0
TP2	C50 E1
TP3	C50 E2
TP4	C50 E3
TP5	C50 F0
TP6	C50 F1
TP7	C50 F2
TP8	C50 F3
TP11	C44 A
TP12	C44 B
TP13	C44 C
TP14 (& D1)	C44 D

The testpoints will be active when the corresponding processor is working.

Links

A number of links are implemented on the board to allow for several different applications. Links LK1, LK2 and LK3 are used to identify the board as one out of maximum eight boards in one system.

LK3	LK2	LK1	BSP ID
0	0	0	BSP 0
0	0	1	BSP 1
0	1	0	BSP 2
0	1	1	BSP 3
1	0	0	BSP 4
1	0	1	BSP 5
1	1	0	BSP 6
1	1	1	BSP 7

Link applications

The following links are ON (closed) in this application:

- BSP0 is the master processor (no links).
- BSP1 is the slave processor (link LK1).

Switches

There are no switches on the board.

Connections

The Beamforming & Signal Processing (BSP) holds the following plugs and sockets:

P1	Sonar input data
P2	ISA bus component
P3	Emulator
P4	Direct memory access
P5	External communication port
P6	Test access port
P7	External communication port

The P1, sonar input data, is connected to BIFB via a flat cable plug.

Beamformer Interface Board (BIFB)

Note

The old version of the BIFB board is called BIF board. It is a full length ISA board and the functionality is exactly the same as the newer version BIFB. The BIF board was a part of the EM 3000 until the year 2000.

Purpose and description

The Beamformer Interface Board (BIFB) is an interface board between the BSP (Beamformer and Signal Processing) board in the Processing Unit (a PC), and a EM 3000 transducer head with high-speed serial data sent on TAXI line. The BIFB board receives data, decode and write them into a FIFO (First In, First Out), located on the BSP board. A converter between the RS232, from the Processing Unit, and RS485, to the transducer head, is implemented. RS232 data is received through a 10-pin connector (P2). The direction on RS485 (P9) is controlled by RS232 signal RTS.

The BIFB board is a single slot half-length ISA board made to fit into a personal computer.

How it works

The BIFB board contains 4 main sections:

- *Serial to parallel conversion*

BIFB board receives data on high-speed serial line (Taxi line) and write it into a FIFO located on the BSP board. All data and all commands other than SYNC are written to the BSP board.

- *Power to transducer head*

24Vdc is sent down to the transducer head, on connector P9 from the Processing Unit internal power supply

- *Commands to transducer head*

All commands to the transducer head are sent on a standard RS485, half duplex on connector P9. RS232 signals from the CPU (in the Processing Unit) are converted to RS485 and the direction is controlled by the RS232 signal RTS (Request To Send).

- *Trig out during transmit*

During transmit time, a Trig out is sent out on the minicoax connector P14 and a signal on the connector P13. This is to synchronise other systems. Only Master boards (programmed by the CPU) may run the trig signal.

Facilities

LEDs

There are two LEDs used on the BIFB board. LED1 is used as the "MASTER", programmed by the CPU. LED4 is the "ping activity" LED.

Jumpers

One jumper, ST1, is implemented on the BIFB board.

When ST1 in: Interface for transducer head 1

When ST1 out: Interface for transducer head 2

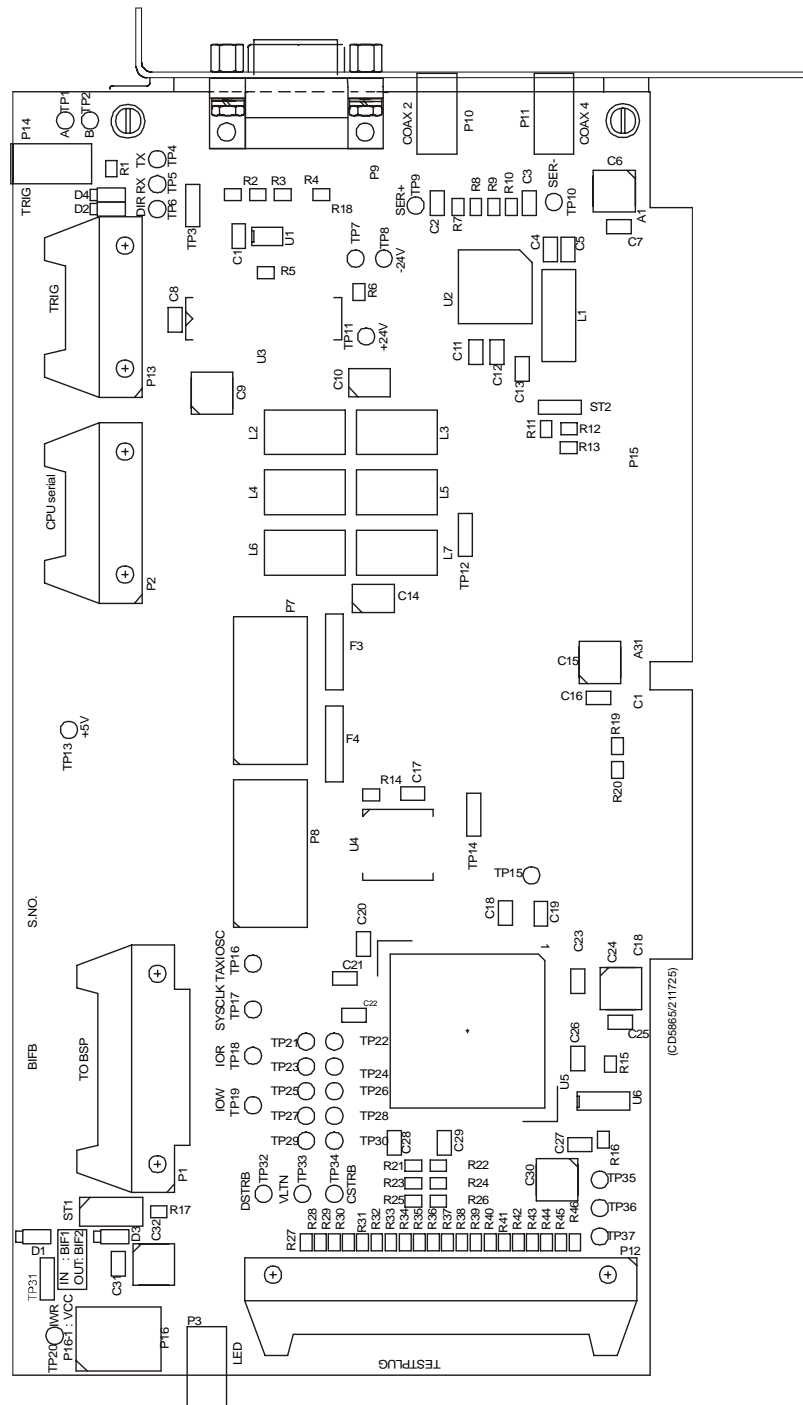
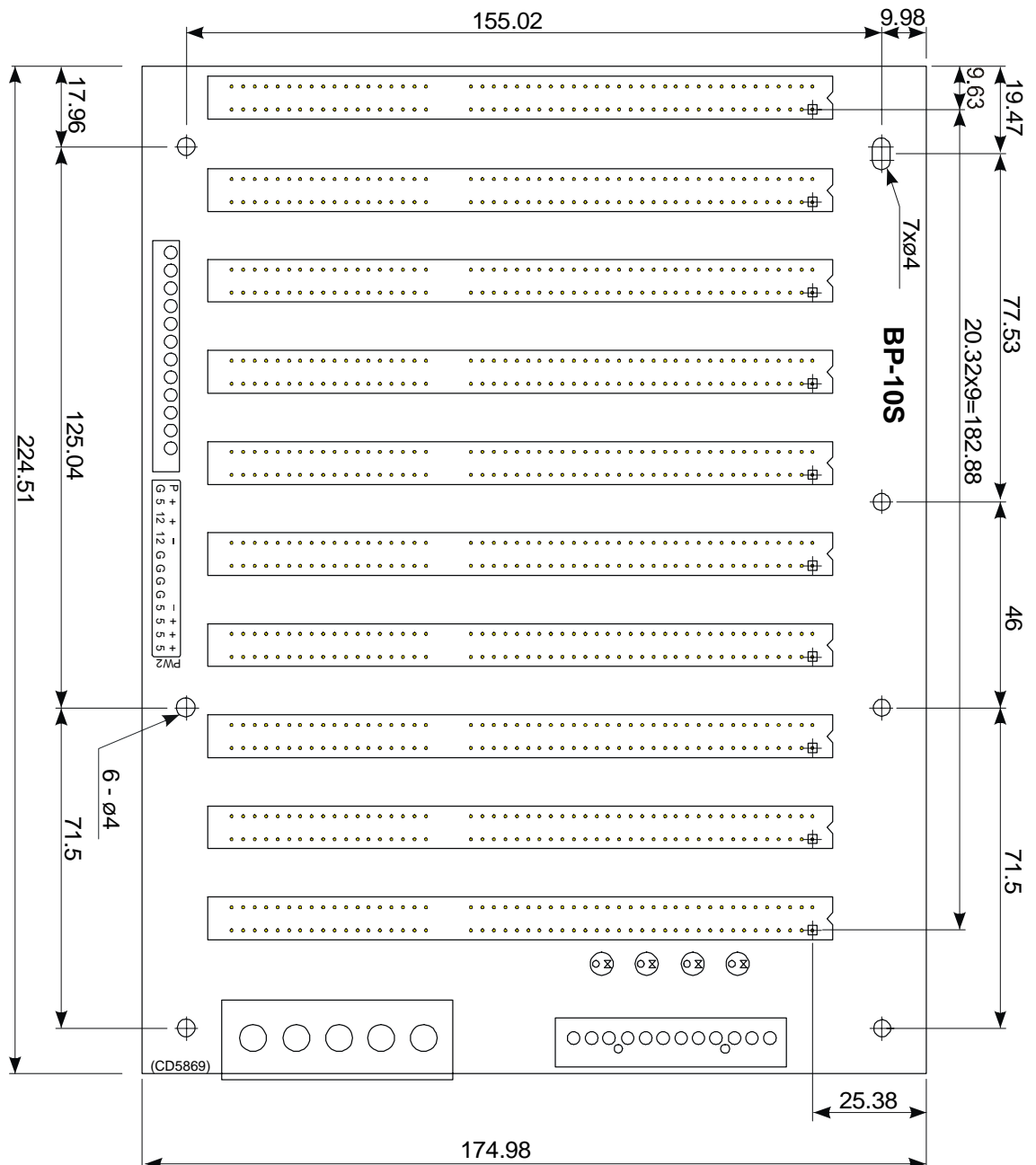


Figure 23 BIFB board

The AUV Processing Unit has a special 4 slot backplane.



How it works

There are no active components on this backplane.

Facilities

LEDs

The LEDs are used as power supply indicators. There are five LEDs on the backplane:

- + 5V
- - 5V
- + 12V
- - 12V

- 5V is not used and therefore not lit. The three other LEDs should be lit at all times.

Test points

None

Links

None

Connections

+ 5V, + 12V and - 12Vdc.

Ethernet Adapter

Note

This board is used in older systems only.

Purpose and description

This is a 16-bit ISA adapter designed and produced by 3Com, identified as 3C509B-COMBO. The purpose of the adapter is to connect the transceiver unit to the operator unit. The circuit board is located in the Processing Rack.

How it works

The cable types and connector specifications in the Ethernet Adapter are:

- 10BASE5 thick Ethernet coaxial, 10BASE2, fibre etc. with an AUI connector.
- 10BASE2 thin Ethernet coaxial with a BNC connector.
- 10BASE-T, twisted-pair cable with a RJ-45 connector.

→ *The 3C509B-COMBO edge connectors is shown in figure 24.*

The 3C509B-COMBO has a LED for the link beat. This LED confirms that there is an active connection between the adapter and the hub. The thin ethernet segment is terminated at both ends with a 50 Ω terminator.

The maximum bus speed supported by the Ethernet Adapter is 10 MHz.

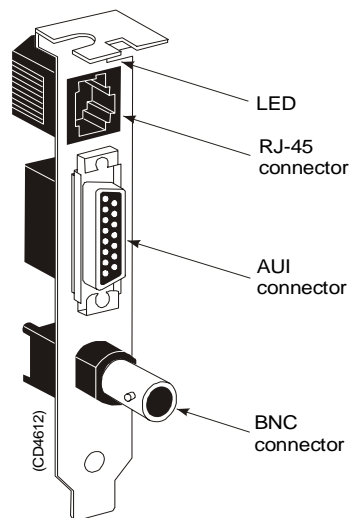


Figure 24 The 3C509B-COMBO backplate with its connectors

Facilities

LEDs

Confirms that there is an active connection between the adapter and the hub.

- If the LED is on, the link beat is working. (The connection is correct).
- If the LED is off, the link beat has not been established or there is a problem with the connection between the adapter and the hub.
- If the LED is blinking, the cable polarity is reversed.

→ *See figure 24*

Connections

The internal wiring gives access to the BNC and RJ45 connections at the bottom plate of the Transceiver Unit.

Setup of the board

If the type of ethernet cable is known at delivery time, the board is set up accordingly. If not, the board is set up for 10BASE-T (RJ-45).

It is difficult to reconfigure the board on site. (A PC with ISA-bus and special software is needed).

Processing Unit Power Supply

Purpose and description

The purpose of the power supply is to feed +5 Vdc, -12 Vdc and +12 Vdc to the Processing Unit. It also supplies 24 Vdc to the Sonar Head. It is located on the front side of the Standard Processing Unit.

How it works

This is a commercial switch mode power supply.

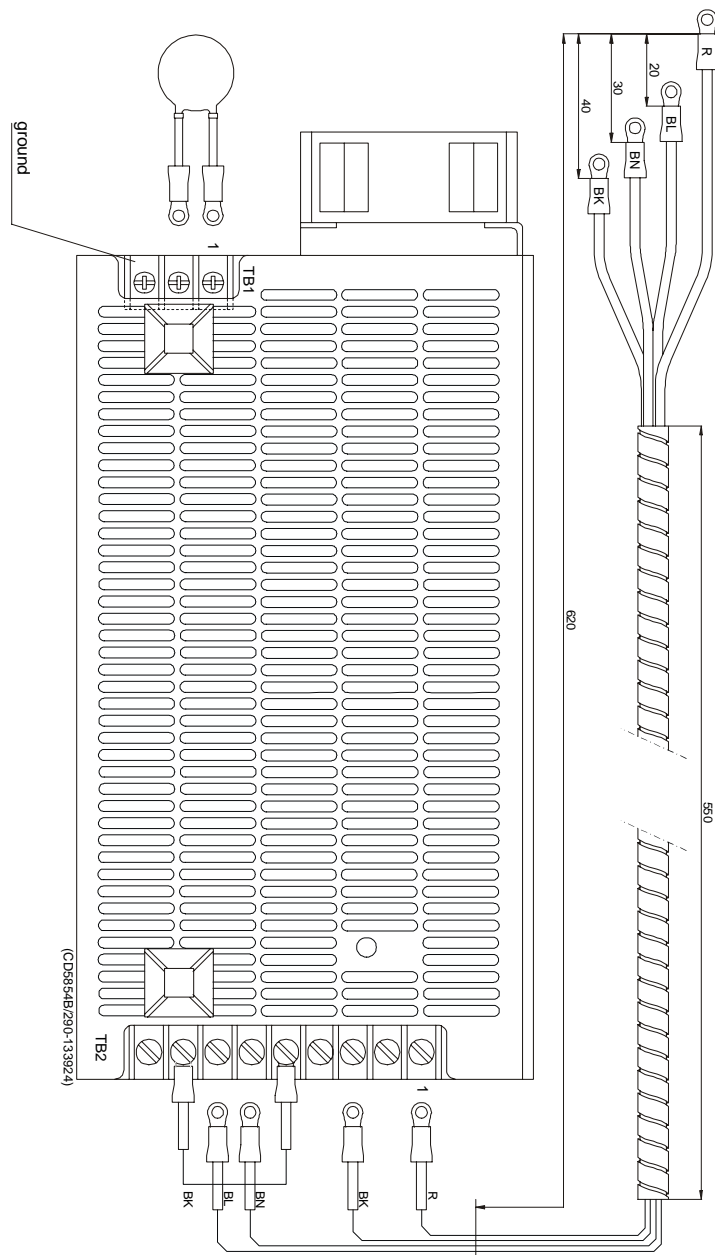


Figure 25 Power supply, wired

6 SONAR HEAD

6.1 Description and main functions

Overview

The EM 3000 Sonar Head contains the transducers and all transmitter and receiver electronics. It is the only part of the system that needs to be submerged in water.

A single cable with an underwater plug, connects the Sonar Head to the EM 3000 Processing Unit.

This chapter provides the following information:

- *Description and main functions, page 89.*
- *Sonar Head outline, page 90.*
- *Circuit boards and modules, page 94.*
- *Theory of operation, page 92.*
- *Sonar head, details, page 94.*

6.2 Sonar Head drawings

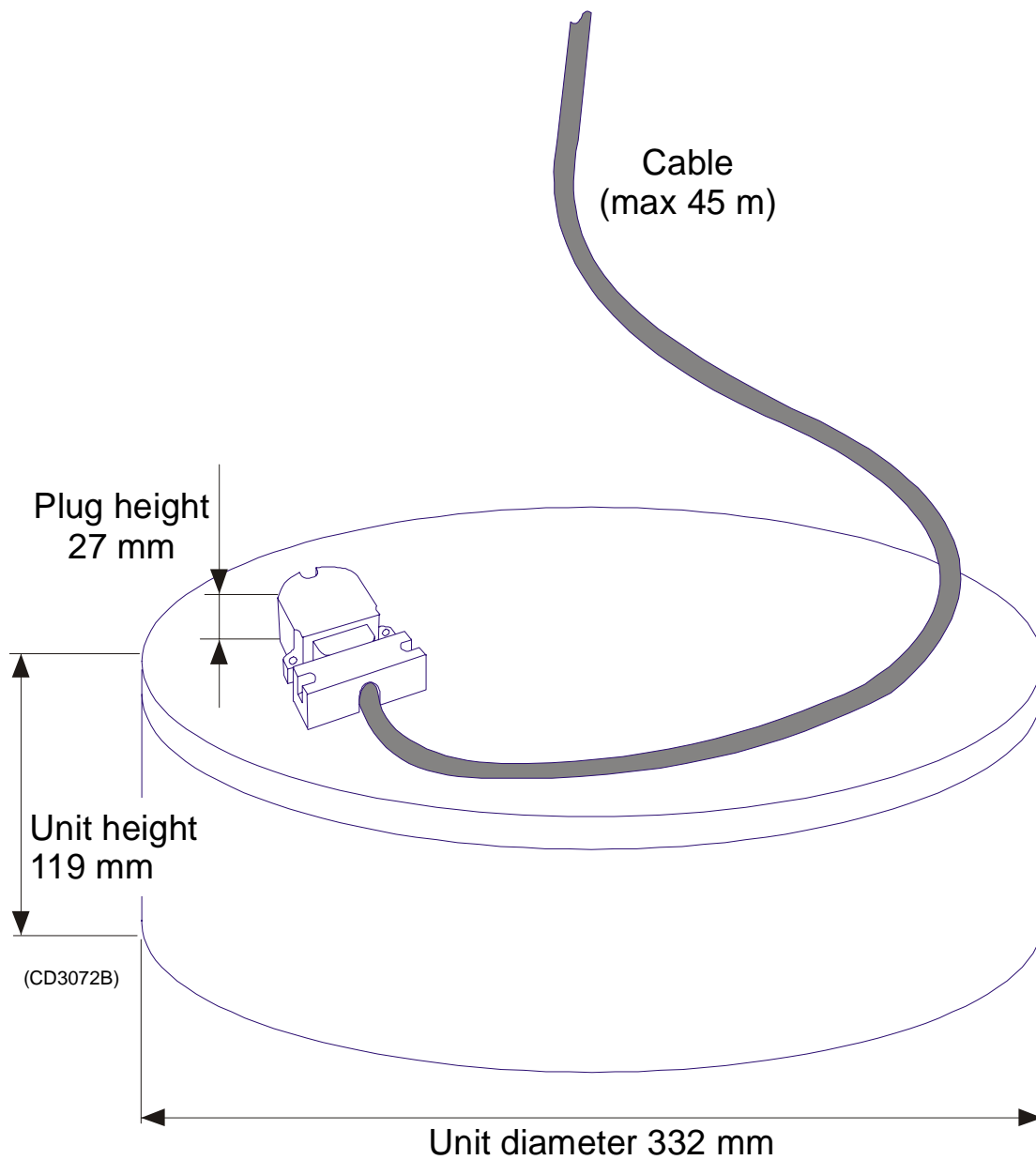


Figure 26 Sonar Head, outline dimensions

6.3 Circuit boards descriptions

Circuit boards descriptions

The Sonar Head is a watertight unit containing two circuit boards, a transmit transducer with 56 elements and a receive transducer with 80 staves.

→ *The Sonar Head - as seen from above - is shown in figure 27.*

- HRX board
- HCT board

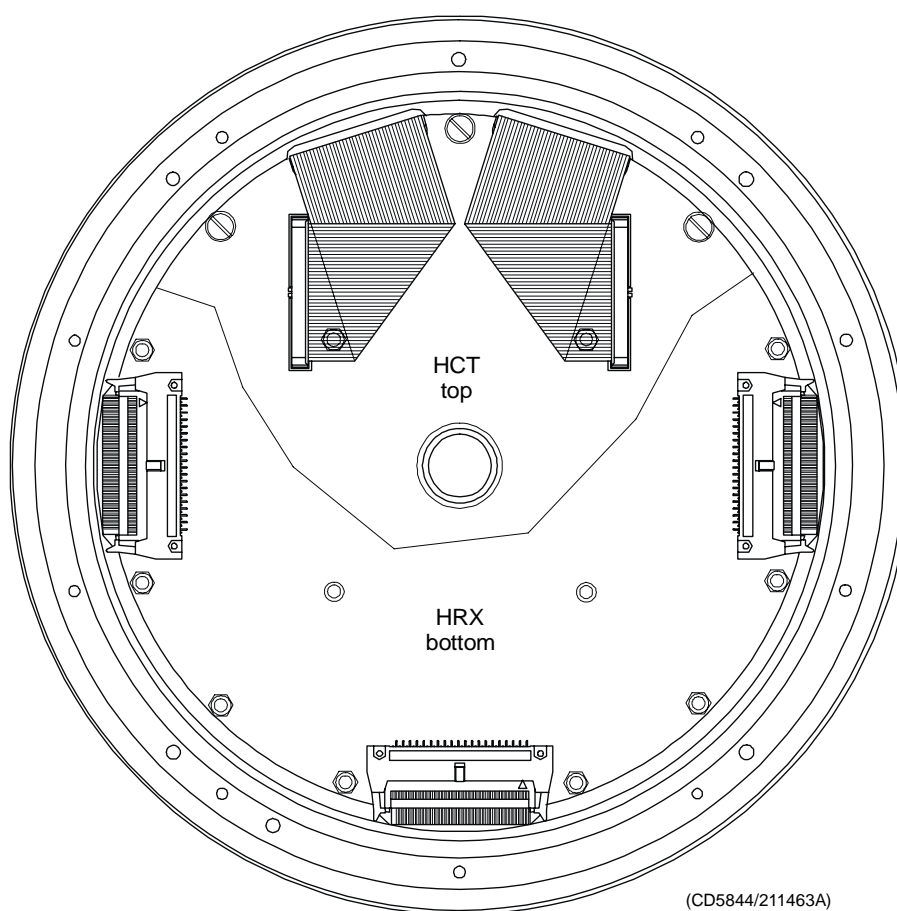


Figure 27 the Sonar Head

6.4 Theory of operation

Overview

This chapter presents a functional description of the Sonar Head.

Note

Figure 28 shows the EM 3000 system with a dual head. That is why two BSP boards and two BIF boards are mentioned. If your system only has a single head, there is only one BSP board and one BIF board.

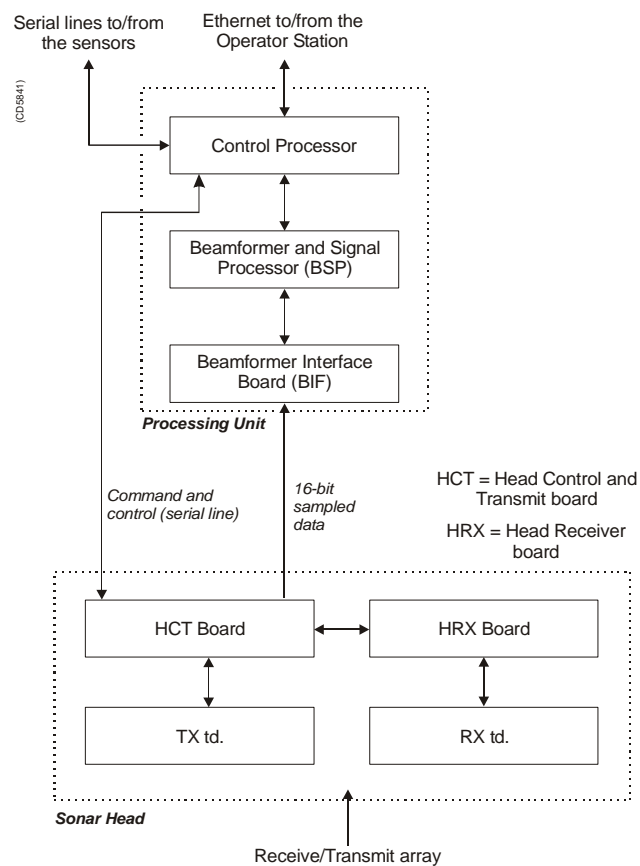


Figure 28 EM 3000, simplified block diagram

Simplified block diagram

The diagram presents the following main functions:

- Transmission
- Reception
- Processing

→ Refer to figure 28.

Control functions

The control functions in the Sonar Head are handled by the HCT board.

6.5 Sonar Head details

Circuit boards and modules

Head Control and Transmit (HCT)

The HCT receive commands from the host computer.

→ *The board is described on page 95.*

Head Receiver (HRX)

The HRX is a 80 channel receiver, that together with the HCT PCB, is a complete 80 channel transceiver unit.

→ *The board is described on page 97.*

HCT board

Purpose and description

This board is, together with the HRX board, designed to control transmit and receive tasks in the EM 3000 Sonar Head.

The Head Control and Transmit (HCT) board receive commands from the host computer, on half duplex RS-485 serial line, and send data out on a high speed serial line (TAXI link). Its purpose is to transmit amplitude and phase variation into the 56 TX channels. It should also read data from the 80 RX channels on the HRX board.

The board is connected to the HRX board, the TX transducer and the Processing Unit through separate connectors.

Note

This board should only be repaired, tested or maintained by Kongsberg Maritime AS or other personnel approved by Kongsberg Maritime AS.

Facilities

LEDs

None

Test Points

Testpoint	Function
TP01	TX_HV. Transmit voltage
TP02	Not mounted
TP03	Not mounted
TP04	Not mounted
TP05	RENTXFIFO~. Transmit from TX fifo(TXENABLE)
TP06	Not mounted
TP07	4xRXFREQ. Four times RX frequency to PDH
TP08	Not mounted
TP09	RSDATI. RS485 data input from PU
TP10	RSDATO. RS485 data output from PU
TP11	Not mounted
TP12	SAMP-INT~. Sample interrupt to CPU
TP13	Not mounted
TP14	Not mounted
TP17	RST~.Reset input to processor.
TP18	Chassis. Connect GND to chassis.
TP22	Not mounted

TP24	TAXI_STRB. Write signal to taxi transmitter
TP25	TVG voltage to PDH
TP28	FILTCLK. Filter clock to PDH
TP29	IFX_VPP. Program voltage to PLD
TP30	GND point for scope
TP31	IS~. IO strobe from CPU
TP32	DS~. Data strobe from CPU
TP33	STRB~. Strobe signal from CPU
TP34	PS~. Program strobe from CPU
TP35	Not mounted
TP36	Not mounted
TP37	Not mounted
TP38	+ 5V digital

Connections

Electrical Interface, interconnection sockets:

P1	Connector to TX transducer
P2	Connector to TX transducer
P3	Connector to Processing Unit
P4	Connector to DSP emulator
P5	Connector to Flexlogic PLD
P6	Taxi connector
P7	Taxi connector
P8	Control Interface to HRX

HRX board

Purpose and description

The circular HRX board is mounted between the HCT2 board and TX/RX transducer modules.

Power supplies and all control signals to the HRX are supplied by the HCT2 board. There are no links on the board, but a few test points are added.

The Head Receiver PCB (HRX) is a complete 80 channel receiver system, and consists of the following functions:

- 20 4-channel TVG-amplifier and demodulator hybrids (PDH)
- 20 8-channel 12 bit A/D converters for digitising phase- and quadrature signals
- Bus Interface circuits

The HRX has interface for test-signal injection. All digital control signals, TVG control voltage and power supplies are supplied by the HCT (Head Control and Transmit PCB).

How it works

The main function blocks are:

- 20 “rxad” blocks
- One ana_ctrl block
- One dig_ctrl block

The rxad - receiver and analog to digital converter block, consist of four identical receiver channels. On the left side of the blocks the channel numbers and plug pin numbers are shown.

The ana_ctrl block consist of the analog circuit functions for the BITE test signal, TVG control and AD-converter reference voltage.

The dig_ctrl block consist of the digital circuit functions for the bus interface between the HRX and HCT.

The signals from the transducers are brought through a matching filter, that has an input impedance of about 3 kohm. The input signal is amplified in the VCA (Voltage Controlled Amplifier). This is located on the PDH hybrid with the rest of the modules.

The signal is then filtered in a low-Q bandpass filter, and through a second amplifier before being applied to the quadrature demodulator.

The quadrature demodulator. consist of two parallel channels, each with a mixed, programmable amplifier (0 - 30 dB in 6 dB steps), switched capacitor lowpass filter and simultaneous sample/hold amplifiers.

FacilitiesLEDs

None

Test points

Testpoint	Function
TP01	AVCC, +5V analog supply
TP02	AGND, analog ground
TP03	AVEE, -5V analog supply
TP04	VTEST, BITE test signal
TP05	VCTRL, TVG control voltage
TP06	ADCREF, 2.5V buffered reference voltage for AD-con-verters
TP07	GND, digital ground
TP08	VCC, +5V digital supply

Connections

Testpoint	Function
P1	Connector to the RX Transducer
P2	Connector to the RX Transducer
P3	Control Interface to the HCT

7 TROUBLESHOOTING

7.1 Messages (for UNIX only)

Introduction

The EM 3000 provides numerous messages to inform you of major and minor hardware and software errors.

The messages, if they occur, will be displayed in the Status Display in the Message field.

The different utilities operating on the EM 3000 Operator Station each issue several messages. These messages can be sorted in four categories:

- display warnings
- display errors
- warnings
- errors

The messages presented as **display warnings** and **warnings** merely point out small inaccuracies, and must be regarded as guidelines to the normal operation of the system.

The **display errors** and operational **errors** reflect major and minor hardware and software errors, some of which must be acted upon to ensure the normal operational capability.

The following chapters present all the possible messages, and briefly explain the proper action to be taken.

The information is provided as follows:

<Nxxx>: - <Message text>

Necessary action with applicable references.

<Nxxx> is the message identifier. The number will allow you to find the message easier in this document, and it tells you which utility issued it.

N - *module/utility identifier*.

xxx - *message identifier*

In the list below you will find one letter representing each module. Each module is described in its own chapter. The number **xxx** is only an identifier.

S: setup messages

W: ESO/workstation messages

L: launchpad messages

E: sound speed profile editor messages

P: Ping Display messages

p: Transceiver / Processing Unit messages (Hardware messages)

The **Hardware** and **CPU CMOS setup** messages are presented with the exact same layout. The Hardware messages also start with a message identifier <Nxxx>, and have a following message text.

The message text contains an error code which has to be decoded to get the exact error condition.

Most display errors are equipped with a help-textfunction, giving additional help on the errors. This text will, in most cases, be identical to the action text found in this manual.

Setup messages

The following messages are presented by the **Setup** utility.

Display Warning

S10: - Remember to set correct Gain parameters when using Manual bottom detection!

Normal mode should be Range And Gain, which uses Automatic bottom detection!

This mode should only be used when automatic bottom detection doesn't work. Make sure that the Depth To Normal Incidence depth indicator has a sensible value - it should have a value fairly close to the expected depth.

Display Error

S15: - Unable to write BIST output buffer to printfile <filename>.

An attempt was made to open the printfile in the system defaults directory for writing, but the operation failed. You should have full read and write access to the directory and all files in the directory.

Display Error

S17: - Unable to write BIST output buffer to file <filename>.

An attempt was made to open the savefile in the system defaults directory for writing, but the operation failed. You should have full read and write access to the directory and all files in the directory.

Display Error

S18: - No reply to the current BIST test!

Each of the Built In Self Test (BIST) commands is required to give a response within a fixed period of time. The length of this period varies with the type of test. The Processing Units has sub-units that may not respond in time, but this should be reported back to the operator as part of the reply to the current BIST test.

If the Processing Unit does not respond within the allocated time period, you should try one of the other tests to see if this is a general problem. If this is the case, or if the problem persists, you should try rebooting the Processing Unit.

Display Warning

S21: - The profile is not deep enough, and should be extended. When you select the OK button, the profile will be sent to the profile editor for automatic extension.

All profiles used by the system require a maximum depth of 12000 meters. Profiles less deep will be extended by the system, starting from the original maximum depth. The extension is based on standard table values, with two points interpolated between last value pair in profile and first table value pair.

Error

S25: – The Profile contains errors and will not be used. Errors detected:

The same message is used for several types of warnings:

1. Out-of-bounds depth values. Legal interval is 0 - 12000m.
2. Out-of-bounds sound speed values. Legal interval is 1400 - 1700 m/s.
3. Fewer actual samples than stated in profile header, using actual no. of samples in profile.
4. Gradient anomalies checking two neighbouring value pairs.

Even though you are given the choice to use the profile, it is recommended that you use the profile editor to verify and correct it. Otherwise, the echo sounder soundings may suffer quality degradation.

Error

S28: – Too steep gradients...

If one or more of the samples are spike values, they should be removed from the profile.

Display Warning

S32: – The sound velocity profile <name> contains too few samples.

The profile header says that the profile contains less than two entries. At least two entries are required, and for any real life sounding that is really too few entries.

Display Warning

S33: – The sound velocity profile <name> contains more than 1000 samples!

The system is not designed to handle profiles exceeding 1000 depth/speed pairs. You should use the profile, or download again, using 1000 depth/speed pairs as a maximum.

Display Error

S37: – Sound Velocity Profile <name> was not found!

The specified profile was not located in the directory containing the sound speed profiles (\$SHAREDHOME). You could have misspelt the profile name, or the profile has been removed from this directory after it was selected. Try selecting the profile from the pull-down menu. This menu is updated every time it is opened, and should give you the exact list of available profiles.

Display Error

S50: – The file <filename> is not found in the \$HOME/<directory>, or in the \$NEPTUNEHOME/defaults directory.

Error

S61: – The following entries in the set-up-file are missing or contain an error in value specification:

All set-up parameters are checked when a set-up file is opened. Any parameters that are not within legal range or missing from the file will be listed in this message. By following the instructions, it is possible to get around the problem and recreate the set-up file. You may instead check if you have a backup version of the installation file in the system directory by selecting the 'File->Read...' option. You will probably find some older version of the file, because any modification of the installation parameters followed by a 'File-Save' creates a backup version of the file to be modified.

Display Error

S64: – Profile <name> has an error in line 1. The line should contain a space after the opening parenthesis and one space before the closing parenthesis. Correct the profile before reselecting...

According to the Simrad ASCII profile format, this space is required. You can fix the problem using a text editor. If you have downloaded the profile from an external source, please verify that your profile source or download programs adheres to the file syntax.

Display Error

S65: – Profile <name> has an error in line 1. It seems that the header does not contain the correct no. of elements. Create the profile before retrying.

The profile header should start with "(" and close with ")". One or both of these elements could not be located in the header line. You can fix the problem using a text editor. If you have downloaded the profiles from an external source, please verify that your profile source or download programs adheres to the file syntax.

Display Error

S66: – Sound Velocity Profile directory <name> not found!

The missing directory (\$SHAREDHOME) is created during installation, and should always be present. If not, it means that someone has modified the file system. You should reinstall the system to recreate the proper operating environment.

Display Warning

S69: – Profiles in Simrad Survey Format cannot be downloaded...

The system cannot use this format for sound speed profiles. These profiles are produced when logging data, based on a Simrad ASCII format profile selected by the user. If this ASCII profile is no longer available, and you would like to use it again, you could use the Profile Editor to convert the profile into the Simrad ASCII profile format.

Display Error

S70: – The BIST for SW version returned an empty string!

Each of the Built In Self Test commands will return with the result being displayed in the BIST output area. This message informs you that a reply arrived, but that the reply contained no text to be displayed. This is clearly an error. Please repeat BIST command to check if the problem is repeatable. Errors like this should not occur, and if the problem persists, you are advised to reboot the Processing Unit and restart the operation station software.

Error

S71: – The Set-up-file is empty. Do you want to reinstall the default Simrad file?

The file containing installation parameter set-up values was empty. When this happens, the system can automatically install the default version of the file. The file may have been corrupted during a program crash. Confirming installation of default file allows you to continue. Otherwise, the system cannot be operated...

Display Error

S73: – Format error in BIST return for SW version request!

Each of the Built In Self Test commands will return with the result being displayed in the BIST output area. This message informs you that a reply arrived, but that the reply did not match the expected format. This is clearly an error. Please repeat BIST command to check if the problem is repeatable. Errors like this should not occur, and if the problem persists, you are advised to reboot the Processing Unit and restart the operation station software.

Display Error

S74: – 'BSP Test' failed – do you want to reboot the BSP unit?

The BSP sub-unit may occasionally lock up, with no pings being produced from the echo sounder. When that happens, the BSP BIST command will fail with this message. It is, however, possible to restart the BSP without rebooting the Processing Unit. This will happen when you confirm that a reboot is wanted. When the boot is completed, you should run the BSP BIST command again to verify that the unit responds correctly.

Display Warning

S93: - Both Heads are currently deactivated! Pinging is disabled...

When configuring a dual head system, at least one of the heads must be set up with one of the available frequencies. Of course, an actual dual head requires both heads being assigned frequencies. A dual head system can also be configured as a single head system, assigning frequencies to only one of the heads.

Display Warning

S94: - You cannot use the same frequency on both sonar heads!

Because of interference problems, running both sonar heads with the same frequency is disabled.

Error

021 S93: - Both Heads are currently deactivated! Pinging is disabled...

When configuring a dual head system, at least one of the heads must be set up with one of the available frequencies. Of course, an actual dual head requires both heads being assigned frequencies. A dual head system can also be configured as a single head system, assigning frequencies to only one of the heads.

Error

022 S94: - You cannot use the same frequency on both sonar heads!

Because of interference problems, running both sonar heads with the same frequency is disabled.

Display Error

S96: - Environment 'MODULE_ADDRESSES' undefined!

The program cannot operate without the specified environment. Please verify that the correct start-up procedure is used.

Display Error

S97: - Network Configuration File not found! File: <filename>

The program cannot operate without the specified file. Please verify that the file specified by the environment 'MODULE_ADDRESSES' with hostname as extension is present in your home directory, and that you at least have 'Read' permission.

Error

S98: – Error in connecting to input socket for program <program name>.

The set-up program tries to open an input socket, but the operation failed. The most likely explanation, is that the port no. specified for the set-up program already is in use. Check if any of the programs started from a previous session of the system are still running. If so, terminate these programs. If you do not know how to do this, it will in most cases be sufficient to log out and then back in. This will terminate any running programs and free up resources. Then restart the operator station software...

Display Error

S147: – Error sending datagrams to Ping Display!

Communication with the Ping Display uses IP socket communication, where the Ping Display has opened a specific port for data input. This error occurs when the set-up program tries to send to that port. The most likely explanation is that the port no. specified for the Ping Display is in use by another program.

Display Error

S148: – No profile name entered!

You have not specified a profile name - the input field is empty. Enter a profile name to proceed...

Display Warning

S150: – The file <filename> was empty, and factory defaults was read. Please verify all settings and save all settings using the 'File->Save' menu option.

The specified file containing set-up parameters (runtime or installation) was empty. When this happens, the system automatically installs the default version of the file. The file may have been corrupted during a program crash.

Display Error

S151: – The file <filename> is not found in the \$HOME directory, or in the \$NEPTUNEHOME/defaults directory. After verifying the settings, you may create the file by using the 'File->Save' menu option. The program terminates when you select the OK button.

The specified file containing set-up parameters (runtime or installation) is missing from the system directory, and was not located in any of the predefined locations for the file. The error indicates that the system somehow has been corrupted, possible due to manual operations in the file system. It is advisable to reinstall the system to re-establish system integrity.

Display Error

S152: – Not able to copy the file <filename> to \$HOME/<filename>. The program terminates when you select the OK button.

The specified file containing set-up parameters (runtime or installation) was missing from the system directory, and could not be copied to this directory. Due to problems with the directory access. The error indicates that the system somehow has been corrupted, possible due to manual operations in the file system. It is advisable to reinstall the system to re-establish system integrity.

Display Error

S206: – Min. Depth must be less than Max. Depth!

It should be fairly easy to fix - just enter a minimum value less than the maximum value...

Display Error

S207: – Max. Depth must be greater than Min. Depth!

It should be fairly easy to fix - just enter a maximum value greater than the minimum value...

Display Error

S208: – Legal interval: [<value>, <value>]

The input value is outside the specified interval - re-enter value to proceed...

Display Error

S209: – Max. Port Angle – Max. Starboard Angle must be > 40!

The Max. Port Angle and Max. Starboard Angle are restricted with respect to the angle of each other in order to avoid too wide swath. Re-enter value, keeping the input value within restrictions indicated by the message.

Error

033 S209: – Max. Port Angle – Max. Starboard Angle must be > 40!

The Max. Port Angle and Max. Starboard Angle are restricted with respect to the angle of each other in order to avoid too wide swath. Reenter value, keeping the input value within restrictions indicated by the message.

Display Error

S211: – Couldn't locate Workspace of Main Program!

If this error occurs, it means that certain workspace functions will be disabled, but that the overall functionality will be present. It has been observed that restarting the Operator Station software may remove the problem.

Display Error

S212: - Couldn't connect to SMS Server!

Occurs when the program is started independent of the rest of the system, or when the operating environment is insufficiently defined. It means that none of the functionality based on running an integrated system will be present, thereby rendering the system inoperable. If restarting the system does not remove the problem, it is likely, that the easiest way to fix it is to reinstall the software.

Display Error

S213: - Illegal Window Configuration Command received: <command>

An unknown workspace or window command was received. Should not affect the main functionality of the program.

Display Error

S214: - Couldn't send status to SMS Server!

This is a serious error, which should not occur. It reflects internal corruption in the communication link with the rest of the system. It means that none of the functionality based on running an integrated system will be present, thereby rendering the system inoperable. If restarting the system does not remove the problem, it is likely, that the easiest way to fix it is to reinstall the software.

Display Error

S215: - Server Connection Broken!

This is a serious error, which should not occur. It reflects internal corruption in the communication link with the rest of the system. It means that none of the functionality based on running an integrated system will be present, thereby rendering the system inoperable. If restarting the system does not remove the problem, it is likely, that the easiest way to fix it is to reinstall the software.

Display Warning

S237: - No profile downloaded...

The system has not received any download profiles. When downloading takes place, the set-up program is notified of the profile name. So far, it seems that nothing has arrived.

Display Warning

S238: - Profile not located in profile directory!

When downloading takes place, the set-up program is notified of the profile name. The system has received a download profile, but it could not be located in the directory used for sound speed profiles.

Display Error

S239: – Sensor Offset + current sound speed exceeds maximum speed of 1700.0 m/s.

The system does not recognise sound speeds in water exceeding 1700 m/s. To correct, enter an offset value, which keeps the sum of sound speed and offset value below or equal to 1700 m/s.

ESO messages

The following messages are presented by the **ESO** utility.

Display error

W5: - Serial Set-up-file <filename> missing. Install Default file?

The specified file is either removed or renamed. However, the default file provided will enable all functions on a system not extended with a serial port expansion card.

Display error

W9: - No Serial input device is open! Select the 'Smart Probe Profile Inputs' as the current serial I/O function in the 'Workstation I/O Interfaces' menu.

The serial port specified for this function could not be opened as expected probably due to error in read/write permission, or that a non-existing device is specified in the set-up-file.

Display error

W12: - Unable to open temporary file <filename>!

The error occurs because of inaccurate read/write permissions to the system directory. This is either an installation error, or an error introduced after installation.

Display error

W17: - Input Error. To enable new input, you must reselect the current input function.

The input format was not recognised. Reading from the serial port was disabled to avoid further input, and must be reactivated by reselecting the input function.

Display warning

W22: - No probe samples logged!

The sampling of probe values was terminated, but no values were actually received. Check probe connections and serial port set-up.

Display warning

W26: - The file <name> was empty. Factory Defaults was used instead. Please verify settings and use the 'File -> Save' command to make settings permanent.

This means that the set-up-file somehow has been corrupted. (E.g. system crash, text editor). A workaround is to set all parameters in the menus as required, and recreate the set-up-file using the 'File->Save' command. If this is followed by the 'File->Read' command, full functionality should be restored. Alternatively, you could exit the program - remove the empty file - and then restart the program. This will enable you to install the default set-up-file delivered with the system.

Display error

W27: - The file <filename> is not found in the \$HOME directory, or on \$NEPTUNEHOME/defaults directory.

The set-up-file should be present in both the indicated locations. If you at any point have done a system upgrade, you should check for backup copies in any of the system directory backups in the login directory. Backup file syntax: ".eso_system<date_time>/ .esoSetup.serial". If no such files are found, search for the file on the CD-ROM containing the installation.

Display error

W28: - Not able to copy the file <filename> to \$HOME/.eso_system. Program terminates when you select the OK button.

The error occurs because of inaccurate read/write permissions to the system directory. This is either an installation error, or an error introduced after installation.

Display error

W29: -Not able to remove the file <filename>. Check access and owner of the file. Program terminates when you select the OK button.

The error occurs because of inaccurate read/write permissions to the system directory. This is either an installation error, or an error introduced after installation.

Display error

W30: - Unable to open device <device-name>!. You may have a permission problem.

The error occurs because of inaccurate read/write permissions to the specified serial port device. This is either an installation error, or an error introduced after installation.

Display error

W40: - The set-up file is incomplete. Verify all parameters. Then save your configuration using the 'File->Save Set-up' menu option. Then read the set-up using the 'File->Read Set-up' to reinitiate the system!

The file could be corrupted (system crash), or modified outside the program (text editor), accidentally removing parts of the file.

Display error

W41: - Incomplete SVP CALC profile received on the network...

When receiving from the network, AML CALC files are supposed to be received in one go, i.e. complete with both profile identifier and termination sequence. In this case, no termination sequence was found in input.

Warning

W43: - The device associated with this function is in active use by the following function:

<function>.

To use the selected function:

1. Switch OFF the other function
or
2. Change device associated with one of the two functions.

Warning

W44: - You must terminate any active functions before reading set-up file!

Warning

W45: - Could not open tide output file: <filename>. You may have a permission problem...

An attempt was made to open the tide file in the current survey directory, but the operation failed. You should have full read & write access to the directory and all files in the directory.

Correct the directory & file access and activate the tide input function again.

Warning

W46: - The <name> function cannot share device with the <name> function. Per definition, only the following functions may share device:

<list of functions>

These functions may all be active at the same time.

Warning

W53: - Serial Port input not recognised! To enable new input, you must reselect the last selected input function

The input received was not recognized. This could be due to errors in the format used for transmitted data, or, if a serial line is used, errors in setting up serial line characteristics.

Warning

W54: – Input buffer overrun – function disabled! To enable new input, you must reselect the currently disabled input function.

Error

W60: – The last command sequence to the probe failed. Repeat your latest action to retransmit sequence. If this message was issued when bringing up this window, select the 'Apply Settings' button in the 'Sampling Parameters' section to repeat sequence.

The probe did not recognize the last command issued. This could be caused by garbled serial line transfer. Verify your serial line settings and retry the command once again.

Error

W61: – No reply to last SV Plus command! Probe may be disconnected or without power...

Error

W62: Format Error in SV Plus Input!

The input from the probe was not recognized. This could be caused by garbled serial line transfer. Verify your serial line settings and retry the command once again.

Launchpad messages

The following messages are presented by the **Launchpad** utility.

Display Error

L12: - The following Program(s) should always run, but is still NOT running:

The Operator Station software is an integrated system, and is based on having a predefined set of programs running. If not, the echo sounder cannot be operated.

You may look for any messages related to the offending program in the 'Messages' area of the 'Status Display', or use the 'File->Print / View' menu item to bring up the 'Message Viewer'.

Select the icon for the offending program(s) to check for any messages that could help you locate and fix the problem.

Display Error

L13: - Echo Sounder Not Ready!

The Initial 'Power Up' Built In Self Test (BIST) has failed. Details may be found in the ESO Set-up BIST Self Test (Show->Testing) menu.

The Echo Sounder has a range of Built In Self Test (BIST) commands, testing various parts of the Sounder.

Every time the Operator Station software is started, a link to the Processing Unit is established and the Initial Power-Up-Test is performed. If this fails, the Echo Sounder is inoperable, and the operator should examine the error messages in the BIST test window in the Set-up-program.

Additional status information may be obtained using the other BIST tests available.

Display Error

L15: - Error in Runtime or Installation set-up values!

Must be corrected before activating!

All parameters go through verification checks. First while reading from the Set-up-file, and second while entering parameters manually. The reported error is detected while reading from a Set-up-file, and will block Echo Sounder operation until corrected.

Set the correct value for the offending parameter(s) in the set-up program, and use the 'File' menu 'Read' command to read the set-up back in.

This will automatically verify the new set-up.

Display Warning

L16: - No reply from PU on 'Time Request'. Logging NOT started!

When activating logging of data, the system timestamps some of the datagrams used in the process.

The time to use was requested from the Processing Unit, but the reply did not arrive within a fixed period of time. This may be due to a Processing Unit running at full capacity, or - if the situation continues, while having a normal load on the system - that you may have network problems.

Display Warning

L39: - The <program name> program has not yet registered.
Do you still want to wait for the program to come up?

When starting one of the programs used by the system, it will try to hook up to enable the necessary communication and supervision. If a program does not succeed with this initial registration or hook up, it may have problems in the initial phase of starting up.

Please refer to the 'Status Display, Messages Section' for possible error messages that may help sorting out the problems.

Display Error

L40: - The following Program(s) has not yet registered:

All programs started and supervised by the Launchpad establishes a communication link with the system when they are launched. The listed program(s) did not succeed in establishing this link. It could be that the program (s) crashed before the linkup was attempted. If so, the program(s) has no possibility to communicate with the rest of the system. You may try a manual start of the system in a window, to see if you can find any useful messages written in the window.

Warning

L45: - Error reading input datagram...

Reading from the communication input socket failed. This is a low-level error, and should not occur if the system managed to start properly. If the error persist, try terminating the system and restart the software again.

Display Error

L47: - The Initial Power Up Self Test failed.
Do you want to repeat the test?

Please refer to the test menus in the Echo Sounder Set-up program for details.

Warning

L52: - Sound Speed At Transducer deviates more than X m/s from the corresponding value defined by the current Sound Speed Profile!

The sound speed at transducer depth received from the probe exceeded the selected alarm offset 5 times in a row. You should verify that you are using the correct sound speed profile, and also verify the size of the alarm offset.

Warning

L54: - Current Center Depth exceeds original maximum depth from the current Sound Speed Profile!

Center Beam Depth = <depth>
Profile Max. Depth = <depth>.

The original profile had a maximum depth before the automatic profile extension extended the profile down to 12000 m. The depth you now are registering exceeds this depth. This could mean that your original profile isn't deep enough for this area.

Display Error

L59: - Echo Sounder Not Ready!
Error in Sound Speed Profile!

There are no samples in the current Sound Speed Profile! Verify & correct current profile, or select a new one! After doing this, you should run the Power Up Built In Self Test (BIST) to enable the system.

Display Error

L60: - Echo Sounder Not Ready!
Error in echo sounder set-up parameters!

All parameters go through verification checks. First while reading from set-up-file and second when entering parameters manually. The reported error is detected while reading from the set-up-file, and must be corrected before continuing! After doing this, you should run the Power Up Built In Self Test (BIST) to enable the system.

Display Error

L62: - No Processing Unit has been detected while scanning the Network.
Do you want to terminate the Launchpad?

The Operator Station is not receiving broadcast datagrams from the Processing Unit. The continuing flow of broadcast datagrams tells the rest of the system that the PU is still alive. To prevent gaps in the line and possible data corruption, logging was stopped. Possible reasons for loss of contact:

- . Processing Unit is not Powered On
- . Network Cable Problems
- . Configuration Errors
- . Processing Unit Hardware / Software malfunction

Error

L64: - Connection timeout - Logging switched Off!

The Operator Station stopped receiving broadcast datagrams from the Processing Unit. The continuing flow of broadcast datagrams tells the rest of the system that the PU is still alive. To prevent gaps in the line and possible data corruption, logging was stopped. Possible reasons for loss of contact:

- .Processing Unit is not Powered On
- .Network Cable Problems
- .Configuration Errors
- .Processing Unit Hardware / Software malfunction

Error

L65: - Connection timeout - Pinging switched Off!

The Operator Station stopped receiving broadcast datagrams from the Processing Unit. The continuing flow of broadcast datagrams tells the rest of the system that the PU is still alive. The system status was set to No Pinging. Possible reasons for loss of contact:

- .Processing Unit is not Powered On
- .Network Cable Problems
- .Configuration Errors
- .Processing Unit Hardware / Software malfunction

Error

L66: - Timeout in Processing Unit <-> Launchpad Connection!

The Operator Station stopped receiving broadcasts from the Processing Unit. The continuing flow of broadcasts tells the rest of the system that the PU is still alive. Possible reasons for loss of contact:

- .Processing Unit is not Powered On
- .Network Cable Problems
- .Configuration Errors
- .Processing Unit Hardware / Software malfunction

Display Error

L67: - Format Error in Processing Unit Broadcast!

The Processing Units broadcast their presence on the Network. Such a broadcast message was received, but did not meet the format specification.

Display Error

L76: - No reply to the Initial Power-Up BIST. Do you want to Retry?

The network connection is OK, but the Processing Unit is not responding. Cancel the current attempt. Power the Processing Unit 'Off' and then 'On' again. Then try restarting the operating software.

Display Error

L83: - Could not create Config-file!

An attempt was made to store the current layout configuration onto the system defaults directory, but the operation failed. You should have full read & write access to this directory.

Display Error

L84: - Error in retrieving 'All Workspaces' info!

This is an internal error in the Launchpad, and should never happen. If it does occur, it will be during saving of the layout configuration to file. You should then restart the Operator Station software, and try the same command once again. This error may indicate internal problems for the Launchpad program, and should be reported.

Display Error

L85: - Program <name> contains an error in the configuration-file start-string!

This is a serious error. An attempt was made to update the main configuration file from data in memory. The attempt failed because the internal information did not adhere to the syntax for this type of information. You should exit and restart the system to avoid loss of operational control.

Display Error

L89: - Could not create Log-file Backup!

An attempt was made to open the log-file in the system defaults directory, but the operation failed. You should have full read & write access to this directory.

Display Error

L99: - Not able to change to Raw Data Directory <name> when generating Survey Parameters file.

An attempt was made to change the internal working directory to the one used for raw data (\$RAWDATAHOME), but the operation failed. Please verify that you have full read, write & execute access to this directory.

Display Warning

L111: - Tape Operation Aborted!

Reason:

The reason for an aborted tape operation may vary. With the exception of a user-triggered abort, the reason stated in the message body originates from the operating system, but should be fairly easy to understand. Examples of this could be a message stating that the tape drive is offline or that no data cartridge is loaded.

Display Warning

L112: - You cannot delete the current survey!

The current survey could be active, meaning that the associated directories and files are in use for data storage and processing. Removal of the current survey is therefore prohibited.

Display Warning

L113: - The Log-file is quite large: size X Mb - reset recommended!

The messages in the log-file may be viewed using the 'File->Print / View' command. If the file contains too many messages, it may be prove too 'crowded' for practical purposes. It is recommended that you pay heed to the suggestions of reset offered by the system. Use the 'File->Reset Log-file' option. If you are afraid of loosing useful information, please note that any errors reported while logging data, is logged in a separate log-file along with the survey data. Also remember, that you are offered the option of backing up your log-file before resetting.

Display Warning

L114: - You cannot alter logging set-up while logging is Active!

Due to the programmed functionality of the system, some parameters (logging set-up & installation parameters) may not be modified, because that would disrupt proper functionality and data integrity.

Display Warning

L117: - The root partition of this system now has less than 2Mb space left...

If the disk space on the root partition falls to zero, you may experience various types of problems while operating the system. It is advisable to increase this space to a minimum of 10 - 20 Mb.

Display Warning

L118: - Both Heads are currently deactivated!
Pinging is disabled...

When configuring a dual head system, at least one of the heads must be set up with one of the available frequencies. Of course, an actual dual head requires both heads being assigned frequencies. A dual head system can also be configured as a single head system, assigning frequencies to only one of the heads.

Display Warning

L119: - You cannot use the same frequency on both sonar heads!
Pinging is disabled...

Because of interference problems, running both sonar heads with the same frequency is disabled.

Display Error

L120: - The main configuration file <filename> was not found. Since this is a vital file for the system, the Launchpad will terminate when you select the OK button...

This file contains the overall configuration of the operator station software. The system can't operate without this file. The file was copied to the system directory during installation, and may have been accidentally removed.

Display Error

L121: - Error(s) found in the Launchpad Configuration File!
When you select the 'OK' button, the file will be deleted and this program will terminate.
When restarting the system, the Factory Default Configuration File will be installed.

The Launchpad program uses a text-file to define which programs are included in the system. Quite a few bits of information are stored here, using a fixed syntax. This error occurs because the line for this program does not adhere to the syntax. An erroneous modification may have been done using a text editor. A new default version of the file will automatically be installed when restarting the system.

Error

L122: - There are too many entries in setup-file! Max = 18.

The configuration file contains all programs included in the integrated system, but may also contain programs added by the user. These programs may be started from the Launchpad, but are not supervised as the other programs.

The total number of entries has exceeded the maximum limit, probably due to manual modifications of this configuration file.

To restore the default file supplied by the system, remove the \$HOME/.eso_system/esoEmX_config file, and restart the system.

Error

L123: - Not able to obtain the icon for <this utility>!

Each of the programs integrated into the system has a button in the rightmost part of the Launchpad, and each of these buttons should have a symbol / icon for identification purposes.

The symbol name specified in the external configuration file was not found, indicating an error in the file, or a mismatch between the configuration file and the file containing the icon descriptions.

If this error occurs, a capital 'X' is drawn instead of the proper icon.

Error

L124: - Not able to obtain default icon!

Each of the programs integrated into the system has a button in the rightmost part of the Launchpad, and each of these buttons should have a symbol / icon for identification purposes.

The symbol name specified in the external configuration file was not found, indicating an error in the file, or a mismatch between the configuration file and the file containing the icon descriptions.

If this error occurs, a capital 'X' is drawn instead of the proper icon. This message indicates that the 'X' icon was not found.

Display Error

L137: - A survey name must be provided before this program can start!

Fill in or select a survey name to continue!

Display Error

L140: - Illegal character(s) in the Survey Name!

The characters ('>' or '<') are illegal as part of all file-names, survey-names and operator names. Space(' ') will be substituted with '_ '.

Display Error

L141: - Illegal character(s) in the Operator Name!

The characters ('>' or '<') are illegal as part of all file-names, survey-names and operator names. Space(' ') will be substituted with '_ '.

Error

L142: - Environment 'MODULES_ICON_FILE' not found, or empty! Fix and restart!

The file containing the icon descriptions used by the system cannot be located, because the environment variable, giving the name of this file, was undefined. All environment variables used by the system are defined when installing the system, so this message indicates a system installation error.

Error

L143: - Unable to open module icon description file <name> specified in environment 'MODULES_ICON_FILE'. Fix and restart!

The file containing the icon descriptions could not be opened. The file may be missing, or you do not have the proper file access.

Display Error

L144: - Program <name> (possibly specified by the environment symbol <symbol name> in the start-up script) was not found in the Network Configuration File.

File: DPC.addresses.<hostname>

The system cannot work until the problem is fixed, and will terminate when you select the 'OK' button.

The specified file contains network addresses and port no.'s for all programs attached to the system. The error occurs when the program listed in the error message does not have an appropriate entry in the file.

Display Error

L145: - Error opening Network Configuration File!

File: DPC.addresses.<hostname>

The system cannot work until the problem is fixed, and will terminate when you select the 'OK' button.

The specified file contains network addresses and port no.'s for all programs attached to the system. The error occurs when your program tries to access this file, but is denied access. Several possible reasons:

1. The file does not exist. Removed? Wrong Name?
2. You have no file system access.

Display Error

L146: - Error in connecting to socket given by <entry name> in the file: DPC.addresses.<hostname>.

The system cannot work until the problem is fixed, and will terminate when you select the 'OK' button.

All programs in this system have an entry in the specified file. The most likely reason for this problem is that this entry is in use by a process (program) running on the system now. If you cannot find and terminate such a process, then try logging out and logging on before restarting the system.

Display Error

L147: - The following environment variables are undefined:
<variable list>

Part of the system uses external definition of various elements used within the programs. One such type of external definition is Environment Variables. One or more of these are undefined, leaving the system without all information needed to function properly. The environment variables should be defined as part of the installation process, and these error points to either an error in the installation, or manual interference in the files defining these variables.

Display Error

L149: - Active Pos. Sys.: No Input...

The system does not receive any input from the positioning system defined as Active. This could be due to the wrong system being selected as Active. You should also check input port parameters in the set-up program, and finally, check that the cabling is OK and that the positioning system unit generates the correct datagrams.

Display Error

L150: - Heading Sensor: No Input...

The system does not receive any input from the system generating the Heading. This could be due to the wrong system being selected for Active Heading. You should also check input port parameters in the set-up program, and finally, check that the cabling is OK and that the unit from which heading is used, generates the correct datagrams.

Display Error

L151: - Attitude Sensor: No Input...

The system does not receive any input from the attitude sensor. You should check input port parameters in the set-up program, and that the cabling is OK. Also check that the attitude sensor generates the correct datagrams.

Error

L152: - Clock: No Input...

The system does not receive any clock input from the positioning system. You should check input port parameters in the set-up program, and that the cabling is OK. Also check that the positioning system generates the correct datagram.

Error

L154: - Logging of Survey Data to Disk was switched Off due to an error in the <name> program!

Refer to messages in the Status Display for further details.

Error

L155: - Logging of Raw Data to Disk was switched Off due to an error in the <name> program!

Refer to messages in the Status Display for further details.

Display Error

L163: - Quit Signal Received! System will shut down when you select the 'OK' button!

The system uses built-in mechanisms to handle signals (interrupts) originating both internally and externally. The type of signal is described in the message. All, except the external Terminate Signal, is caused by errors in the program.

Display Error

L164: - Floating Point Exeption! System will shut down when you select the 'OK' button!

The system uses built-in mechanisms to handle signals (interrupts) originating both internally and externally. The type of signal is described in the message. All, except the external Terminate Signal, is caused by errors in the program.

Display Error

L165: - Bus Error! System will shut down when you select the 'OK' button!

The system uses built-in mechanisms to handle signals (interrupts) originating both internally and externally. The type of signal is described in the message. All, except the external Terminate Signal, is caused by errors in the program.

Display Error

L166: - Segmentation Violation! System will shut down when you select the 'OK' button!

The system uses built-in mechanisms to handle signals (interrupts) originating both internally and externally. The type of signal is described in the message. All, except the external Terminate Signal, is caused by errors in the program.

Display Error

L167: - Terminate Signal Received! System will shut down when you select the 'OK' button!

The system uses built-in mechanisms to handle signals (interrupts) originating both internally and externally. The type of signal is described in the message. All except the external Terminate Signal, is caused by errors in the program.

Display Error

L168: - Illegal Instruction Signal Received! System will shut down when you select the 'OK' button!

The system uses built-in mechanisms to handle signals (interrupts) originating both internally and externally. The type of signal is described in the message. All, except the external Terminate Signal is caused by errors in the program.

Display Error

L169: - SIGNAL <signal no.> received! System will shut down when you select the 'OK' button!

The system uses built-in mechanisms to handle signals (interrupts) originating both internally and externally. The type of signal is described in the message. All, except the external Terminate Signal, is caused by errors in the program.

Error

L170: - Unable to create Process List!

An attempt was made to open the process id log- file in the system directory for writing, but the operation failed. You should have full read & write access to the specified file and directory.

Error

L171: - Unable to open Process List!

An attempt was made to open the process id log- file in the system directory for reading, but the operation failed. You should have full read & write access to the specified file and directory.

Display Error

L172: - The following Programs are still running, and must be terminated before continuing:

The operating software uses several programs in an integrated system. Each running program is represented internally as a process. It has been observed, mostly after a crash, that these processes may continue to be active when they should not have been. The system detects these processes when it is restarted, and will, on users confirmation, issue termination commands before the system continues initialisation. But on rare occasions, the termination signal sent to these processes fails, and manual intervention is required as instructed in the error message.

Display Error

L173: - The following Programs could not be terminated:

The operating software uses several programs in an integrated system. Each running program is represented internally as a process. It has been observed, mostly after a crash, that these processes continue to be active when they should not have been. The system detects these processes when it is restarted, and will, on user confirmation, issue termination commands before the system continues initialisation. But on rare occasions, the termination signal sent to these processes fails, and manual intervention is required as instructed in the error message.

Display Error

L176: - The following Program(s) should always run, but is still NOT running:

All programs started and supervised by the Launchpad establishes a communication link with the system when they are launched. The listed program(s) did not succeed in establishing this link. It could be that the program (s) crashed before the linkup was attempted. In that case, the program(s) has no possibility to communicate with the rest of the system. You may try to start the system manually in a window, to see if you can find any useful messages written in the window. These programs are so called system programs, and it will be impossible to run the system when they are not running as intended.

Display Error

L177: - Could not read Raw Data directory for survey <name>.

You do not have the correct access to the specified directory. Correct ownership of directories and files are defined when the system is installed, so this problem could be the result of a manual operation in the file system. Please verify that you have read, write & execute access to the storage directories for raw data (\$RAWDATAHOME).

Display Error

L178: - Not able to change to Survey Directory <name> when fetching Line Statistics file!

The system could not perform an internal change of directory to the specified directory due to error in directory access. You should have read, write & execute access to all directories and files in the data storage locations. Please verify and correct.

Display Error

L179: - Not able to change to Home Directory when fetching Line Statistics file!

The system could not perform an internal change of directory back to your login directory due to error in directory access. You should have read, write & execute access to all directories and files in the data storage locations. Please verify and correct.

Display Error

L181: - Not able to copy the file <filename> to \$HOME/<filename>. Program terminates when you select the OK button!

This is the file setting up the configuration of the status filed in the Launchpad. An attempt was made to copy this file from the system defaults directory, but failed. You should have read & write access to all files in the system directory and to the directory itself. Please verify and correct.

Display Error

L182: - Could not open Operators File!

Open a terminal window, and go to the \$HOME/.eso_system directory. Verify that you have both Read and Write access to the file 'esoSetup.operators'.

Display Error

L183: - Not able to copy the Status Config file to <directory name>. Using default values...

This is the file setting up the configuration of the status fields in the Launchpad. An attempt was made to copy the file from the system defaults directory, but failed. You should have read & write access to all files in the system directory and to the directory itself. Please verify and correct.

Display Error

L184: - Status Config file not found. Using default values...

This is the file setting up the configuration of the status fields in the Launchpad. It was not located in any of the predefined locations. This is an error by itself - but the system uses a default set-up, and will be operable. If you define a new status set-up, remember to save the set-up for later use.

Display Error

L186: - Could not init log-file!

It was not possible to create the file due to error in permissions. You should have read & write access to all files in the system directory and to the directory itself. Please verify and correct.

Display Error

L187: - Could not open log-file for append!

It was not possible to open the file for append due to error in file access. You should have read & write access to all files in the system directory. Please verify and correct.

Display Error

L189: - Line Statistics File could not be opened!

Survey: <survey name>

File: <line name>.linestat

The line statistics file for the specified line exists, but it could not be opened due to error in file access. You should have read, write & execute access to all files in the data storage directories. Please verify and correct.

Display Error

L190: - Statistics File for Survey <survey name>, line <line name> is empty!

The line statistics file for the specified line exists, but it was empty. It is difficult to state the reason for this, because all lines, no matter how small, should have something in this type of file. The file should be removed.

Display Error

L193: - Raw Data Parameters File for Survey <survey name> could not be opened!

The line parameters file for the specified line exists, but it could not be opened due to error in file access. You should have read, write and execute access to all data storage files and directories. Please verify and correct.

Display Error

L194: - Survey Parameters File for Survey <survey name>, line <line name> is empty!

The line parameters file for the specified line exists, but it was empty. It is difficult to state the reason for this, because all lines, no matter how small, should have something in this type of file. The file should be removed.

Display Error

L198: - Not able to change to Survey Directory <directory name> when fetching Line Statistics file!

There can be several reasons for this error, the most probable is that you don't have the correct access to the specified survey directory. Please verify that you have read, write & execute access to all directories in the \$PROCHOME location. '\$PROCHOME' is an environment variable defining the top location of your storage area for processed data (not raw data).

Display Error

L209: - You do not have WRITE access to file <name>.

You do not have the correct access to the specified file. Correct ownership of directories and files are defined when the system is installed, so this problem could be the result of a manual operation in the file system. Please verify that you have read, write & execute access to the shared system directory (\$SHAREDHOME) and all files and subdirectories.

Display Error

L212: - Operation cancelled!

Echo Sounder not ready!

The system was interrupted while performing a Power Up test. One of the main criteria for initiating the system is that the Power Up test is completed without error. When this test is cancelled, the system is defined to be inoperable. It will remain so until the test is completed successfully.

Display Error

L222: - Line Statistics File not found.

Survey: <survey name>

File: <line name>.linestat

The specified Line Statistics File does not exist. When terminating logging to a line, such a file is produced automatically. This error indicates that the file system has been manually modified.

Display Error

L228: - The file <filename> is not found on \$HOME/<name> directory, or on \$NEPTUNEHOME/defaults directory.

Since this is a vital file for the system, the Launchpad will terminate when you select the OK button...

The main configuration file is not located in any of the predefined locations. The system cannot be operated without this file. You should check if you have any backups of the system directory - one is made during every upgrade / reinstall of the system. If that fails, reinstall the system.

Display Error

L229: - The file <filename> is not found on \$HOME/<name> directory, or on \$NEPTUNEHOME/defaults directory.
Using default set-up...

The main configuration file is not located in any of the predefined locations. The system cannot be operated without this file. You should check if you have any backups of the system directory - one is made during every upgrade / reinstall of the system. If that fails, reinstall the system.

Display Warning

L230: - Operator <name> has no Config-file...

Use the 'Update Operator's 'Config-file' popup menu option on the 'All Programs' icon in the 'Programs' section of the Launchpad. This will generate a default file for the current operator.

Display Error

L231: - The file <filename> is not found on \$HOME/<name> directory, or on \$NEPTUNEHOME/defaults directory.

The specified file is not located in any of the predefined locations. The system cannot be operated without this file. You should check if you have any backups of the system directory - there is made one during every upgrade / reinstall of the system. If that fails, reinstall the system.

Display Error

L232: - Not able to remove the file <file name>.

Check access and owner of the file. Program terminates when you select the OK button.

You do not have the correct access to the specified file. Correct ownership of directories and files are defined when the system is installed, so this problem could be the result of a manual operation in the file system. Please verify that you have read, write & execute access to the system directory and all files in this directory (\$HOME/.eso_system).

Display Error

L233: - Unable to open Table Of Contents!

You do not have the correct access to the selected file. Correct ownership of directories and files are defined when the system is installed, so this problem could be the result of a manual operation in the file system. Please verify that you have read, write & execute access to the system directory and all files in this directory (\$HOME/.eso_system).

Display Error

L234: - Unable to open temporary copy of the log-file!

It was not possible to open the file, due to an error in file access. You should have read & write access to all files in the system directory (\$HOME/.eso_system). Please verify and correct.

Display Error

L235: - Cannot allocate enough memory for viewing the log-file. You should reset the file using the 'File->Reset Log-file' option.

The log-file was too big for the available memory resources. If it is important to view the log-file, you could try terminating as many of the programs as possible before retrying. If the problem persists, you should reset the log-file. When resetting, it is possible to take a backup copy of the log-file.

Display Error

L297: - Raw Data Parameters File for
Survey <survey name>
Line <line name>
could not be opened!

The parameter file for the specified survey exists, but it could not be opened due to error in file access. You should have read, write and execute access to all data storage files and directories. Please verify and correct. Due to the sequence of events producing this file, this error is not likely to occur.

Display Error

L298: - Survey Parameters File for Survey <name> does not exist!

The survey parameter file is based on the parameters for each line, and presents information regarding changes in line parameter set-up. For some reason, this file could not be produced. It may be, that there are no lines in the survey, or that the logged lines are corrupted.

Display Error

L299: - Raw Data Parameters File for
Survey <survey name>
Line <line name>
does not exist!

The file contains the parameter set-up being used when logging the line. For some reason, this file could not be produced. It may be that the logged line is corrupted.

Display Error

L300: - Environment variable for Network Configuration File not defined!

Some of the information required to have the system running properly, is set outside of the actual programs, using environment variables. The specified variable is not defined, and probably means an installation error, or manual modification in the definition of variables.

Display Error

L301: - Could not open Network Configuration File!

File: <filename>

It was not possible to open the file due to error in file access. You should have read & write access to all files in the system directory. Please verify and correct.

Display Error

L302: - Unable to open Serial Datagram Set-up-file

It was not possible to open the file due to error in file access. You should have read & write access to all files in the system directory. Please verify and correct.

Display Error

L303: - Unable to open Datagram Set-up-file!

File: <filename>

This file contains the datagrams available for subscription. It will not be possible to use the subscription facility without this file. You should have read & write access to all files in the system directory. Please verify and correct.

Display Error

L304: - Format error on input from Datagram Set-up-file!

File: <filename>

Datagrams available for user-defined distribution are defined using a fixed format. One or more of the entries in this file does not fit this format. The safest way to fix the problem is to remove the file, and restart the system. The file will then be copied to the system directory, using the default version supplied with the installation.

Display Error

L318: - Illegal format on IP address!

Format: ddd.ddd.ddd.ddd, where 'd' is a digit.

Leading zeros may be omitted.

The networking addresses used by the system must follow the specified syntax. Normally, if you have subscribers running on the same computer as the operating software, you should use the IP address of this computer.

Display Warning

L321: -This is the system's broadcast IP address, and cannot be deleted. If you were thinking of defining a new broadcast address, this one will be automatically adjusted whenever the system's IP address is modified.

When removing an IP address, all programs having the selected address will be modified. Since the selected address is of vital importance for the system, deletion or modification is not allowed. The address is used to establish and maintain the connection with the echo sounder.

Display Warning

L325: - You cannot change the datagram set-up of the system's reserved programs!

Currently, only user-defined datagram subscriptions may be modified. Allowing the user to modify the flow of datagrams needed for proper operation of the system could result in operational problems.

Display Warning

L326: - You cannot modify the IP address of the system's reserved programs!

Currently, only user-defined datagram subscription set-up may be modified. Allowing the user to modify the networking set-up, needed for proper operation of the system, could result in operational problems.

Display Warning

L327: - The specified IP Port no. is outside bounds!
Legal interval: [2000, 6000]

The interval is limited to avoid interfering with the internal port no. usage of the system. Using port no.'s already in use will give operational problems, both for the system programs and for user programs.

Display Warning

L328: - IP Port no. <port no.> is already in use by the <subscriber name> subscriber!
Legal IP Port interval: [2000, 6000]

Opening and using the same port no. for reading is not allowed. You may send datagrams to the same port no. from several programs, but since you are defining datagram distribution, you cannot use the same port as another program.

Display Warning

L333: - Logging cannot be started when Edit Mode is enabled in the Set-up menu!

The reason for this restriction is that when logging to a line is started, all current values of the installation parameters are logged with the data. And since only one such representation is possible per line, editing of these parameters is prohibited when already logging.

Display Error

L334: - PPS not received!

The system does not receive any input from the system generating the 1PPS. This could be due to the wrong system being selected for 1PPS. You should also check input port parameters in the set-up program, and finally, check that the cabling is OK and that the unit from which heading is used, generates the correct datagrams.

Display Warning

L335: - Initial Power-Up Test was interrupted! Echo Sounder Not Ready!

The initial power-up test was interrupted by the user. And since it is an absolute requirement that this test is successfully completed, this test should be performed (with no errors reported).

Display Warning

L336: - No Sound Speed Probe values received!

The system is supposed to receive Sound Speed Probe values, but does not receive any. Verify probe connections, set-up and power.

Display Error

L337: - Depth/Height Sensor: No Input...

The system is supposed to receive sensor input, but does not receive any. Verify sensor connections, set-up and power.

Warning

L355: - Unknown NMEA Telegram received...

The datagram received were not uniquely recognised. It seems to be a NMEA datagram, but one not supported by the system. The datagram may also contain format errors. Please refer to separate documentation on datagram definitions.

Error

L356: - Format Error in Remote Control Telegram!

The datagram received was recognised as a Remote Control datagram, but the content does not adhere to the datagram syntax. Please refer to separate documentation on datagram definitions.

Display Warning

L357: - Datagram subscriber 'remoteLogging' not defined!
Use 'Options->DatagramSubscriptions...' to enter 'remoteLogging' as a subscriber. Remember to supply IP address and port.no. to receive datagrams on!

The system has received a Remote Control datagram, but vital information is missing from the datagram distribution set-up. Without this, none of the remote control functionality will be available. The rest of the sounder will operate as normal.

Display Warning

L358: - No datagrams are selected for the 'remoteLogging' subscriber!
Use 'Options->DatagramSubscriptions...' and select datagrams for subscription for the 'remoteLogging' subscriber.

When using the Remote Control functionality, you must define a selection of datagrams that you want distributed to the 'remoteLogging' subscriber. Otherwise, nothing will flow to this subscriber, even though it is properly defined with an IP address and port number.

Display Error

L364: - The system is currently configured NOT to launch the Survey Display automatically. Changing this mode requires changing the configuration file...

Some installations have their own Survey Control software. The message indicates that the current configuration of the system has disabled this particular feature. Please refer to the documentation for information on how to enable this software.

Display Warning

L372: - Could not verify incoming profile!

The Profile Editor is already running, and profile verification is currently suspended. Terminating the current editor session will automatically bring up the received profile for verification.

Display Error

L400: - Could not open print tmp-file.

You do not have the correct access to a work-file in your own home directory. Correct ownership of directories and files are defined when the system is installed, so this problem could be the result of a manual operation in the file system. Please verify that you have read, write & execute access to your login directory and the files in this directory.

Display Error

L401: - Error in Launchpad Message Server Initialize!

Some system resources could not be allocated, because some other program is holding these resources. Check if any of the programs started from a previous session of the system are still running. If so, terminate these programs. If you do not know how to do this, it will in most cases be sufficient to log out and then back in. This will terminate any running programs and free up resources. Then restart the operator station software...

Sound Speed Profile Editor messages

The following messages are presented by the **SSP Editor** utility.

Warning

E10: - Profile contains fewer points than specified in Profile Header.
Using number of points read from file!

The profile may have been edited manually, creating a mismatch between header no. of entries and actual no. of entries. The profile was automatically corrected.

Warning

E11: - Profile contains more points than specified in Profile Header.
Using number of points read from file!

The profile may have been edited manually, creating a mismatch between header no. of entries and actual no. of entries. The profile was automatically corrected.

Warning

E13: - You have no WRITE access to profile directory <directory name>.

The profile directory is created with full Read and Write access when installing the system. This problem may be caused by manual modifications of the file system. Set the correct directory access before retransmitting.

Warning

E33: - The file <filename> containing the selected Sound Profile was not found.

Someone has deleted the selected Sound Velocity Profile from the disk after the list was created! The list was produced using only actual and existing profiles. If you have no idea how this could have happened, get in touch with the System Administrator.

Warning

E38: - You have no WRITE access to the selected Sound Velocity Profile directory!

The File Selection Box enables traversal of the file system directory structure, which means that you may select any directory as a storage area for the SV Profile - even those you do not have WRITE access to. If you are denied access to a directory that you would like to have access to, check the System Manager to see if this is permissible.

Warning

E42: - You have no DELETE access to the selected Sound Velocity Profile!

The profile directory is created with full Read and Write access when installing the system. This problem may be caused by manual modification of the file system. Set the correct directory & file access before retrying.

Error

E46: -

Environment 'SVP_EDITOR_MODULE_NO' not defined or empty!
Environment 'SVP_EDITOR_MODULE_NAME' not defined or empty!
These errors results in a program that does not work properly. Fix and restart!

Most of the variable elements of the system configuration can be configured outside the programs. This is done by quite a few 'environment variables', which is set to an initial value when installing the system, and then fetched by the programs when needed. The environment variables listed in the error message must be set to match the initial values.

Warning

E54: - Please use the 'Save As...' command to give the profile a name.

Warning

E56: - No points in Profile...

The editable buffer is empty. Create a profile using the New Profile command in the File menu. You may also use the Copy SV Profile or the Combine SV Profiles in the Edit menu.

Warning

E60: - Illegal Survey Format File Name: <filename>

The survey format profile name does not match the syntax, which is as follows:

<line_no_yyyymmdd_hhmmss_sensor_version>.sfsvp

The only way to correct this is to do a manual profile rename. Since the survey profiles are named automatically, this is an error that should not have occurred.

Warning

E61: - Empty file: <filename>

The file does not contain any samples, and cannot be used. It is not possible to state any reasons for this. The file should be removed from the profiles directory.

Warning

E62: - Currently no editable profiles in work area to save!

Ping Display messages

The following messages are presented by the **Ping Display** utility.

P32: – No information received from the ESO! Ignore this message if used in stand-alone mode.

When starting up, the program tries to get some information from the ESO system. But when running in a standalone mode, it does not receive any answer. The requested information is not important in the standalone mode.

If you get this message when running as part of the complete system, try restarting the operator software.

7.2 CMOS SETUP - AUV Processing Unit

Setup for Cool Monster (C3/400)

To change the setup you must mount a standard VGA card and connect a VGA monitor and a keyboard.

Main

System Time

System Date

Legacy Diskette A: [1.44/1.25 MB 31/2]

Legacy Diskette B: [Disabled]

Primary Master:

- Type: [Auto]
- 32 Bit I/O [Disabled]

Primary Slave:

- Type: [Auto]
- 32 Bit I/O [Disabled]

Secondary Master:

- Type: [Auto]
- 32 Bit I/O [Disabled]

Secondary Slave:

- Type: [Auto]
- 32 Bit I/O [Disabled]

Memory Shadow:

- CC00 - CFFF [Disabled]
- D000 - D3FF [Disabled]
- D400 - D7FF [Disabled]
- D800 - DBFF [Disabled]
- DC00 - DFFF [Disabled]

Memory Cache:

- Memory Cache: [Enabled]
- Cache System BIOS Area: [Write Protect]
- Cache Video BIOS Area: [Write Protect]
- Cache Extended Memory Area: [Write Back]
- Cache CC00 - CFFF: [Disabled]
- Cache D000 - D3FF: [Disabled]
- Cache D400 - D7FF: [Disabled]
- Cache D800 - DBFF: [Disabled]
- Cache DC00 - DFFF: [Disabled]

System Memory: 640 KB
Extended Memory: 62 MB

Advanced

Note

Setup Warning: Setting items on this menu to incorrect values may cause your system to malfunction.

Advanced Chipset Control:

- Graphics Aperture: [64 Mb]
- Enable memory gap: [Extended]
- EEC Config: [Disabled]
- SERR signal condition: [Multiple bit]

- 8-bit I/O Recovery: [4.5]
- 6 bit I/O Recovery: [4.5]

PNP OS Installed: [No]
Reset Configuration Data: [No]
Secured Setup Configurations: [Yes]

PCI Configuration:

- PCI Device, Slot #1
 - Option ROM Scan: [Enabled]
 - Enable Master: [Enabled]
 - Latency Timer: [0040h]
- PCI Device, Slot #2
 - Option ROM Scan: [Enabled]
 - Enable Master: [Enabled]
 - Latency Timer: [0040h]
- PCI Device, Slot #3
 - Option ROM Scan: [Enabled]
 - Enable Master: [Enabled]
 - Latency Timer: [0040h]
- PCI Device, Slot #4
 - Option ROM Scan: [Enabled]
 - Enable Master: [Enabled]
 - Latency Timer: [0040h]

PCI IRQ line 1: [Auto Select]
PCI IRQ line 2: [Auto Select]
PCI IRQ line 3: [Auto Select]
PCI IRQ line 4: [Auto Select]

PCI/PNP ISA UMB Exclusion:

- CC00 - CFFFF: [Available]
- D000 - D3FFF: [Available]
- D400 - D7FFF: [Available]
- D800 - DBFFF: [Available]
- C00 - DFFFF: [Available]

PCI/PNP ISA IRQ Resource Exclusion

- IRQ 3: [Available]
- IRQ 4: [Available]
- IRQ 5: [Available]
- IRQ 7: [Available]
- IRQ 9: [Reserved]
- IRQ 10: [Reserved]
- IRQ 11: [Available]
- IRQ 12: [Reserved]

Default Primary Video Adapter: [AGP]

ISA graphics device installed: [No]

Assign IRQ to PCI VGA [No]

PS/2 Mouse: [Disabled]

Keyboard Features:

- NumLock: [Auto]
- Key Click: [Disabled]
- Keyboard auto-repeat rate: [30/sec]
- Keyboard auto-repeat delay: [1/2 sec]

I/O Device Configuration:

- Local Bus IDE adapter: [Both]
- Floppy disk controller: [Enabled]
 - Base I/O address: [Primary]
 - Floppy Drive Swap: [Disabled]
- Serial port A: [Enabled]
 - Base I/O address: [3F8]
 - Interrupt: [IRQ 4]
- Serial port B: [Enabled]
 - Mode: [Normal]
 - Base I/O address: [2F8]
 - Interrupt: [IRQ 3]

- Serial port C: [Enabled]
 - Base I/O address: [3E8]
 - Interrupt: [IRQ 11]
- Serial port D: [Enabled]
 - Base I/O address: [2E8]
 - Interrupt: [IRQ 11]
 - Interface: [RS232]
- Parallel port: [Enabled]
 - Mode: [EPC]
 - Base I/O address: [378]
 - Interrupt: [IRQ 7]
 - DMA channel: [DMA 3]

Legacy USB Support: [Disabled]

Watchdog Setting:

- Mode: [Disabled]

Large Disk Access Mode: [DOS]

Halt On Error: [Yes]

Security

Supervisor Password Is: Clear

User Password Is: Clear

Set Supervisor Password: [Enter]

Set User Password: [Enter]

Password on boot: [Disabled]

Fixed disk boot sector: [Normal]

Diskette access: [Supervisor]

Virus check reminder: [Disabled]

System backup reminder: [Disabled]

Power

Power Savings: [Disabled]

Standby Timeout: [Off]

Auto Suspend Timeout: [Off]

IDE Drive 0 Monitoring: [Disabled]

IDE Drive 1 Monitoring: [Disabled]

IDE Drive 2 Monitoring: [Disabled]

IDE Drive 3 Monitoring: [Disabled]

PCI Bus Monitoring: [Disabled]

Boot

Floppy check: [Disabled]
Summary screen: [Disabled]
QuickBoot Mode: [Disabled]
Dark Boot: [Disabled]

Boot Device Priority

Hard Drive:

- SanDisk
- Primary Master
- Bootable Add-in Cards

Removable Devices

- Legacy Floppy Drives

ATAPI CD-ROM Drive

Network Boot

Onboard LAN RPL ROM [Disabled]

Format the Boot drive for SM 2000

- Format the Boot drive for SM 2000 to be a system drive. The flash disk is mounted as D:
 - format D: /s
- Copy the DOS boot files and VXWorks boot files for this SM 2000 system
 - The DOS files:
 - copy AUTOEXEC.BAT D:
 - copy COMMAND.COM D:
 - copy CONFIG.SYS D:
 - The VXWorks files
 - copy VXLOAD.COM D:
 - copy VXWORKS.ST D:
- Make the directory for DOS commands.
 - mkdir c:\dos

- Copy the DOS files that are needed.
 - copy COUNTRY.SYS
 - copy DISPLAY.SYS
 - copy EDIT.COM
 - copy EGA.CPI
 - copy FDISK.EXE
 - copy FORMAT.COM
 - copy HIMEM.SYS
 - copy KEYB.COM
 - copy KEYBOARD.SYS
 - copy MODE.COM
 - copy QBASIC.EXE
 - copy SETVER.EXE
 - copy XCOPY.EXE
- Make the directory for BSP programs
 - mkdir c:\BSP_2000
- Copy the files for the BSP cards.
 - copy BBOT.OUT
 - copy C44A.OUT
 - copy C44D.OUT
 - copy C44X.OUT
 - copy C50.OUT
 - copy HC.OUT
 - copy HCT_MON.OUT
 - copy CALIB.TXT

7.3 CMOS SETUP - standard Processing Unit

Setup for VI Per

Standard CMOS Setup

Date

Time

HARD DISKS	type	Mode
Primary Master	Auto	Auto
Primary Slave	Auto	Auto
Secondary Master	Auto	Auto
Secondary Master	Auto	Auto

Drive A: 1.44M, 3.5 in.

Drive B: None

Video: EGA/VGA

Halt On: All, But Disk/Key

BIOS Feature Setup

Note *While setting up the DiskOnModule or DiskOnFlash module, the CPU has to boot on the floppy drive!*

Boot Sequence: **A,C,SCSI**

Note *Remember to put back before booting from DiskOnModule!*

Boot Sequence: **C,A,SCSI**

Virus Warning: Disabled

CPU Internal Cache: Enabled

External Cache: Enabled

CPU L2 Cache ECC Checking: Enabled

Processor Number Feature: Enabled

Quick Power On Self Test: Enabled

Boot Sequence: C,A,SCSI

Swap Floppy Drive: Disabled

Boot Up Floppy Seek: Disabled

Boot Up NumLock:	On
Gate A20 Option:	Fast
Typematic Rate Setting:	Disabled
Typematic Rate (Char/Sec):	6
Typematic Delay (Msec):	250
Security Option:	Setup
PCI/VGA Palette Snoop:	Disabled
OS Select For DRAM > 64MB:	Non-OS2
Report No FDD Fpr WIN 95:	Yes

Video BIOS Shadow:	Disabled
C8000-CBFFF Shadow:	Disabled
CC000-CFFFF Shadow:	Disabled
D0000-D3FFF Shadow:	Disabled
D4000-D7FFF Shadow:	Disabled
D8000-DBFFF Shadow:	Disabled
DC000-DFFFF Shadow:	Disabled

Chipset Features Setup

SDRAM RAS-to-CAS Delay:	3
SDRAM RAS Precharge Time:	3
SDRAM CAS latency Time:	3
SDRAM Precharge Control:	Disabled
DRAM Data Integrity Mode:	Non-ECC
System BIOS Chacheable:	Disabled
Video BIOS Chacheable:	Disabled
Video RAM Chacheable:	Disabled
8 Bit I/O Recovery Time:	3
16 Bit I/O Recovery Time:	2
Memory Hole at 15M-16M:	Enabled
Passive Release:	Enabled
Delayed Transaction:	Disabled
AGP Aperture Size (MB):	64

CPU Warning Temperature: 66°C/151°F

Current System Temp:

Current CPU Temperature

CPU FAN Speed

VCCP: VTT:

VCC3: + 5 V:

+12 V: -12 V:

- 5 V:

Shutdown Temperature: 70°C/158°F

Power Management Setup

ACPI function: Disabled

Power Management: User Define

PM Control by APM: No

Video Off Method: V/H SYNC+Blank

Video Off After: NA

MODEM Use IRQ: NA

Doze Mode: Disable

Standby Mode: Disable

Suspend Mode: Disable

HDD Power Down: Disable

Throttle Duty Cycle: 62.5%

PCI/VGA Act-Monitor: Disabled

Soft-Off by PWR-BTTN: Instant-Off

PowerOn by Ring: Enabled

Resume by Alarm: Disabled

IRQ 8 Break Suspend: Disabled

**** Reload Global Timer Events ****

IRQ[3-7,9-15],NMI: Disabled

Primary IDE 0:	Disabled
Primary IDE 1:	Disabled
Secondary IDE 0:	Disabled
Secondary IDE 1:	Disabled
Floppy Disk:	Disabled
Serial Port:	Enabled
Parallel Port:	Disabled

PNP/PCI Configuration

PNP OS Installed:	No
Resource Controlled By:	Manual
Reset Configuration:	Disabled

IRQ-3 assigned to:	Legacy ISA
IRQ-4 assigned to:	Legacy ISA
IRQ-5 assigned to:	PCI/ISA PnP
IRQ-7 assigned to:	Legacy ISA
IRQ-9 assigned to:	Legacy ISA
IRQ-10 assigned to:	Legacy ISA
IRQ-11 assigned to:	Legacy ISA
IRQ-12 assigned to:	Legacy ISA
IRQ-14 assigned to:	PCI/ISA PnP
IRQ-15 assigned to:	PCI/ISA PnP
DMA-0 assigned to:	PCI/ISA PnP
DMA-1 assigned to:	PCI/ISA PnP
DMA-3 assigned to:	PCI/ISA PnP
DMA-5 assigned to:	PCI/ISA PnP
DMA-6 assigned to:	PCI/ISA PnP
DMA-7 assigned to:	PCI/ISA PnP

Used MEM base addr: N/A

Load BIOS Defaults

NO

Load Setup Defaults

NO

Integrated peripherals

IDE HDD Block Mode:	Enabled
IDE Primary Master PIO:	Auto
IDE Primary Slave PIO:	Auto
IDE Secondary Master PIO:	Auto
IDE Secondary Slave PIO:	Auto
IDE Primary Master UDMA:	Auto
IDE Primary Slave UDMA:	Auto
IDE Secondary Master UDMA:	Auto
IDE Secondary Slave UDMA:	Auto
On-Chip Primary PCI IDE:	Enabled
On-Chip Secondary PCI IDE:	Enabled
USB Keyboard Support:	Disabled
Init Display first:	PCI Slot
KBC input clock:	8 MHz
Onboard FDC Controller:	Enabled
Onboard Serial Port 1:	3F8/IRQ4
Onboard Serial Port 2:	2F8/IRQ3
UART Mode Select:	Normal
Onboard Parallel Port:	378/IRQ7
Parallel Port Mode:	SPP

Supervisor password

PASSWORD DISABLED

User password

PASSWORD DISABLED

IDE HDD Auto detection

Do not choose Disk On Module here, it should be set to auto:

Primary Master: No

Primary Slave: No

Secondary Master: No

Secondary Slave: No

Save and Exit Setup

YES

Processing Unit messages

The following messages are reported by the software monitoring the hardware circuitry in the Processing Unit.

After receiving error messages from the Processing Unit, you should always run the appropriate BIST tests to verify the hardware status.

Each bit in the trailing number indicates a specific error condition.

P480: Error status from the Processing Unit = 0x10000

The number is to be decoded as follows:

Sonar Head cross connection.

P480: Error status from the Processing Unit = 0x20000

The number is to be decoded as follows:

No attitude with this data.

Note

Please note that the four following messages are for the BSP 1.

P481: Error status from the BSP = 0x0100

The number is to be decoded as follows:

Link communication problem, HCT <-> BSP

P481: Error status from the BSP = 0x0200

The number is to be decoded as follows:

Communication problem, PU <-> BSP

P481: Error status from the BSP = 0x0400

The number is to be decoded as follows:

Communication problem, PU <-> HCT

P481: Error status from the BSP = 0x0800

The number is to be decoded as follows:

Internal problem BSP

Note

Please note that, in a dual head configuration, the four following messages are for the BSP 2.

P481: Error status from the BSP = 0x01000

The number is to be decoded as follows:

Link communication problem, HCT <-> BSP

P481: Error status from the BSP = 0x02000

The number is to be decoded as follows:

Communication problem, PU <-> BSP

P481: Error status from the BSP = 0x04000

The number is to be decoded as follows:

Communication problem, PU <-> HCT

P481: Error status from the BSP = 0x08000
The number is to be decoded as follows:
Internal problem BSP

Note

Please note that the four following messages are for the HCT 1.

P482: Error status from the HCT = 0x0001
The number is to be decoded as follows:
Temperature is over limit, power down.

P482: Error status from the HCT = 0x0004
The number is to be decoded as follows:
Voltage error.

Note

Please note that, in a dual head configuration, the four following messages are for the HCT 2.

P482: Error status from the HCT = 0x0010
The number is to be decoded as follows:
Temperature is over limit, power down.

P482: Error status from the HCT = 0x0040
The number is to be decoded as follows:
Voltage error.

7.4 CPU CMOS SETUP

Setup for SSC-486H

To change the setup you must mount a standard VGA card and connect a VGA monitor and a keyboard.

This setup is based on BIOS:KU26C-03B. Hit "DEL" key after power on and confirm/change to following settings in CMOS:

Advanced setup

Typematic rate (char/sec): 30

System keyboard: Absent

Primary display: Absent

Mouse support: Disable

Above 1MB memory test: Enable

Memory test tick sound: Enable

Parity error check: Enable

Hit "DEL" message display: Enable

Extended Bios RAM area: 0:300

Wait for "F1" if any error: Enable

System boot up num-lock: On

Numeric processor test: Enable

Wietek processor: Absent

Floppy drive seek at boot: Disable

System boot up sequence: A:,C:

System boot up CPU speed: High

External cache: Enable

Internal cache: Enable

Internal cache WB or WT: WR-thru

Turbo switch function: Enable

Password checking: Setup

Video shadow, C000, 16k: Enable

Video shadow, C400, 16k: Enable

Shadow, C800, 16k: Disable

Shadow, CC00, 16k: Disable

Shadow, D000, 16k: Disable

Shadow, D400, 16k: Disable
Shadow, D800, 16k: Disable
Shadow, DC00, 16k: Disable
Shadow, E000, 64k: Disable
IDE multi-sector transfer: Auto
Primary IDE 32-bit transfer: Disable
Primary IDE block mode: Master
Primary IDE LBA mode: Mas/Sla
Secondary IDE present: None
Secondary IDE 32 bit transfer: Disable
Secondary IDE Block mode: Disable
Secondary IDE LBA mode: Mas/sla

Peripheral setup

Onboard FDC: Enable
Onboard IDE: Enb-pri
Serial port 1: 3F8h
Serial port 2: 2F8h
Parallel port: 378h
Parallel port mode: Normal
Parallel extended mode: ECP

Chipset setup

Auto config function: Enable
Cache read: 3-2-2-2
Cache write: 1 ws
DRAM wait: 1 ws
DRAM page: Fast
Keyboard clock: 9.5 MHz
AT clock select: PCLK/4
Local ready: Delay 1T
CPU ADS# delay: No delay
Alt bit in tag SRAM: 7+1 bit
Signal LDEV# sample time: in T3
HW DRAM parity check: Disable

ISA bus refresh disable bit: Fast
DRAM refresh method: Ras only
Devicer for refresh: Reserved (1/1)
Video ROM cache C000, 16k: Disable
Video ROM cache C400, 16k: Disable
Adapter ROM cache: Disable
System memory remap or not: Enable
LOWA20# select: Chipset
RC reset select: Chipset
IO recovery time select: 5 BCLK
Hold CPU percentage: Disable
Software flush 80486: Disable
Enable force read miss: Disable

Setup for SSC-5x86H

This setup is based on Award Bios v4.51G. ICP version KU35-LSV3.2. Hit "DEL" key after poweron and confirm/change to following settings in CMOS:

Standard setup

Primary Master: None
Primary Slave: None
Drive A: None
Drive B: None
Video: EGA/VGA
Halt on: All, but keyboard

BIOS features setup

Virus Warning: Disabled
CPU internal cache: Enabled
External cache: Enabled
Quick power on self test: Disabled
Boot sequence: A,C
Swap floppy drive: Disabled
Boot up floppy seek: Disabled
Boot up Numlock status: On

Boot up system speed: High
Gate A20 option: Fast
Memory parity check: Disabled
Typematic rate setting: Disabled
Typematic rate (chars/sec): 6
Typematic delay (msec): 250
Security option: Setup
PS/2 mouse functional ctrl: Disabled
PCI/VGA Palette snoop: Disabled
OS selector for DRAM>64Mb: Non OS2
Video bios shadow: Enabled
C8000-CFFFF Shadow: Disabled
D0000-D7FFF Shadow: Disabled
D8000-DFFF Shadow: Disabled

Chipset features

Auto configuration: Enabled
AT-BUS CLK: CLK/4
DRAM read timing: Normal
DRAM write timing: Normal
SRAM read timing: 3-1-1-1
SRAM write timing: 0 Wait
Hidden refresh: Disabled
Memory hole (15M-16M): Disabled
ISA I/O recovery: Enabled
Fast back to back: Enabled

Power managment setup

Power Management: Disable
PM control by APM: Yes
Video Off Option: Susp/stby -> OFF
Video Off Method: V/H Sync+Blank
MODEM use IRQ: 3

PM TIMERS

HDD power down: Disabled

Doze mode: Disabled

Standby mode: Disabled

Suspend mode: Disabled

PM EVENTS

VGA: Off

FDD (3F_xH): On

LPT & COM: LPT/COM

HDD (1F_xH): On

NMI: OFF

IRQ3 (COM2): On

IRQ4 (COM1): On

IRQ5 (LPT2): On

IRQ6 Floppy disk: On

IRQ7 LPT1: On

IRQ8 RTC Alarm: Off

IRQ9 IRQ2 redir: On

IRQ10 Reserved: Off

IRQ11 Reserved: Off

IRQ12 PS/2 Mouse: On

IRQ13 Coprocessor: Off

IRQ14 Hard disk: On

IRQ15 Reserved: Off

Integrated peripherals

On-chip Local Bus IDE: Disabled

Onboard FDC control: Enabled

Onboard UART1: 3F8/IRQ4

Onboard UART2: 2F8/IRQ3

Onboard paralell port: 378

Parallel port mode: Normal

7.5 BIST tests

Software data/version

Presents the software versions of the processors in the system.

Sonar Head Temp

This test checks the temperature inside the Sonar Head. The normal temperature inside the head is 20° C higher than the water temperature. If the temperature exceeds 70° C, an alarm message is issued.

If the Sonar Head contains a humidity sensor, the reading from this will also be displayed. Normal humidity should be approximately 40%.

BIF / BSP

This test checks the communication between the Beamformer Interface (BIF) and the Beamformer and Signal Processing (BSP) circuit boards in the Processing Unit. It tests the ISA-bus interface, but, the TAXI communication link is not tested. The Processing Unit uses the BIF ISA-bus interface to load known data into the Beamformer & Signal Processor (BSP) board. The BSP processors read and verify these data.

- The equivalent isotropic noise level for each receiver channel (ref 1 V per μ Pascal)

BSP test

This test check the Beamformer and Signal Processing circuit boards in the EM 3000 Transceiver Unit.

Sonar Head HCT pcb

This is a self test of the Head Control Transmit (HCT) circuit board in the Sonar Head.

Sonar Head Serial No

This test reads the serial number(s) from the Sonar Head(s) connected to the EM 3000 Processing Unit. The numbers for the Sonar Head, the Head Receiver (HRX) and the Head Control Transmit (HCT) circuit boards are returned to the message field.

Rx Channels

This test tests all the receiver channels.

This test checks the amplitude and phase on all the receiver channels. A test signal is injected into all the receivers. Data for all channels are sent on the TAXI link to the Beamformer & Signal Processor (BSP) board. The test signal is then turned off, and the BSP uses the data samples to verify the amplitude and phase response on all the RX channels.

Sonar Head Power

The analogue ± 5 Vdc, the digital +5 Vdc and the +15 Vdc TX voltage levels in the Sonar Head are measured. Acceptable deviations for the 5 Vdc supplies are ± 0.25 Vdc, and ± 1 Vdc for the 15 Vdc supply. The status and the measured values are returned.

Noise test

This test measures the noise level on all the receiver channels.

Time Varied Gain (TVG) and fixed gain is set to a maximum level, and data for all channels are sent on the TAXI link to the Beamformer & Signal Processor (BSP) circuit board. The data is analysed by the BSP, and results are displayed.

Normally, the noise level is due to electronic self noise in the preamplifier circuitry. A very high noise level in the water - either from the vessel hull or machinery, or for other noise sources in the vicinity - may result in an increase in the noise level.

- The average equivalent isotropic noise level for all channels. (Typical value is 50-55 dB ref 1 V per μ Pascal).

TX Channels

One receiver channel is used to check the output from the transmitters. The Head Control Transmit (HCT) board transmits on each of the 56 transmitters, one by one. The signals are received on RX element number 80. Standard transmit pulse length of 0.15 ms is used. The average of 2 samples is taken and checked against a limit. If bad channels are discovered, the channel numbers are displayed.

TVG voltage

HCT (Head Control Transmit) board sends 10 different TVG-values (Time Variable Gain-values) and reads them back through an A/D converter and checks that the difference is not greater than 0.1 volt.

TAXI Link

This test checks the functionality of the TAXI communication link between the Processing Unit and the Sonar Head(s). The Head Control Transmit (HCT) board sends a fixed number of bytes with fixed values on the TAXI line. The Beamformer & Processor Board (BSP) verifies the data string. If an error is detected, a detailed error report will be displayed.

Reboot BSP cards

This is not a test, but a reboot of the BSP software in the Processing Unit. This should normally not be used.

8 REPLACEMENT PROCEDURES

8.1 Introduction

Overview

This chapter presents the basic procedures for disassembly and reassembly of the replaceable parts in the EM 3000 sonar system.

Tools required in general

A standard tool set is required to perform the removal and replacement of the modules. This tool set should contain the following tools:

- Cabinet key
- Standard screwdrivers in different widths and lengths
- Standard cross-slot screwdrivers in different widths and lengths
- Allen keys in metric sizes
- Philips screwdrivers in different sizes
- Pozidrive screwdrivers in different sizes
- Flat nosed pliers
- Lap jointed pliers
- Wire cutters
- Soldering iron
- Open ended and ring spanners in metric sizes
- Adjustable spanners
- Socket set

The following expendables are recommended:

- Solder
- Wire straps in different sizes

Tools required for changing boards in the Sonar Head

This list is a supplement to the list of tools required in general.

- Four 5mm screws
- Four 6mm screws
- Four (flat)washer for 6mm screws
- Six 4mm edge key
- Lubricant “AQUA LUBE”
- Lubricant Super-O-ring

8.2 Processing Unit procedures

Overview

The Line Replaceable Units (LRUs) in the EM 3000 Processing Unit are:

- 4-Ports Serial Line board
- Control Processor board (CPU)
- Beamformer & Signal Processor (BSP1 and BSP2)
 - Two boards if dual head
- Beamformer Interface (BIF1 and BIF2)
 - Two boards if dual head
- Ethernet Adapter
- Fan
- Motherboard

Other devices:

- AC mains fuse and filters
- Fuses

The replacement procedures for these parts are described in the following disassembly and reassembly procedures.

The modules that are accessible, are described in this chapter.

Circuit boards and modules

Introduction

The Processing Unit hold plug-in circuit boards and modules. The replacement of these modules is described in this procedure.

The system must be switched off prior to disassembly. Access is gained by opening the top and/or side panel(s) of the Processing Unit. How to open the Processing Unit is described under the Disassembly procedure.

Disassembly procedure

- 1 Remove the mounted cables from the applicable circuit boards.
- 2 Release the thumb-screws if required.
- 3 Pull the board/unit carefully out.

Reassembly procedure

- 1 Check links and switches on the new board and compare to the old board.

- 2 Insert new circuit boards and modules in reverse order. Mount the removed cables and the front covers.
- 3 Check that the circuit boards and modules have been installed in their correct locations! (Refer to the applicable pictures and drawings).

Fans

Introduction

Two of the fans are mounted on the bottom plate in the Processing Unit. One is mounted next to the Power Supply. Remember to switch off the system.

The system must be switched off prior to disassembly. Access is gained to the wired rack by opening the top panel of the Processing Unit. How to open the Processing Unit is described under Disassembly procedures of the Circuit boards and modules.

Disassembly procedure

- 1 When you have reached access to the fan, unscrew it, and remove the cable connected.
- 2 Replace the fan with a new one.

Reassembly procedure

- 1 Mount the screws, and put the cables back to their original place.

Power Supply

Introduction

How to open the Processing Unit is described under the Disassembly procedures of the Circuit boards and modules.

Disassembly procedure

- 1 Switch off the circuit breaker.
- 2 Unbolt the unit. It is mounted with four captive-bolts so they cannot fall out. The nuts and spring washers are accessible.

Reassembly procedure

The new power supply is replaced by reversing the above procedure.

8.3 Sonar Head procedures

Overview

Caution

The Sonar Head should not be opened by unauthorized personnel. We recommend that you contact your nearest Kongsberg Simrad office. When you open the Sonar Head, your insurance will no longer be regarded as valid!

The Line Replaceable Units (LRUs) in the EM 3000 Sonar Head are:

- HCT board
- HRX board

The replacement procedures for these boards are described in the following disassembly & reassembly procedures.

The modules that are accessible, are described in this chapter.

Introduction

The Sonar Head hold plug-in circuit boards. The replacement of these boards are described in this procedure.

The system must be switched off prior to disassembly. Before removing any modules, be sure that the voltmeter shows zero (0) volts. Access is gained to the wired rack by opening the top panel of the Sonar Head. How to open the Sonar Head is described under Disassembly procedure.

Disassembly procedure

Unscrew the ten titan screws with a 4 mm 6 edge key (Allen key).

Caution

When the cover is loose, be very careful! Do not remove it from the transducer house before you have removed the cables from the HCT board.

To change the HCT board (board on top):

- 1 Remove 11 screws, four nuts, one distance piece and 3 flat ribbon cables. (check with the drawings).
- 2 Change the board with a new one.
- 3 Mount the screws, nuts and cables back to their original place.

To change the HRX board (board at the bottom):

- 1 Remove the HCT board, the distance piece, the shield plate and three flat ribbon cables on the HRX board.

- 2 Change the board with a new one.
- 3 Mount everything back. (Check with drawings).

Reassembly procedure

- 1 Before mounting the cover to the transducer house, check the o-rings.

O-ring used in the cover is 259,3 x 5,7 MIL413. Simrad reg.number is 540-086946. O-ring used in the transducer house is 269,3 x 5,7 MIL413B. Simrad reg.number is 540-085883.

- 2 Use super-O-lube to lubricate the O-rings.
- 3 When mounting the cover to the transducer, connect the cables from the cover to the transducer. Check that the cables lays OK, and not in clamp between cover and transducer.
- 4 To press cover and transducer together, use the 6 mm screws and washers.
- 5 Before putting the titan screws back, be sure that they are OK. If not, change them. Use "AQUA LUBE".
- 6 Remove the 6 mm screws and washers. Screw the rest of the titan screws.

9 EM DATAGRAM FORMATS

9.1 Introduction

Note *The information herein is common for the EM 3002, EM 3000, EM 2000, EM 1002, EM 300 and EM 120 multibeam echo sounders. Some of the information may not be relevant for your specific system. Please disregard this.*

Note *The information in this document is not valid for the EM 12, EM 100, EM 950 and EM 1000 multibeam echo sounders.*

The formats for data input and output to and from the EM Series multibeam echo sounders are described here. The information given here is valid for the Kongsberg Maritime multibeam echo sounders introduced after 1995.

Note *In order to meet special customer requirements, Kongsberg Maritime may have to change the datagram formats described here. The formats presented in this document may therefore be altered without prior notice, although backward compatibility will be maintained as far as possible. Before software is written in accordance with this document, it is strongly recommended to contact Kongsberg Maritime to ensure that the latest version is used, and that any planned changes are taken into account.*

9.2 Presentation format

The format description is according to the NMEA 0183 standard for ASCII fields, with the ASCII character(s) given as follows:

- “x.x” defines a variable length numerical field, with optionally included decimal point and sign.
- “c--c” defines a variable length field of printable characters.
- “x--x” defines a variable length field of numeric characters.
- “a_ _” defines a fixed length field of alphabetical characters (for example “aa”= two character long field.
- “x_ _” defines a fixed length field of numeric characters.

For binary fields, the length is given in number of bytes plus “U” for unsigned and “S” for signed data.

9.3 Input datagrams

Introduction

Only a limited number of input formats from external sensors are accepted. These are primarily in accordance with the NMEA 0183 specification, or based upon the principles of that specification.

Note

The majority of these formats have not been defined by Kongsberg Maritime. Thus, these formats are not controlled by Kongsberg Maritime.

Almost all input formats are ASCII. Serial line input on the multibeam echo sounder's Processing Unit is most common, but some datagrams - which are not time critical - are interfaced on serial line(s) or Ethernet to the Operator Station.

Position

Overview

The EM Series accepts position data in the following formats:

- NMEA 0183 GGA
- GGK
- SIMRAD 90
- With the GGA and GGK datagrams, information contained in NMEA 0183 VGST and VTG datagrams will also be accepted and used.
- A datagram format for Sonar Head depth is provided for the EM 3002, EM 3000 and the EM 2000. Note that the format is the same as that used by the Paroscientific Digiquartz pressure sensor. This format may also be used for input of for example varying datum heights or other special height information on all models.
- A datagram format for input of tidal height is provided.

The **GGA format** is given below according to the NMEA 0183 version 2.30 description.

The **GGK format** was originally defined by the US Army Corps of Engineers for their tests with kinematic GPS.

Trimble's proprietary version of the format is supported. If any changes to the format are made if it becomes part of the NMEA standard, this will be implemented.

To preserve the inherent accuracy of the kinematic GPS data it is necessary to correct the data for vessel motion. This requires accurate timing synchronisation between the motion sensor and the GPS receiver. It is therefore imperative that:

- the position datagram has a constant and known time delay
- or
- the time stamp in the datagram is actually the time of the position fix, that synchronisation to the 1 PPS signal of the GPS receiver is enabled, and that the system clock has been set correctly

As neither of these conditions may not be possible to achieve with a sufficient accuracy, the application of motion correction is operator selectable. Motion compensation may be applied to any position input, not only kinematic GPS.

In addition to position data from the GGA or GGK datagrams, speed and course over ground from **NMEA VTG** datagrams may also be copied into the position output datagram. These values may be useful in filtering of the positioning during postprocessing. If a VTG datagram does not follow the GGA or GGK datagram the course and speed fields of the output datagrams will be set to their invalid values.

As an alternative to GGA, the **SIMRAD 90 format** position datagram may be used. The SIMRAD 90 format is intended to be the format of choice when the positioning system is not a stand-alone GPS receiver supplying GGA or GGK format datagrams. The SIMRAD 90 format can in addition to global longitude latitude coordinates also be used for Northing Easting type projection coordinates (e.g. UTM).

To cater for applications where the EM 2000 or EM 3000 Sonar Head is mounted on a subsea vehicle, the original SIMRAD 90 format has been expanded to allow inclusion of the depth of the vehicle in addition to its horizontal position in longitude latitude or Northing Easting coordinates.

GGA Datagram

Data Description	Format	Valid range	Note
Start identifier = \$	Always 24h	–	–
Talker identifier	aa	Capital letters	–
Sentence formatter	Always GGA,	–	–
UTC of position	hhmmss.ss,	000000 to 235959.9...	–
Latitude in degrees and minutes, plus optional decimal minutes	llll.ll,	0000 to 9000.0...	–
Latitude – N/S	a,	N or S	–
Longitude in degrees and minutes, plus optional decimal minutes	yyyyy.yy,	00000 to 18000.0...	–
Longitude – E/W	a,	E or W	–
GPS quality indicator	x,	0 to 8	1
Number of satellites in use	xx,	00 to 12	–
HDOP	x.x,	0 to	1
Antenna altitude re mean sea level (geoid)	x.x,	–	2
Units of antenna altitude	M,	–	–
Geoidal separation (sea level re WGS–84)	x.x,	–	2
Units of geoidal separation	M,	–	–
Age of differential GPS data	x.x,	–	–
Differential reference station id	xxxx,	0000 to 1023	–
Checksum	*hh	–	–
End of sentence delimiter = CRLF	Always 0Dh 0Ah	–	–

Note 1

The HDOP (Horizontal Dilution Of Precision) value will be scaled and copied to the "Measure of position fix quality" field in the position output datagram. The scale factor depends upon the GPS quality indicator's value:

- 1 - (SPS or standard GPS) => 1000
- 2 - (differential GPS) => 100
- 3 - (PPS or precise GPS) => 200, but 10 if GGA is treated as RTK. (See Note 2)
- 4 - (kinematic GPS with fixed integers) => 10
- 5 - (kinematic GPS with floating integers) => 50
- 6 - (estimated or dead reckoning mode) => 1000
- 7 - (manual input mode) => 1000
- 8 - (test mode) => 1000, but 10 if GGA is treated as RTK. (See Note 2)
- The "Measure of position fix quality" field will be set to 65534 (largest valid number) if the indicator is zero (non-valid position).

This scaling is used to give at least a relatively correct position fix quality change (in the order of cm) if there are dropouts in differential, precise or kinematic measurements, although HDOP is not a meter value.

Note 2

When the quality factor is 4 or 5 a height output datagram is automatically generated, and also if the quality factor is 3 or 8 and the operator has set the GGA position to be an RTK position. The height is the sum of these two fields which are assumed positive upwards (antenna above geoid).

GGK Datagram

Data Description	Format	Valid range	Note
Start identifier = \$	Always 24h	—	—
Talker identifier	aa	Capital letters	—
Sentence formatter	Always GGK,	—	—
UTC time of position	hhmmss.ss,	000000 to 235959.99...	—
UTC date of position	MMDDYY,	010100 to 123199	—
Latitude in degrees and minutes, plus optional decimal minutes	llll.lllll,	0000 to 9000.0...	—
Latitude – N/S	a,	N or S	—
Longitude in degrees and minutes, plus optional decimal minutes	yyyyy.yyyyyy,	00000 to 18000.0...	—
Longitude – E/W	a,	E or W	—
GPS quality indicator	x,	0 to 3	1
Number of satellites in use	xx,	00 to 12	—
DOP	x.x,	0 –	1
Antenna ellipsoidal height	x.x,	—	—
Units of antenna ellipsoidal height	M,	—	—
Checksum	*hh	—	—
End of sentence delimiter = CRLF	Always 0Dh 0Ah	—	—

Note 1

The DOP (Dilution Of Precision) value will be scaled and copied to the "Measure of position fix quality" field in the position output datagram. The scale factor depends upon the GPS quality indicator's value:

- 1 (SPS or standard GPS) => 1000
- 2 (differential GPS) => 100
- 3 (kinematic GPS) => 10

The "Measure of position fix quality" field will be set to 65534 (largest valid number) if the indicator is zero (non-valid position).

This scaling is used to give at least a relatively correct position fix quality change (in cm) if there are dropouts in differential, precise or kinematic measurements, although DOP is not a meter value.

VTG Datagram

Data Description	Format	Valid range	Note
Start identifier = \$	Always 24h	–	–
Talker identifier	aa	Capital letters	–
Sentence formatter	Always VTG,	–	–
Course over ground, degrees true	x.x,T,	0 to 359.9...	1
Course over ground, degrees magnetic	x.x,M,	0 to 359.9..	1
Speed over ground, knots	x.x,N,	0 –	1
Speed over ground, km/h	x.x,K,	0 –	1
Mode indicator	a	A,D,E,M,S or N	–
Checksum	*hh	–	–
End of sentence delimiter = CRLF	Always 0Dh 0Ah	–	–

Note 1

Only true course and the first valid speed field will be used.

Transponder position Datagram

SSB - SSBL Position:

Data Description	Format	Valid range	Note
Start_character	\$		
Address	PSIMSSB		
Time	,hhmmss.ss		2
TP code	,B01		3
Status	,A		4
Error code	,cc_		1
Coordinate system (always radians)	,R		
Orientation (always north oriented)	,N		
SW filter	,		1
X coordinate (Latitude)	,x.x		
Y coordinate (Longitude)	,x.x		
Depth (Sonar depth in m)	,x.x		
Expected accuracy (Pos. quality in m)	,x.x		
Additional info	,		1
First add value	,		1
Second add value	,		1
Checksum	*hh		
Termination	CRLF		

Note 1

Not used by multibeam echo sounders.

Note 2

Is decoded and used if Clock Synchronisation is set from position datagram.

Note 3

Only this transponder type is accepted by the multibeam.

Note 4

A = OK, V will give bad positions, but datagram will be accepted for logging.

Simrad 90 Datagram

Data Description	Format	Length	Valid range	Note
Start identifier = \$	Always 24h	1	–	–
Talker identifier	aa	2	Capital letters	–
Sentence formatter	Always S90,	4	–	–
Date of position	DDMMYY,	7	010100 to 311299	–
UTC of position as hour, minute, second, hundredth of second	hhmmssss,	9	00000000 to 23595999	–
Latitude in degrees, minutes and decimal minutes	xxxx.xxxx	9	0000.0000 to 9999.9999	A
Hemisphere identifier	a,	2	N or S	A
Longitude in degrees, minutes and decimal minutes, or depth in meters	xxxxx.xxxx	10	00000.0000 to 18000.0000	A
Hemisphere or depth identifier	a,	2	E, W or D	A
Northing or range in meters	xxxxxxxxx.x,	12	000000000.0 to 999999999.9	B
Easting or depth in meters	xxxxxxxx.x,	10	0000000.0 to 9999999.9	B
UTM zone number	xx,	3	01 to 60	–
User defined central meridian longitude or bearing	xxxxx.xxxx	10	00000.0000 to 35999.9999	C
Hemisphere or bearing identifier	a,	2	E, W, or B	C
System descriptor	x,	2	0 to 7	1
Position fix quality indicator	x,	2	0 to 9 and A to F	2
Speed over ground in m/s	xx.x,	5	00.0 to 99.9	3
Course over ground in degrees	xxx.x	5	000.0 to 359.9	3
End of sentence delimiter = ,CRLF	Always 2Ch 0Dh 0Ah	3	–	–

Note 1

Value of system descriptor defines content of datagram as follows. (Note that the Kongsberg Maritime EM 12, the EM 950 and the EM 1000 multibeam echo sounders will only accept values less than 3):

- **0** - The position is longitude latitude in global coordinates given in the fields noted A.
- **1** - The position is Northing Easting on the Northern hemisphere given in the fields noted B. If the projection is defined to be UTM the UTM zone number or a user definable central meridian longitude may be given in the field noted C.
- **2** - As for system descriptor equal to 1, but the position is on the Southern Hemisphere.
- **3** - As for system descriptor equal to 0, but in addition the depth is given in the Easting field noted B.
- **4** - As for system descriptor equal to 1, but in addition the depth is given in the longitude field noted A.
- **5** - As for system descriptor equal to 2, but in addition the depth is given in the longitude field noted A.

Note 2

The position fix quality given in the position output datagram will be derived from the quality indicator (this differs from the original definition of the format) as follows (in m):

F	E	D	C	B	A	9	8	7	6	5	4	3	2	1	0
0.01	0.02	0.05	0.1	0.2	0.5	1	2	5	10	20	50	100	200	500	1000

Note 3

If these fields have valid values they will be copied to equivalent fields in the position output datagram. They may be used in filtering of the positioning during postprocessing. (The original definition of the format had line heading in the course field and its use was to orient real-time displays).

Tide input

Data Description	Format	Valid range	Note
Start identifier = \$	Always 24h	—	—
Talker identifier	a	Capital letter	—
Sentence formatter	Always TIDE,	—	—
Date and time of prediction / measurement	YYYYMMDDhhmm,	199601010000 to 999912312359	—
Tide offset in meters and decimal meters	x.x	±327.66	1
Optional checksum	*hh	—	—
End of sentence delimiter = CRLF	Always 0Dh 0Ah	—	—

Note 1

A negative number will be assumed to indicate an increase in sea level.

Depth pressure or height input

Data Description	Format	Valid range	Note
Start identifier = *	Always 2Ah	–	–
Sentence identifier	ii	00 to 09	1
Talker identifier	ii	00 to 99	–
Depth or height in meters and decimal meters	x.x	–	2
End of sentence delimiter = CRLF	Always 0Dh 0Ah	–	–

Note 1

A sentence identifier equal to 00 is used for underwater vehicle depth, all other identifiers are customer specific (usually a datum height).

Note 2

If input is depth, it will be used in the depth output datagram to offset the transmit transducer depth. If input is height, which will usually imply a time or position variable datum height, its use will depend on the sentence identifier and will be implemented as required by a specific customer. Depth is positive downwards. Depths may be scaled and offset by operator settable constants:

$$\text{output_depth [m]} = \text{scale_factor} * (\text{input_depth} - \text{offset})$$

Attitude data**Overview**

Attitude data is generally accepted on one or more serial input port(s) as:

- roll, pitch, heave and heading on one port,
- or
- roll, pitch and heave on one port and heading separately on another port.

The data update rate should be commensurate with the expected dynamics of the vessel (typically up to 100 Hz).

The acceptable format for roll, pitch, heave and optionally also heading is a 10 byte long message originally defined in the EM 1000 for use with digital motion sensors. It is supported by the following sensors:

- Applied Analytics POS/MV
- Photokinetics Octans
- Seatex MRU
- Seatex SeaPath
- TSS DMS-05

Heading will be accepted in the NMEA 0183 HDT format or in the format used by the Simrad Robertson SKR80(82) gyrocompass. A current loop to RS-232 converter may then be required. The Lemkuhl LR40(60) Scan Repeater format is also accepted, as it is the same as that of the SKR80 with the exception of an extra status byte. Note that if the attitude sensor is capable of reading the gyrocompass and transfer the heading to the attitude sensor datagram (if it does not measure heading itself), this is preferable to interfacing the gyrocompass directly to the system.

Attitude data may be supplied from more than one sensor. All data may be logged, but only one set as chosen by the operator will be used in real time.

EM Attitude input format

The EM attitude format is a 10-bytes long message defined as follows:

- Byte 1: Sync byte 1 = 00h, or Sensor status = 90h-AFh
- Byte 2: Sync byte 2 = 90h
- Byte 3: Roll LSB
- Byte 4: Roll MSB
- Byte 5: Pitch LSB
- Byte 6: Pitch MSB
- Byte 7: Heave LSB
- Byte 8: Heave MSB
- Byte 9: Heading LSB
- Byte 10: Heading MSB

where **LSB** = least significant byte, **MSB** = most significant byte.

All data are in 2's complement binary, with 0.01° resolution for roll, pitch and heading, and 1 cm resolution for heave.

- Roll is positive with port side up with $\pm 179.99^\circ$ valid range
- Pitch is positive with bow up with $\pm 179.99^\circ$ valid range

- Heave is positive up with ± 9.99 m valid range
- Heading is positive clockwise with 0 to 359.99° valid range.

Non-valid data are assumed when a value is outside the valid range.

How roll is assumed to be measured is operator selectable, either with respect to the horizontal plane (the Hippy 120 or TSS convention) or to the plane tilted by the given pitch angle (i.e. as a rotation angle around the pitch tilted forward pointing x-axis). The latter convention (called Tate-Bryant in the POS/MV documentation) is used inside the system in all data displays and in logged data (a transformation is applied if the roll is given with respect to the horizontal).

Note that heave is displayed and logged as positive downwards (the sign is changed) including roll and pitch induced lever arm translation to the system's transmit transducer.

This format has previously been used with the EM 950 and the EM 1000 with the first synchronisation byte always assumed to be zero. The sensor manufacturers have been requested to include sensor status in the format using the first synchronisation byte for this purpose. It is thus assumed that:

- 90h in the first byte indicates a valid measurements with full accuracy
- any value from **91h to 99h** indicates valid data with reduced accuracy (decreasing accuracy with increasing number)
- any value from **9Ah to 9Fh** indicates non-valid data but normal operation (for example configuration or calibration mode)
- and any value from **A0h to AFh** indicates a sensor error status

HDT format

Data Description	Format	Valid range	Note
Start identifier = \$	Always 24h	—	—
Talker identifier	aa	Capital letters	—
Sentence formatter	Always HDT,	—	—
Heading, degrees true	x.x,T	0 to 359.9...	—
Checksum	*hh	—	—
End of sentence delimiter = CRLF	Always 0Dh 0Ah	—	—

SKR80 format

The SKR80 sends out a stream of data with four bytes for each measurement. There is one byte for each digit:

- The first byte for the decimal degree (Example: xxx.X)
- The second for the degree (Example: xxX.x)
- The third for the 10's degree (Example: xXx.x)
- The fourth for the 100's degree (Example: Xxx.x)

The two uppermost bits of a byte are always zero, the next two bits give the digit, 00 for the decimal, 01 for the degree, 10 for the 10's degree, and 11 for the 100's degree. The lowest four bits give the digit value in 4-bit BCD format. As an example a heading of 234.5° will give the four bytes 05h 14h 23h 32h. The LR40 adds a fifth byte at the end for status with the two upper bits of the status byte set to 11 (11000000 for OK, 11001010 for alarm). This status byte is ignored.

Clock

The system clock is used to time stamp all data output. The clock may be set upon start of new survey or power-up on the Processing Unit (recommended source is a NMEA ZDA format datagram). The clock will drift, typically some seconds per day, unless it is synchronised to a 1 PPS (pulse per second) input signal (the clock millisecond counter will be set to zero whenever a pulse is received). A fully correct clock is only necessary if the output data are later to be combined with other time critical data logged or created by other systems, for example an accuracy of up to one minute would be necessary to apply tidal changes. If the timestamp supplied in the position input datagrams is to be used, it is imperative that the system clock is correctly set and that 1 PPS synchronisation is used.

ZDA format

Data Description	Format	Valid range	Note
Start identifier = \$	Always 24h	–	–
Talker identifier	aa	Capital letters	–
Sentence formatter	Always ZDA,	–	–
UTC	hhmmss.ss,	000000 to 235959.9...	–
Day	xx,	01 to +31	–
Month	xx,	01 to +12	–
Year	xxxx,	0000 to 9999	–
Local zone hours	xx,	–13 to +13	1
Local zone minutes	xx	00 to +59	1
Optional checksum	*hh	–	–
End of sentence delimiter = CRLF	Always 0Dh 0Ah	–	–

Note 1

Local zone time is not used. An offset time may be entered by the operator to get the system clock to show a different time than UTC.

Note 2

Trimble UTC format is also supported.

Sound Speed

Overview

A sound speed profile may be loaded into the Operator Station either on a serial line or on Ethernet. Formats previously used with existing Kongsberg Maritime echo sounders (Kongsberg Maritime ASCII and Binary Sound Velocity Profile input datagrams) will be accepted, but since their resolution in depth is limited to 1 m and the number of entries to 100, a new format given below without these limitations is recommended. This format is also accepted by the Kongsberg Maritime HIPAP and HPR underwater positioning systems (but not necessarily vice-versa). Note that a complete profile may be pieced together from several datagrams and edited with the Operator Station's Sound Speed Editor.

The new format is completely in ASCII and allows 9998 entries without limitations in resolution. In addition to depth and sound speed, it allows input of absorption coefficient, pressure, temperature and salinity or conductivity. The latter parameters may be used to calculate depth, sound speed and absorption coefficient. Use of a depth dependent absorption coefficient allows a more accurate determination of bottom backscatter strength.

Note that this datagram may also be logged as output, retaining information not included in the standard sound speed profile output datagram, such as where and when the profile has been taken.

Kongsberg Maritime SSP format

Data Description	Format	Length	Valid range	Note
Start identifier = \$	Always 24h	1	–	–
Talker identifier	aa	2	Capital letters	–
Datagram identifier	Always Sxx,	4	S00to S53	1,2
Data set identifier	xxxxx,	6	00000 to 65535	–
Number of measurements = N	xxxx,	5	0001 to 9999	–
UTC time of data acquisition	hhmmss,	7	000000 to 235959	3
Day of data acquisition	xx,	3	00 to 31	3

Data Description	Format	Length	Valid range	Note
Month of data acquisition	xx,	3	00 to 12	3
Year of data acquisition	xxxx,	5	0000 to 9999	3
N entries of the next 5 fields – See note 4				
– Depth in m from water level or Pressure in MPa	x.x,	2 –	0 to 12000.00 0 to 1.0000	–
– Sound velocity in m/s	x.x,	1 –	1400 to 1700.00	–
– Temperature in °C	x.x,	1 –	–5 to 45.00	–
– Salinity in parts per thousand or Conductivity in S/m	x.x,	1 –	0 to 45.00 0 to 7.000	–
Absorption coefficient in dB/km	x.x	0 –	0 to 200.00	–
Data set delimiter	CRLF	2	0Dh 0Ah	–
End of repeat cycle				
Latitude in degrees and minutes, plus optional decimal minutes	III.II,	Variable 5–	0000 to 9000.0...	5
Latitude – N/S	a,	2	N or S	5
Longitude in degrees and minutes, plus optional decimal minutes	yyyyy.yy,	Variable 6–	00000 to 18000.0...	5
Longitude – E/W	a,	2	E or W	5
Atmospheric pressure in MPa	x.x,	1 –	0 to 1.0000	5
User given comments	c– –c	Variable	–	5
Optional checksum	*hh	–	–	6
End of datagram delimiter = \CRLF	5Ch 0Dh 0Ah	3	–	–

Note 1

The datagram identifier identifies what type of data is included. This is shown in the following table where D is depth, P is pressure, S is salinity, C is conductivity, c is sound speed, α is absorption coefficients, and L is latitude. The notation c(T,S) indicates for example that the sound speed is to be calculated from the temperature and salinity input data. When pressure is used, the atmospheric pressure must be given if the pressure is absolute, otherwise the pressure must be given re the sea level and the atmospheric pressure must be zero.

Identifier	Input data	Data to be used
S00	D, c	D, c
S10	D, c	D, c
S11	D, c, α	D, c, α
S12	D, c, T, S	D, c, α (D,T,S,L)
S20	D, T, S	D, c(D,T,S,L)

Identifier	Input data	Data to be used
S21	D, T, S, α	D, c(D,T,S,L), α
S22	D, T, S	D, c(D,T,S,L), α (D,T,S,L)
S30	D, T, C	D, c(D,T,C,L)
S31	D, T, C, α	D, c(D,T,C,L), α
S32	D, T, C	D, c(D,T,C,L), α (D,T,C,L)
S40	P, T, S	D(P,T,S,L), c(P,T,S,L)
S41	P, T, S, α	D(P,T,S,L), c(P,T,S,L), α
S42	P, T, S	D(P,T,S,L), c(P,T,S,L), α (P,T,S,L)
S50	P, T, C	D(P,T,C,L), c(P,T,C,L)
S51	P, T, C, α	D(P,T,C,L), c(P,T,C,L), α
S52	P, T, C	D(P,T,C,L), c(P,T,C,L), α (P,T,C,L)

Note 2

S00 is a special case because then the sound speed profile will be taken into use immediately without further operator intervention. The checksum is then mandatory and must be correct. Furthermore entries for zero depth and a deeper depth than expected during the survey must be included.

Note 3

Note that these fields have fixed length and leading zeros must be used.

Note 4

The depth or pressure field is always required while the other fields are optional except for those required by the datagram identifier. The field-delimiting commas must always be included even if the fields are empty.

Note 5

The positions, atmospheric pressure and comment fields are optional. Note that the option field must not include a \. It is recommended to include sensor type in the comment field.

Note 6

The checksum field is calculated between the \$ and the * delimiters by exclusive OR'ing of all bytes. The checksum is required for datagram S00, but is optional for the others.

AML Smart Sensor format

An **AML Smart Sensor** may be used directly for sound speed profile input on a serial line to the Operator Station. The sensor may also be used to measure the sound speed at the transducer depth continuously during surveying.

The supported AML Smart Sensor message formats are:

SV = Sound Velocity

SV&P = Sound Velocity and Pressure

SV&T = Sound Velocity and Temperature

Each message from the sensor is transmitted as a sequence of ASCII characters terminated by a CRLF pair.

The accepted message formats are as follows:

SV Format:

±	X	X	X	X	.	X		CR	LF
---	---	---	---	---	---	---	--	----	----

where xxxx.x is the measured sound speed in m/s.

SV&P Format:

±	X	X	X	.	X	X		±	X	X	X	X	.	X		CR	LF
---	---	---	---	---	---	---	--	---	---	---	---	---	---	---	--	----	----

where the first field is the pressure in decibars relative to the surface and the second is sound speed in m/s.

SV&T format:

±	X	X	.	X	X	X		±	X	X	X	X	.	X		CR	LF
---	---	---	---	---	---	---	--	---	---	---	---	---	---	---	--	----	----

where the first field is the temperature in degrees Celsius and the second is sound speed in m/s.

Note

The message formats above are presented in table format to make it easier to see the location and number of spaces in each message.

Note

Note The '±' character should be interpreted as follows. If the number in the field immediately following this character is negative, then this character will be "-" (minus). However, if the number in the field immediately following this character is positive, then this character will be a " " (space).

Depth input from single beam echo sounder

Overview

Depth datagrams from a single beam echo sounder are accepted for display and logging on the system. The following formats are supported:

- NMEA 0183 DBS
- NMEA 0183 DPT
- binary datagrams from the Kongsberg Maritime EA 500 echo sounder series.

DBS format

Data Description	Format	Valid range	Note
Start identifier = \$	Always 24h	–	–
Talker identifier	aa	Capital letters	–
Sentence formatter	Always DBS,	–	–
Depth in feet	x.x,f,	0.1 –	1
Depth in meters	x.x,M,	0.1 –	1
Depth in fathoms	x.x,F	0.1 –	1
Checksum	*hh	–	–
End of sentence delimiter = CRLF	Always 0Dh 0Ah	–	–

Note 1

The decoding priority will be meter field, feet field and fathom field with the depth value extracted from the first field with valid data.

DPT format

Data Description	Format	Valid range	Note
Start identifier = \$	Always 24h	–	–
Talker identifier	aa	Capital letters	–
Sentence formatter	Always DPT,	–	–
Depth in meters from the transducer	x.x,	0.1 –	–
Offset of transducer from waterline in meters	x.x,	0 –	1
Maximum range scale in use	x.x	–	–
Checksum	*hh	–	–
End of sentence delimiter = CRLF	Always 0Dh 0Ah	–	–

Note 1

A negative value implying that the offset is from the keel should not be used.

EA 500 format

Data Description	Format	Valid range	Note
Start identifier = D	Always 34h	–	–
Channel identifier	x,	1 to 3	1
Time as HHMMSShh	xxxxxxx,	00000000 to 23595999	1
Depth in meters from the transducer	32 bit IEEE 754 floating point	0.1 –	1
Bottom backscattering strength in dB	32 bit IEEE 754 floating point	–	–
Transducer number	32 bit integer	–	–
Athwartship slope in degrees	32 bit IEEE 754 floating point	–	–

Note 1

Only the channel identifier, depth and time will be decoded by the system. The least significant byte is transmitted first (the Intel convention).

Note

The datagram must be sent on Ethernet to UDP port number 2200 on the Operator Station.

Remote control**Overview**

A Remote Control datagram has been implemented to allow:

- the multibeam echo sounder to start logging on remote command.
- the multibeam echo sounder to send out parameter and sound speed profile datagrams as a response to the remote command.
- the survey line numbers to be set from a remote location.

Note that the parameter and sound speed profile datagrams are always sent out when logging is started or any changes are made to the parameters or sound speed. They may also be sent out regularly at operator specified intervals.

Data Description	Format	Valid range	Note
Start identifier = \$	Always 24h	–	–
Talker identifier	aa	Capital letters	–
Datagram identifier	Rxx,	R00 to R20	1
EM model number	EMX=dddd,	–	–
Responsible operator	ROP=a--a,	–	–
Survey identifier	SID=a--a,	–	–
Survey line number	PLN=d..d,	–	–

Data Description	Format	Valid range	Note
Survey line identifier (planned line no)	PLL=d--d,	–	–
Comment	COM=a--a	–	–
Optional checksum	*hh	–	–
End of datagram delimiter = \CRLF	5Ch 0Dh 0Ah	–	–

Note 1

Rxx defines what action the system is to take with respect to pinging and logging of data in addition to changes in the parameters. Note that logging of survey data on local storage is not affected, this is determined by operator control from the menu only.

- R00 - System to stop pinging (and logging if on)
- R10 - System to stop all logging (but continue or start pinging).
- R11 - System to start logging on new line to both local and remote
- R12 - System to star logging on new line but only to local storage
- R13 - System to start logging on new line but only to remote
- R20 - System to send installation parameter datagram and sound speed profile datagrams to remote

9.4 Output datagrams

Introduction

Output datagrams are usually logged to disk or tape on the EM Series Operator Station. The output datagrams may also be exported to user provided programs on the Operator Station or on an external Ethernet network using UDP protocol (remote logging). An NMEA DPT depth datagram may be exported on a serial line.

The output datagrams are mostly in binary format using signed or unsigned integer numbers with lengths of 1, 2 or 4 bytes.

The same endian (little or big) as used in the input datagrams will be used for the output datagrams. With a PC based operator station little endian is normally used.

Note

We recommend that software written to decode EM Series data includes a check for the byte ordering with a provision for byte swapping. Suitable data fields to check on are the length field at the start of the datagram, the EM Series model number field and possibly the date and time fields.

The basic output datagram structure established with the EM 100 echo sounder is retained.

- All datagrams (except the NMEA DPT datagram) start with STX, datagram type and time tag, and end with ETX and checksum (sum of bytes between STX and ETX). In addition the total length of the datagram (*not including the length field*) will precede the STX byte, given as a four byte binary number.
- The length field is only included when logging to tape and/or disk, but not for datagrams logged to a remote location. The length can then be derived from the network software. Systems logging data remotely should add this length at the start of each datagram. This length is required if the data are to be used with Kongsberg Maritime post-processing systems.
- The time stamp resolution is 1 millisecond and includes the century. The time stamp is binary. The date is given as 10000*year(4 digits) + 100*month + day, for example 19950226 for February 26, 1995. All date fields in the output datagrams use this format. A time is usually given (in milliseconds) from midnight.

- The datagrams identify the multibeam echo sounder model and its serial number. The system model number is 120 for the EM 120, 300 for the EM 300, etc. For the EM 3000D (the dual head system) the model number was originally given as 3002 and the serial number is that of Sonar Head number 1. However in the depth datagram model numbers 3003-3008 are now used to also identify the actual transmit and sampling frequencies of the two heads. If only one head is activate on the EM 3000D, it is coded as a single head system. For EM 3002 the model number is 3020.
- Due care has been taken to include all parameters needed in postprocessing in the relevant datagrams, with a minimum of data duplication. Where resolution of a data field is variable, a resolution descriptor is included.
- Invalid data are always identified by the highest positive number allowed in a field unless otherwise noted.
- A real-time parameter datagram has been added to enable logging of parameters not used in postprocessing, but which may be important in checking the quality of the logged data, or to allow tracing of reasons for possible malfunctions.
- Attitude data as time continuous records and raw ranges and beam pointing angles are logged to allow eventual postprocessing corrections. The logged attitudes are valid at the transmit transducer, and are corrected for any sensor offsets.
- A new *Range and beam angle datagram* (type f), is now included, that contains more details. (From January 2004).

Depth

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	—	—
Start identifier = STX (Always 02h)	1U	—	—
Type of datagram = D(epth data) (Always 44h)	1U	—	—
EM model number (Example: EM 3000 = 3000)	2U	—	4
Date = year*10000 + month*100 + day (Example: Feb 26, 1995 = 19950226)	4U	—	—
Time since midnight in milliseconds (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	—
Ping counter (sequential counter)	2U	0 to 65535	—
System serial number	2U	100 —	—
Heading of vessel in 0.01°	2U	0 to 35999	—
Sound speed at transducer in dm/s	2U	14000 to 16000	—

Data Description	Format	Valid range	Note
Transmit transducer depth re water level at time of ping in cm	2U	0 to 65536	1
Maximum number of beams possible	1U	48 –	–
Number of valid beams = N	1U	1 to 254	–
z resolution in cm	1U	1 to 254	–
x and y resolution in cm	1U	1 to 254	–
Sampling rate (f) in Hz	2U	300 to 30000	3
or Depth difference between sonar heads in the EM 3000D	2S	–32768 to 32766	4
Repeat cycle – N entries of :	16*N	–	–
Depth (z) from transmit transducer (unsigned for EM 120 and EM 300)	2S or 2U	–32768 to +32766 or 1 to 65534	2
Acrosstrack distance (y)	2S	–32768 to 32766	2
Alongtrack distance (x)	2S	–32768 to 32766	2
Beam depression angle in 0.01°	2S	–11000 to 11000	3
Beam azimuth angle in 0.01°	2U	0 to 56999	3
Range (one–way travel time)	2U	0 to 65534	3
Quality factor	1U	0 to 254	5
Length of detection window (samples/4)	1U	1 to 254	–
Reflectivity (BS) in 0.5 dB resolution) (Example: –20 dB = 216)	1S	–128 to +126	–
Beam number	1U	1 to 254	6
End of repeat cycle			
Transducer depth offset multiplier	1S	–1 to +17	1
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Note 1

The transmit transducer depth plus the depth offset multiplier times 65536 cm should be added to the beam depths to derive the depths re the water line. The depth offset multiplier will usually be zero, except when the EM 2000/3000 Sonar Head is on an underwater vehicle at a depth larger than 655.36 m. Note that the offset multiplier will be negative (-1) if the actual heave is large enough to bring the transmit transducer above the water line. This may represent a valid situation, but may also be due to an erroneously set installation depth of either the transducer or the water line.

Note 2

The beam data are given re the transmit transducer or sonar head depth and the horizontal location of the active positioning

system's antenna. Heave, roll, pitch, sound speed at the transducer depth and ray bending through the water column have been applied. On the EM 1002/2000/3000/3002 the beam depths must be regarded as signed values to take into account beams which may be going upwards. On the EM 120/300 the beam depths are always positive and the values are therefore unsigned.

Note 3

The range, beam depression angle (positive downwards and 90° for a vertical beam) and beam azimuth angle (re vessel centerline) are given relative to the transducer (sonar head) at the ping transmit time. Heave, roll, pitch and sound speed at the transducer depth have been applied, but not ray bending. These values may thus be directly used for a new ray bending calculation with a revised sound speed profile to generate new sounding depths and positions without any need for using attitude data.

One way travel time = range / sampling rate / 4

Note that if the data need to be reprocessed with a new sound speed at the transducer depth or new roll, pitch or heave values, full reprocessing starting with the raw range and beam angle data is required. Attitude data is also required in this reprocessing, and both these data types will in the future be logged as standard.

If the beam azimuth angle has a value larger than 35999, the beam pointing angle has replaced the beam depression angle, and the raw two-way travel time has replaced the one-way heave and beam angle corrected travel time. The transmit tilt angle plus 54000 is given in the beam azimuth angle field. The use of this data definition is available on remote output to a port named as "RawDepth..." for use by other systems which do their own attitude and sound speed processing.

Note 4

In an EM 3000D the transmit transducer depth is that of Sonar Head number 1, taking into account the depth offset multiplier as described in note 1. The range multiplier is replaced by the difference in depth between Sonar Head number 1 and 2, i.e. head 2 depth is equal to head 1 depth (possibly modified with depth offset multiplier) plus the depth difference. The range sampling rates in Hz of the two heads is given through the EM model number according to the following table:

EM model number	3003	3004	3005	3006	3007	3008
Sonar Head 1	13956	14293	13956	14621	14293	14621
Sonar Head 2	14621	14621	14293	14293	13956	13956

Previously the model number of the EM 3000D was given as 3002 with head sample rates of 13956 and 14621 Hz respectively. The head depths in this case should be assumed to be equal, and although the mathematical derivation of final beam depths would otherwise be the same as described above, the transmit transducer depth was not actually exactly that of the sonar heads.

Note 5

The quality number's upper bit signifies whether amplitude (0) or phase (1) detection has been used. If amplitude the 7 lowest bits give the number of samples used in the centre of gravity calculation. If phase the second highest bit signifies whether a second (0) or first (1) order curve fit has been applied to determine the zero phase range, and the 6 lowest bits indicates the quality of the fit (actually the normalized variance of the fit re the maximum allowed, i.e. with a lower number the better the fit).

Note 6

Beam 128 is the first beam on the second sonar head in an EM 3000D dual head system.

Raw range and beam angle (new)

New datagram, added January 2004. This datagram replaces the old F datagram.

Note

This version of the datagram is not yet implemented on the EM 3000. Use the version below.

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	—	—
Start identifier = STX (Always 02h)	1U	—	—
Type of datagram = f (Always 66h)	1U	—	—
EM model number (Example: EM 3000 = 3000)	2U	—	—
Date = year*10000 + month*100 + day (Example: Feb 26, 1995 = 19950226)	4U	—	—
Time since midnight in milliseconds (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	—
Ping counter (sequential counter)	2U	0 to 65535	—
System serial number	2U	100 —	—

Data Description	Format	Valid range	Note
Number of transmit sectors = Ntx	2U	1 to 20	–
Number of valid receive beams = N	2U	1 to 1999	–
Sampling frequency in 0.01 Hz (F)	4U	100 to 100000	
ROV depth in 0.01 m	4S		
Sound speed at transducer in 0.1 m/s	2U	14000 to 16000	–
Maximum number of beams possible	2U	1 to 1999	
Spare 1	2U		
Spare 2	2U		
Ntx entries of :	20*Ntx	–	
Tilt angle in 0.01°	2S	–2900 to 2900	–
Focus range in 0.1 m (0 = No focus)	2U	0 to 65535	–
Signal length in μ s	4U		–
Transmit time offset in μ s	4U		–
Center frequency in Hz	4U		–
Bandwidth in 10 Hz	2U	1 to 65535	–
Signal waveform identifier	1U	0 to 99	1
Transmit sector number	1U	0 to 19	–
N entries of :	12*N		
Beam pointing angle ref array in 0.01°	2S	–11000 to 11000	–
Range in 0.25 samples (R)	2U	0 to 65535	2
Transmit sector number	1U	0 to 19	–
Reflectivity (BS) in 0.5 dB resolution	1S	–128 to 127	–
Quality factor	1U	0 to 254	–
Detection window length in samples (/4 if phase)	1U	1 to 254	
Beam number	2S	–1999 to 1999	3
Spare	2U		
Spare (Always 0)	1U	0	–
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Note 1

0 = cw, 1 = FM

Note 2

Two way travel time = $R / (4 * F / 100)$

Note 3

The beam number normally starts at 0.

Raw range and beam angle

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–
Type of datagram = F (Always 46h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Ping counter (sequential counter)	2U	0 to 65535	–
System serial number	2U	100 –	–
Maximum number of beams possible	1U	48 –	–
Number of valid beams = N	1U	1 to 254	–
Sound speed at transducer in dm/s	2U	14000 to 16000	–
Repeat cycle – N entries of :	8*N	–	
– Beam pointing angle in 0.01°	2S	–11000 to 11000	1
– Transmit tilt angle in 0.01°	2U	–2999 to 2999	1
– Range (two-way travel time)	2U	0 to 65534	1
– Reflectivity (BS) in 0.5 dB resolution	1S	–128 to 126	–
– Beam number	1U	1 to 254	–
End of repeat cycle			
Spare (Always 0)	1U	–	–
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Note 1

The beam pointing angle is positive to port and the transmit tilt angle is positive forwards for a normally mounted system looking downwards. The range resolution in time is the inverse of the range sampling rate given in the depth datagrams.

Seabed image

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–
Type of datagram = S(eabed image data) (Always 53h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (Example: Feb 26, 1995 = 19950226)	4U	–	–

Data Description	Format	Valid range	Note
Time since midnight in milliseconds (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Ping counter (sequential counter)	2U	0 to 65535	–
System serial number	2U	100 –	–
Mean absorption coefficient in 0.01 dB/km	2U	1 to 20000	1
Pulse length in μ s	2U	50 –	1
Range to normal incidence used to correct sample amplitudes in no. of samples	2U	1 to 16384	–
Start range sample of TVG ramp if not enough dynamic range (0 else)	2U	0 to 16384	–
Stop range sample of TVG ramp if not enough dynamic range (0 else)	2U	0 to 16384	–
Normal incidence BS in dB (BSN) (Example: –20 dB = 236)	1S	–50 to 10	–
Oblique BS in dB (BSO) (Example: –1 dB = 255)	1S	–60 to 0	–
Tx beamwidth in 0.1°	2U	1 to 300	–
TVG law crossover angle in 0.1°	1U	20 to 300	–
Number of valid beams (N)	1U	1 to 254	–
Repeat cycle – N entries of :	6*N	–	
beam index number	1U	0 to 253	2
sorting direction	1S	–1 or 1	3
number of samples per beam = Ns	2U	1 –	–
centre sample number	2U	1 –	4
End of repeat cycle			
Repeat cycle – ΣNs entries of:	Σ Ns	–	
Sample amplitudes in 0.5 dB (Example: –30 dB = 196)	1S	–128 to 126	–
End of repeat cycle			
Spare byte if required to get even length (Always 0 if used)	0–1U	–	–
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Note 1

These fields have earlier had other definitions.

Note 2

The beam index number is the beam number - 1.

Note 3

The first sample in a beam has lowest range if 1, highest if -1.
 Note that the range sampling rate is defined by the sampling rate in the depth output datagram and that the ranges in the seabed image datagram are all two-way from time of transmit to time of receive

Note 4

The centre sample number is the detection point of a beam.

Position

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–
Type of datagram = P(osition data) (Always 050h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Position counter (sequential counter)	2U	0 to 65535	–
System / serial number	2U	100 –	–
Latitude in decimal degrees*20000000 (negative if southern hemisphere) (Example: 32°34' S = –65133333)	4S	–	–
Longitude in decimal degrees*10000000 (negative if western hemisphere) (Example: 110.25° E = 1102500000)	4S	–	–
Measure of position fix quality in cm	2U	–	1
Speed of vessel over ground in cm/s	2U	0 –	1
Course of vessel over ground in 0.01°	2U	0 to 35999	1
Heading of vessel in 0.01°	2U	0 to 35999	–
Position system descriptor	1U	1 to 254	2
Number of bytes in input datagram	1U	– 254	–
Position input datagram as received	Variable	–	3
Spare byte if required to get even length (Always 0 if used)	0–1U	–	–
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Note 1

These data will be valid only if available as input.

Note 2

The position system descriptor shows which source this data is from and its real-time use by bit coding:

- xxxx xx01 - position system no 1
- xxxx xx10 – position system no 2
- xxxx xx11 – position system no 3
- 10xx xxxx – the position system is active, system time has been used
- 11xx xxxx - the position system is active, input datagram time has been used
- xxxx 1xxx – the position may have to be derived from the input datagram which is then in SIMRAD 90 format.

Note 3

Complete input datagram except header and tail (such as NMEA 0183 \$ and CRLF).

Depth (pressure) or height

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–
Type of datagram = h(eight data) (Always 068h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (EXample: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Height counter (sequential counter)	2U	0 to 65535	–
System serial number	2U	100 –	–
Height in cm	4S	–4294967296 to 4294967295	–
Heigth type	1U	0 to 100	1
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Note 1

0: The height is derived from the G GK or GGA datagram and is the height of the water level are the vertical datum (possibly motion corrected).

1 - 99: The height type is as given in the *Depth (pressure) or height input datagram*.

100: The input is depth taken from the *Depth (pressure) or height input datagram*.

Tide

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	-	-
Start identifier = STX (Always 02h)	1U	-	-
Type of datagram = T(ide data) (Always 054h)	1U	—	—
EM model number (Example: EM 3000 = 3000)	2U	-	-
Date = year*10000 + month*100 + day (Example: Feb 26, 1995 = 19950226)	4U	-	-
Time since midnight in milliseconds (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	-
Tide counter (sequential counter)	2U	0 to 65535	-
System serial number	2U	100 -	-
Date = year*10000 + month*100 + day (from input datagram) (Example: Feb 26, 1995 = 19950226)	4U	-	-
Time since midnight in milliseconds (from input datagram) (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	-
Tidal offset in cm	2S	-32768 to 32766	-
Spare (Always 0)	1U	-	-
End identifier = ETX (Always 03h)	1U	-	-
Check sum of data between STX and ETX	2U	-	-

Attitude

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	—	—
Start identifier = STX (Always 02h)	1U	—	—
Type of datagram = A(ttitude data) (Always 041h)	1U	—	—
EM model number (Example: EM 3000 = 3000)	2U	—	—
Date = year*10000 + month*100 + day (at start of data record) (Example: Feb 26, 1995 = 19950226)	4U	—	—
Time since midnight in milliseconds (at start of data record) (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	—
Attitude counter (sequential counter)	2U	0 to 65535	—
System serial number	2U	100 —	—
Number of entries = N	2U	1 —	—

Data Description	Format	Valid range	Note
Repeat cycle – N entries of:	12*N	–	
– Time in milliseconds since record start	2U	0 to 65534	–
– Sensor status	2U	–	1
– Roll in 0.01°	2S	–18000 to 18000	–
– Pitch in 0.01°	2S	–18000 to 18000	–
– Heave in cm	2S	–1000 to 10000	–
– Heading in 0.01°	2U	0 to 35999	–
End of repeat cycle			
Sensor system descriptor	1U	–	2
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Note 1

The sensor status will be copied from the input datagram's two sync bytes if the sensor uses the EM format. See the input format description for further details.

Note 2

The sensor system descriptor will show which sensor the data is derived from, and which of the sensor's data have been used in real time by bit coding:

- xx00 xxxx – motion sensor number 1
- xx01 xxxx – motion sensor number 2
- xxxx xxx1 – heading from the sensor is active
- xxxx xx0x – roll from the sensor is active
- xxxx x0xx – pitch from the sensor is active
- xxxx 0xxx – heave from the sensor is active

Heading

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–
Type of datagram = H(eading data) (Always 048h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (at start of data record) (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (at start of data record) (System: 08:12:51.234 = 29570234)	4U	0 to 86399999	–

Data Description	Format	Valid range	Note
Heading counter (sequential counter)	2U	0 to 65535	–
System serial number	2U	100 –	–
Number of entries = N	2U	1 –	–
Repeat cycle – N entries of:	4*N	–	–
– Time in milliseconds since record start	2U	0 to 65534	–
– Heading in 0.01°	2U	0 to 35999	–
End of repeat cycle			
Heading indicator (active or not) (0 = inactive)	1U	–	–
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Clock

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–
Type of datagram = C(lock data) (Always 043h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (of EM clock) (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (of EM clock) (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Clock counter (sequential counter)	2U	0 to 65535	–
System serial number	2U	100 –	–
Date = year*10000 + month*100 + day (from external clock input) (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (from external clock datagram) (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
1 PPS use (active or not) (0 = inactive)	1U	–	1
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Note 1

Shows if the system clock is synchronised to an external 1 PPS signal or not.

Surface sound speed

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–

Data Description	Format	Valid range	Note
Type of datagram = G (Always 047h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (at start of data record) (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (at start of data record) (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Sound speed counter (sequential counter)	2U	0 to 65535	–
System serial number	2U	100 –	–
Number of entries = N	2U	1 –	–
Repeat cycle – N entries of: – Time in seconds since record start – Sound speed in dm/s (including offset)	4*N	–	
	2U	0 to 65534	–
	2U	14000 to 15999	–
End of repeat cycle			
Spare (Always 0)	1U	–	–
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Sound speed profile

This datagram will contain the profile actually used in the real time raybending calculations to convert range and angle to xyz data. It will usually be issued together with the installation parameter datagram.

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–
Type of datagram = U (Always 055h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (at start of use) (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (at start of use) (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Profile counter (sequential counter)	2U	0 to 65535	–
System serial number	2U	100 –	–
Date = year*10000 + month*100 + day (when profile was made) (Example: Feb 26, 1995 = 19950226)	4U	–	–

Data Description	Format	Valid range	Note
Time since midnight in milliseconds (when profile was made) (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Number of entries = N	2U	1 –	–
Depth resolution in cm	2U	1 to 254	–
Repeat cycle – N entries of:	8*N	–	–
- Depth	4U	0 to 1200000	–
– Sound speed in dm/s	4U	14000 to 17000	–
End of repeat cycle			
Spare byte to get even length (Always 0)	1U	–	–
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Kongsberg Maritime SSP output

This datagram will contain the profile as received as input, and is logged as is to enable use of its data in postprocessing. The real time use of its data is decided by the operator, the sound speed profile actually being used is given by the sound speed profile output datagram (see above).

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–
Type of datagram = W (Always 057h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
SSP counter (sequential counter)	2U	0 to 65535	–
System serial number	2U	100 –	–
Input datagram starting with Sentence formatter and ending with Comment	Variable	–	–
Spare byte if required to get even length (Always 0 if used)	0 – 1U	–	–
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Single beam echo sounder depth

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–

Data Description	Format	Valid range	Note
Type of datagram = E(cho sounder data) (Always 045h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (of EM clock) (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (of EM clock) (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Echo sounder counter (sequential counter)	2U	0 to 65535	–
System serial number	2U	100 –	–
Date = year*10000 + month*100 + day (from input datagram if available) (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (from input datagram if available) (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Echo sounder depth from waterline in cm	4U	0 to 1200000	–
Source identifier (S, T, 1, 2 or 3)	ASCII	–	1
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Note 1

Identifies the source datagram type, i.e. NMEA DBS, NMEA DPT or EA 500 series channel 1-3 respectively.

Runtime parameter

Data Description	Format	Valid range	Note
Number of bytes in datagram	4U	–	–
Start identifier = STX (Always 02h)	1U	–	–
Type of datagram = R(untime parameter) (Always 052h)	1U	–	–
EM model number (Example: EM 3000 = 3000)	2U	–	–
Date = year*10000 + month*100 + day (Example: Feb 26, 1995 = 19950226)	4U	–	–
Time since midnight in milliseconds (Example: 08:12:51.234 = 29570234)	4U	0 to 86399999	–
Ping counter	2U	0 to 65535	–
System serial number	2U	100 –	–
Operator Station status	1U	–	1
Processing Unit status	1U	–	1
BSP status	1U	–	1
Sonar Head or Transceiver status	1U	–	1
Mode	1U	1 –	2
Filter identifier	1U	0 to 254	3

Data Description	Format	Valid range	Note
Minimum depth in m	2U	0 to 10000	–
Maximum depth in m	2U	1 to 12000	–
Absorption coefficient in 0.01 dB/km	2U	1 to 20000	4
Transmit pulse length in μ s	2U	1 to 50000	–
Transmit beamwidth in 0.1 degrees	2U	1 to 300	–
Transmit power re maximum in dB	1S	0 to –50	–
Receive beamwidth in 0.1 degrees	1U	5 to 80	–
Receive bandwidth in 50 Hz resolution	1U	1 to 254	–
Receiver fixed gain setting in dB	1U	0 to 50	–
TVG law crossover angle in degrees	1U	2 to 30	–
Source of sound speed at transducer	1U	0 to 3	5
Maximum port swath width in m	2U	10 to 20000	–
Beam spacing	1U	0 to 3	6
Maximum port coverage in degrees	1U	10 to 110	–
Yaw and pitch stabilization mode	1U	–	7
Maximum starboard coverage in degrees	1U	10 to 110	–
Maximum starboard swath width in m	2U	10 to 20000	–
Spare (Always 0)	2U	–	–
HiLo frequency absorption coefficient ratio	1U	00 to 120	–
End identifier = ETX (Always 03h)	1U	–	–
Check sum of data between STX and ETX	2U	–	–

Note 1

The table below shows the system error status coded by one bit for each detected error. The status bit is set to one if error is detected.

Operator Station status		
Bit number	Function	Model
xxxx xxxx	For future use	
Processing Unit status		
Bit number	Function	Model
xxxx xxx1	Communication error with BSP	All models
xxxx xx1x	Communication error with Sonar Head or Transceiver	All models
xxxx x1xx	Attitude not valid for this ping	All models
xxxx 1xxx	Heading not valid for this ping	All models
xxx1 xxxx	System clock has not been set since power up	All models
xx1x xxxx	External trigger signal not detected	All models
1xxx xxxx	Spare	

BSP status (EM 2000, EM 3000 and EM 3002)		
Bit number	Function	Model
xxxx xxx1	Error on RX data received by BSP 1 (May be a bad high speed link)	EM 2000, EM 3000, EM 3000D, EM 3002, EM 3002D, EM 1002
xxxx xx1x	Too much seabed image data on BSP1	EM 3000, EM 3000D
xxxx x1xx	Invalid command received by BSP1	EM 3000, EM 3000D
xxxx 1xxx	Errors on BSP1	EM 3002, EM 3002D
xxx1 xxxx	Error on RX data received by BSP 2 (May be a bad high speed link)	EM 3000D, EM 3002D
xx1x xxxx	Too much seabed image data on BSP2	EM 3000D
x1xx xxxx	Invalid command received by BSP2	EM 3000D
1xxx xxxx	Errors on BSP2	EM 3002, EM 3002D
Sonar Head status (EM 2000, EM 3000 and EM 3002)		
Bit number	Function	Model
xxxx xxx1	Temperature too high on Sonar Head 1	EM 2000, EM 3000, EM 3000D, EM 3002, EM 3002D
xxxx xx1x	Data link failure on Sonar Head 1	EM 2000, EM 3000, EM 3000D, EM 3002, EM 3002D
xxxx x1xx	DC Supply Voltages in Sonar Head 1 is out of range	EM 2000, EM 3000, EM 3000D, EM 3002, EM 3002D
xxxx 1xxx	Spare	
xxx1 xxxx	Temperature too high on Sonar Head 2	EM 3000D, EM 3002D
xx1x xxxx	Data link failure on Sonar Head 2	EM 3000D, EM 3002D
x1xx xxxx	DC Supply Voltages in Sonar Head 2 is out of range	EM 3000D, EM 3002D
1xxx xxxx		

Note 2

The mode identifier byte is used as follows:

- 0000 0000 - Nearfield (EM 3000) or Very Shallow
- 0000 0001 - Normal (EM 3000) or Shallow (default for EM 2000)
- 0000 0010 - Target detect (EM 3000) or Medium
- 0000 0011 - Deep
- 0000 0100 - Very deep
- 0000 0101 - Extra deep (EM 300)

Note 3

The filter identifier byte is used as follows:

- xxxx xx00 - Spike filter set to Off
- xxxx xx01 - Spike filter is set to Weak
- xxxx xx10 - Spike filter is set to Medium
- xxxx xx11 - Spike filter is set to Strong
- xxxx x1xx - Slope filter is on
- xxxx 1xxx - Sector tracking or Robust Bottom Detection (EM 3000) is on
- 0xx0 xxxx - Range gates have Normal size
- 0xx1 xxxx - Range gates are Large
- 1xx0 xxxx - Range gates are Small
- xx1x xxxx - Aeration filter is on (EM 120 and EM 300)
- x1xx xxxx - Interference filter is on (EM 120 and EM 300)

Note 4

The used absorption coefficient should be derived from the seabed image or central beams echogram datagram if it is automatically updated with changing depth.

Note 5

The sound speed (at the transducer depth) source identifier is used as follows :

- 0000 0000 - From real time sensor
- 0000 0001 - Manually entered by operator
- 0000 0010 - Interpolated from currently used sound speed profile

Note 6

The beamspacing identifier is used as follows:

- 0000 0000 - Determined by beamwidth (FFT beamformer of EM 3000)
- 0000 0001 - Equidistant
- 0000 0010 - Equiangle
- 0000 0011 - Equiangle around nadir, equidistant in between or high density (EM 3002)

Note 7

The yaw and pitch stabilization identifier is set as follows:

- xxxx xx00 - No yaw stabilization
- xxxx xx01 - Yaw stabilization to survey line heading (Not used)

- xxxx xx10 - Yaw stabilization to mean vessel heading
- xxxx xx11 - Yaw stabilization to manually entered heading
- 1xxx xxxxx - Pitch stabilization is on.

Installation parameters

This datagram is an ASCII datagram except for the header which is formed as in all other output datagrams. The datagram is issued as a start datagram when logging is switched on and as a stop datagram when logging is turned off, i.e. at the start and end of a survey line. It may also be sent to a remote port as an information datagram. It is usually followed by a sound speed profile datagram.

In the datagram all ASCII fields start with a unique three character identifier followed by “=”. This should be used when searching for a specific field as the position of a field within the datagram is not guaranteed. The number or character part following is in a variable format with a minus sign and decimal point if needed, and with “,” as the field delimiter. The format may at any time later be expanded with the addition of new fields at any place in the datagram.

For the EM 3000 and EM 3002 the transducer 1 data are for the Sonar Head and the transducer 2 data are for the second Sonar Head of an EM 3000D or an EM 3002. For other new EM systems with separate transmit and receive transducers, transducer 1 refers to the transmit transducer, and transducer 2 refers to the receive transducer.

Data Description	Example	Format	Valid range	Note
Number of bytes in datagram	–	4U	–	1
Start identifier = STX	Always 02h	1U	–	–
Type of datagram = l or i(nstallation parameters) or r(emote information)	Start = 049h Stop = 069h Remote info = 70h	1U	–	–
EM model number	EM 3000 = 3000	2U	–	–
Date = year*10000 + month*100 + day	Feb 26, 1995 = 19950226	4U	–	–
Time since midnight in milliseconds	08:12:51.234 = 29570234	4U	0 to 86399999	–
Survey line number	–	2U	0 to 65534	–
System serial number	–	2U	100 –	–
Serial number of second sonar head	–	2U	100 –	–
Water line vertical location in m	WLZ=x.x,	ASCII	–	–

Data Description	Example	Format	Valid range	Note
System main head serial number	SMH=x.x,	ASCII	100 –	1
Hull Unit	HUN=x	ASCII	0 or 1	–
Hull Unit tilt offset	HUT=x.x	ASCII	–	–
Transducer 1 vertical location in m	S1Z=x.x,	ASCII	–	–
Transducer 1 along location in m	S1X=x.x,	ASCII	–	–
Transducer 1 athwart location in m	S1Y=x.x,	ASCII	–	–
Transducer 1 heading in degrees	S1H=x.x,	ASCII	–	–
Transducer 1 roll in degrees re horizontal	S1R=x.x,	ASCII	–	–
Transducer 1 pitch in degrees	S1P=x.x,	ASCII	–	–
Transducer 1 no of modules	S1N=x – –x,	ASCII	–	–
Transducer 2 vertical location in m	S2Z=x.x,	ASCII	–	–
Transducer 2 along location in m	S2X=x.x,	ASCII	–	–
Transducer 2 athwart location in m	S2Y=x.x,	ASCII	–	–
Transducer 2 heading in degrees	S2H=x.x,	ASCII	–	–
Transducer 2 roll in degrees re horizontal	S2R=x.x,	ASCII	–	–
Transducer 2 pitch in degrees	S2P=x.x,	ASCII	–	–
Transducer 2 no of modules	S2N=x – –x,	ASCII	–	–
System (sonar head 1) gain offset	GO1=x.x,	ASCII	–	–
Sonar head 2 gain offset	GO2=x.x,	ASCII	–	–
Outer beam offset	OBO=x.x	ASCII	–	–
High/Low Frequency Gain Difference	FGD=x.x	ASCII	–	–
Transmitter (sonar head no1) software version	TSV=c – –c,	ASCII	–	2
Receiver (sonar head 2) software version	RSV=c – –c,	ASCII	–	2
BSP software version	BSV=c – –c,	ASCII	–	2
Processing unit software version	PSV=c – –c,	ASCII	–	2
Operator station software version	OSV=c – –c,	ASCII	–	2
Datagram format version	DSV=c – –c,	ASCII	–	2
Depth (pressure) sensor along location in m	DSX=x.x,	ASCII	–	
Depth (pressure) sensor athwart location in m	DSY=x.x,	ASCII	–	
Depth (pressure) sensor vertical location in m	DSZ=x.x,	ASCII	–	
Depth (pressure) sensor time delay in millisec	DSD=x – –x,	ASCII	–	–
Depth (pressure) sensor offset	DSO=x.x,	ASCII	–	–
Depth (pressure) sensor scale factor	DSF=x.x,	ASCII	–	–
Depth (pressure) sensor heave	DSH=aa,	ASCII	IN or NI	3
Active position system number	APS=x,	ASCII	0 to 2	7
Position system 1 motion compensation	P1M=x,	ASCII	0 or 1	4
Position system 1 time stamp used	P1T=x,	ASCII	0 or 1	5
Position system 1 vertical location in m	P1Z=x.x,	ASCII	–	–
Position system 1 along location in m	P1X=x.x,	ASCII	–	–
Position system 1 athwart location in m	P1Y=x.x,	ASCII	–	–
Position system 1 time delay in seconds	P1D=x.x,	ASCII	–	–

Data Description	Example	Format	Valid range	Note
Position system 1 geodetic datum	P1G=c--c,	ASCII	–	–
Position system 2 motion compensation	P2M=x,	ASCII	0 or 1	4
Position system 2 time stamp use	P2T=x,	ASCII	0 or 1	5
Position system 2 vertical location in m	P2Z=x.x,	ASCII	–	–
Position system 2 along location in m	P2X=x.x,	ASCII	–	–
Position system 2 athwart location in m	P2Y=x.x,	ASCII	–	–
Position system 2 time delay in seconds	P2D=x.x,	ASCII	–	–
Position system 2 geodetic datum	P2G=c--c,	ASCII	–	–
Position system 3 motion compensation	P3M=x,	ASCII	0 or 1	4
Position system 3 time stamp use	P3T=x,	ASCII	0 or 1	5
Position system 3 vertical location in m	P3Z=x.x,	ASCII	–	–
Position system 3 along location in m	P3X=x.x,	ASCII	–	–
Position system 3 athwart location in m	P3Y=x.x,	ASCII	–	–
Position system 3 time delay in seconds	P3D=x.x,	ASCII	–	–
Position system 3 geodetic datum	P3G=c--c,	ASCII	–	–
Position system 3 on serial line or Ethernet	P3S= x,	ASCII	0 for Ethernet	–
Motion sensor 1 vertical location in m	MSZ=x.x,	ASCII	–	–
Motion sensor 1 along location in m	MSX=x.x,	ASCII	–	–
Motion sensor 1 athwart location in m	MSY=x.x,	ASCII	–	–
Motion sensor 1 roll reference plane	MRP=aa,	ASCII	HO or RP	–
Motion sensor 1 time delay in milliseconds	MSD=x--x,	ASCII	–	–
Motion sensor 1 roll offset in degrees	MSR=x.x,	ASCII	–	–
Motion sensor 1 pitch offset in degrees	MSP=x.x,	ASCII	–	–
Motion sensor 1 heading offset in degrees	MSG=x.x,	ASCII	–	–
Motion sensor 2 vertical location in m	NSZ=x.x,	ASCII	–	6
Motion sensor 2 along location in m	NSX=x.x,	ASCII	–	6
Motion sensor 2 athwart location in m	NSY=x.x,	ASCII	–	6
Motion sensor 2 roll reference plane	NRP=aa,	ASCII	HO or RP	6
Motion sensor 2 time delay in milliseconds	NSD=x--x,	ASCII	–	6
Motion sensor 2 roll offset in degrees	NSR=x.x,	ASCII	–	6
Motion sensor 2 pitch offset in degrees	NSP=x.x,	ASCII	–	6
Motion sensor 2 heading offset in degrees	NSG=x.x,	ASCII	–	6
Gyrocompass heading offset in degrees	GCG=x.x,	ASCII	–	–
Roll scaling factor	MAS=x.x,	ASCII	–	–
Transducer depth sound speed source	SHC=x	ASCII	0 or 1	8
Active heading sensor	AHS=x,	ASCII	1 to 4	–
Active roll sensor	ARO=x,	ASCII	1 to 4	–
Active pitch sensor port no	API=x,	ASCII	1 to 4	–
Active heave sensor port no	AHE=x,	ASCII	1 to 4	–
Cartographic projection	CPR=aaa,	ASCII	–	–

Data Description	Example	Format	Valid range	Note
Responsible operator	ROP=c--c,	ASCII	–	–
Survey identifier	SID=c--c,	ASCII	–	–
Survey line identifier (planned line no)	PLL=x--x,	ASCII	–	–
Comment	COM=c--c,	ASCII	–	–
Spare byte if required to get even length	Always 0 if used	0–1U	–	–
End identifier = ETX	Always 03h	1U	–	–
Check sum of data between STX and ETX		2U	–	–

Note 1

Serial number of head no 2 if that head is the only one in use with the EM 3000D, otherwise the serial number of head no 1 in the EM 3000D or the only head in the EM 3000.

Note 2

A version number is given as 3 alphanumerical fields separated by decimal points, plus date as yymmdd (for example 3.02.11 991124).

Note 3

IN = the heave of an underwater vehicle is presumed to be measured by the vehicle's depth sensor and the heave sensor input is not used by system.

Note 4

1 = the positions are motion compensated

0 = the positions are not motion compensated

Note 5

0 = the system has used its own time stamp for the valid time of the positions

1 = the system has used the time stamp of the position input datagram (external time).

Note 6

If entries for a second motion sensor are not included although two sensors are being used, they are presumed to have the same parameters.

Note 7

Position system number -1.

Note 8

0 = Transducer depth sound speed is used as the initial entry the sound speed profile used in the raytracing calculations.

1 = Transducer depth sound speed is NOT used for raytracing calculations.

Note that the source of the sound speed at the transducer depth (and this sound speed is always used to calculate beam pointing angles if required) is logged in the runtime datagram.

10 SYSTEM ADMINISTRATION (UNIX)

Note

If you have a SIS operator station please refer to the SIS Operator Manual.

10.1 Introduction

This chapter provides basic reference information useful for the EM 3000 system supervisor. In order to make the most of the information provided, you may need some basic knowledge of the Unix operating system.

10.2 Passwords

EM 3000 Installation setup

In order to change the installation parameters on the EM 3000 system, you need to enter a password. This password is common for all the operators of the EM 3000 system. You will automatically be prompted to enter the password once you select **Edit enable** in the **Edit** menu.

If a password has not been identified, the first attempt to modify the installation parameters will prompt you to enter a new password.

If the password is lost, the current password can be deleted by deleting the following file:

```
$HOME/.eso_system/.esoEM 3000_protection
```

No special privileges are required to delete this file. Once it is gone, the system will prompt you for a new password next time you choose **Edit enable**.

10.3 EM 3000 File system

Introduction

The EM 3000 requires a large number of individual files. Some are used for data storage, others for system setup, while some are used to store operator and system configurations. This chapter lists the various file types and provides brief explanations.

The notation \$<name> is an “environment variable”, usually specifying a filesystem directory.

Survey files

During a survey, the EM 3000 system will record and store the following file types:

- Raw data
- Survey data

The information is stored on the Operator Station harddisk on dedicated data formats defined by Kongsberg Maritime..

Survey data

These are the data files generated by the system. Note that files will only be stored if the **Survey Format To Disk** option is checked in the window opened by **Options -> Logging**.

These files are used by the post-processing software, and by the Survey Display program.

Note

Unless this data is stored, the Survey Display application will not work.

Raw data

These are the files containing the raw data retrieved during the survey. These files are the most important files collected during a survey. If you accidentally lose your survey data format files (required by the post-processing software), you can recreate these files based on the raw data files. Care should be taken to backup raw data files on a regular basis, using the backup facilities supplied as an integral part of the system.

Sound speed profiles

All the sound speed profiles are stored as separate files in directory specified by the environment variable.

\$SHAREDHOME

The files have extension ***.asvp**

Absorption coefficient file

The absorption coefficient file contains number pairs of absorption coefficients and corresponding depths. The coefficients are integrated during loading to the echo sounder and the integrated value is used. The file is named **absorption.coef** and is stored in directory:

\$SHAREDHOME

Workstation I/O

When you define the use of the Operator Station's serial lines, the setup information is stored in the following file:

\$HOME/.eso_system/esoSetup.serial

Echo sounder parameters

These are the files determining how the current echo sounder system is set up. The system uses separate files for runtime and installation parameters.

Installation setup

The installation setup information is saved in the following file:

\$HOME/.eso_system/esoEM3000Setup.installation

Every time you save this file, a backup file is generated automatically. This file is named:

esoEM3000Setup.installation.yyyy_mmdd_hhmm

where:

yyyy=year

mm=month

dd=day

hh=hour

mm=minute.

You can also save the setup files with other names you choose yourself. You can then pick any name, but you must keep the extension as ".installation". The extension is added automatically if you only specify the file name.

Runtime setup

The runtime setup information is saved in the following file:

esoEM3000Setup.runtime

Every time you save this file, a backup file is generated automatically. This file is named:

\$HOME/.eso_system/esoEM3000Setup.runtime.yyyy_mmdd_hhmm

where:

yyyy=year

mm=month

dd=day

hh=hour

mm=minute.

You can also save the runtime files with other names you choose yourself. You can then pick any name, but you must keep the extension as “.runtime”. The extension is added automatically if you only specify the file name.

Echo sounder status

The information in the Status Field in the Launchpad is stored in the following file:

\$HOME/.eso_system/esoSetup.status

IP addresses, ports and datagrams

The IP addresses for the various items in the system, the ports used for the various applications, and the datagram distribution are collected in the following file:

\$HOME/DPC.addresses.<host>

where <host> is the name of the Operator Station.

You may modify the contents of this file by using the **Options -> Datagram subscriptions** choices on the Launchpad.

The datagrams available are listed in the following file:

\$HOME/.eso_system/esoSetup.datagrams

This is a static file, and will only be used by the system.

NMEA 0183

The information for the NMEA 0183 depth serial line is stored in the following file:

\$HOME/.eso_system/esoSetup.serial

BIST files

When you run the built-in test applications, the results displayed in the output area in the BIST window may be saved to disk. The file is created with the following location and file name:

\$HOME/.eso_system/BISToutput

Every time you save the information, the old file will be replaced. The information is stored in ASCII format.

Logfiles

Each application in the EM 3000 system issues report and error messages when required. These messages are collected in logfiles.

The size of the current logfile is monitored by the system. If it exceeds 8Mb, a warning dialogue pops up recommending a reset of the file. The actual reset is done using the **File->Reset Logfile** option, as instructed in the popup dialogue.

When you reset the logfile using the **File -> Reset logfile** command on the Launchpad, you may create a backup copy of the logfile. The backup is named:

\$HOME/.eso_system/esoLogfile.yyyy_mmdd_hhmm

where:

yyyy=year

mm=month

dd=day

hh=hour

mm=minute.

In most cases you do not need to create backup copies of the logfile, since errors and warnings are logged to the survey logfiles during active surveying.

In addition to this logfile, the errors and warnings issued during a survey are saved on a separate file for the active survey. This file is only created while logging takes place. The file is:

\$PROCHOM/<survey>/esoLogfile

where <survey> is the chosen name for the active survey.

Operator configuration files

These are the individual files containing the operator specified window layouts and desktop workspaces for the programs supervised by the EM 3000 Launchpad.

Default window layout

Each operator can define a preferred window and workspace layout, and then use the **Window Layout -> Save Operator's Layout** command on the launchpad's main menu to save this information. The name of the file will be:

`$HOME/.eso_system/esoEmX_config.<operator>`

where <operator> is the current operator of the system, as defined in the Launchpad's Survey field (below the program icons).

The default window layout is:

`$HOME/.eso_system/esoEmX_config`

List of known operators

The list of the operators known to the system is stored in the following file:

`$HOME/.eso_system/esoSetup.operators`

User preferences

All the preferences you define during the survey are stored in a separate file.

`$HOME/.eso_system/esoSetup.launchpad`

This file is created using the **Options -> User preferences** command on the Launchpad's main menu.

Survey jobs

These are the files generated by the Survey Display's Planning module. All these plans are located in the following directory:

`$SHAREDHOME/<job name>.asciiplan`

TOC files

The TOC (Table of Contents) files are created automatically when you select the Generate Tape TOC operation in the File Admin window.

Each TOC file contains a list of all the files on the tape. This is normally all the files used for a specific survey, but in general it can be any file types recognized by the File Admin utility.

The TOC files can be named manually, or they can be assigned a name automatically. This name is then defined based on the current date and time with extension *.TOC.

The files are stored in the following directory:

`$HOME/.eso_system/`

Helmsman Display

The Helmsman Display uses a file named:

`$PROCHOME/<survey>/courseoffset`

This file contains one single line defining the course deviation in 1/10 degrees. This factor is added to all the course calculations made by the Helmsman Display.

The information is entered in the **View -> Show/Hide** window in the Survey Display.

10.4 File formats

Introduction

The main files are described in this chapter, but the header files that follow the system are only referred to and must be inspected by listing the header file of current interest or by checking the computer display.

Survey format and I/O library

The **Survey Format (SF)** files are the key files of the Kongsberg Maritime workstation systems. The files are located in the **\$PROCHOME** directory. An I/O library from Kongsberg Maritime is supplied to the users who wish to access the data themselves. You can then install the I/O library wherever it fits for your development. Header files and libraries are available.

The **SF** is a Kongsberg Maritime defined format that fits for all Kongsberg multibeam echo sounder data, and for the EA 500 and EK 500 single beam echo sounders. The data is converted directly to this format if a Kongsberg Maritime logging system is used. As the lines are run, the raw data is fed into the **handleMessage** or **handleEmX** filter and stored correctly on the **\$PROCHOME/<SurveyName>** directory, while the **survey.lines** file on the same directory is updated with information about the same line.

The survey format

Introduction

This is the Kongsberg Maritime workstation processing format that applies to all multibeam echo sounders and also to some single beam echo sounders. The format is used in other workstation products in addition to *Neptune*, such as *Merlin*, *Poseidon* and *Triton*.

The format is based on indexed files. For each line there is an index file which holds some common index data for each ping. The files handled by the index file are:

- 1 Depth file
- 2 Sonar Image file
- 3 Classification file

The following files have been defined as system administration files:

4 Parameter file**5** sound speed file

These files contain parameter settings and information about the sound speed that has been used during the data collection. The information about the used sound speed is vital for reprocessing old data with new sound speed profiles.

The position files (there might be several due to more than one positioning system) are treated separately. After position processing, a new valid position file is generated and will be used for further processing (Sensor 00), version 02.

A representation of the file structure is described by the following:

Index file	Depth file	Position file
FileHeadrec	FileHeadRec	FileHeadrec
PingHeadRed	DepthFileRec 1	PosHeadRec
IndexFileRec 1	DepthFileRec 2	PositionFileRec
1		
IndexFileRec 2	PositionFileRec
2		
.....
.....	DepthFileRec i
IndexFileRec i	PositionFileR
ec i		
.....	DepthFileRec n
IndexFileRec n	PositionFileRec
n		

Raw sidescan file	Parameter file	sound speed file
FileHeadRec	FileHeadRec	FileheadRec
SideHeadRec	ParameterRec 1	SndVelFileRec 1
SideRawFileRec 1	ParameterRec 2	SndVelFileRec 2
SideRawFileRec 2
.....
.....	ParameterRec i	SndVelFileRec i
SideRawFileRec i
.....	ParameterRec n	SndVelFileRec n
SideRawFileRec n		

Survey format I/O library

The I/O sub-routine library can be used by a company or institution who have bought a license for a Kongsberg Maritime workstation product. It can also be distributed by the Kongsberg Maritime customer to others after agreement between Kongsberg Maritime and the institution or company. Maintenance and help with the library and files are given to those who have maintenance contract with Kongsberg Maritime.

The Survey format coordinate system

The coordinate system of the vessel has an x-axis along the ships keel pointing forwards from the origin of the ship. The y-axis points to starboard, and the z-axis points straight down giving the depths as positive values increasing with depth.

This generates the *right-hand coordinate system* on board the ship. Positive rotation around the axis is defined by the right-hand rule, giving a positive rotation of angles in the horizontal plane in the same way as the gyro rotates positively (Clockwise as seen from above the ship).

The data that is logged on files is in latitude/longitude coordinates. The data is represented by a 4-byte integer that has the following resolutions:

Latitude :

2*10E7 decimal degrees per number unit (+90 to -90 degrees).

Longitude:

1*10E7 decimal degrees per number unit (+180 to -180 degrees).

Depths are treated with centimetre resolution in the EM 3000 system, and represented in this resolution on the XYZ files.

Use of the Kongsberg Maritime I/O library

Introduction

The Kongsberg Maritime I/O library consists of two different parts. One part is intended to be used by those who want to fit their own data into Kongsberg Maritime's *Survey Format* (SF) file format. The modules supported for this use are *msgSim* and *handleMessage*. The *handleMessage* takes its input data from the logging program (Mermaid/Merlin) or from *msgSim*. The other part is intended to be used by those who want to use Survey Format data. This part of the library is called *RWlib* (Read and Write library). All routines in the library return an integer as return parameter. This parameter is negative if something went wrong or the data returned are not valid.

Message simulator

The message simulator (**msgSim**) simulates messages from the logging system by reading one or more raw data files, putting the message length in front of each message and writing it to *stdout*. If the messages are separated on different data files, the files containing the depth data message must end with **.dpt**, position data with **.pos**, sidescan data with **.rss** and start/stop/parameter data with **.inf**. The module also handles the situation when all messages are collected in one file. All of these data files must only contain valid, complete messages and nothing else.

Message handling

Messages from Mermaid/Merlin or msgSim may be 'piped' into **handleMessage**. This module reads the messages from **stdin**, decodes them into survey format and writes them to file. The files written are:

- position files (.pos)
- depth files (.depth)
- sidescan files (.sidescan)
- parameter files (.para)
- sound speed files (.svel)
- index files (.ind).

The name of the new file starts with the line number, an underscore, the date of the start telegram, an underscore, the time, an underscore, sensor number, an underscore, version number and the extension.

Example:

0183_19921031_155630_00_01.depth

The module starts decoding and writing when a start telegram arrives and stops when a stop telegram arrives. If sidescan data is to be handled, depth data must be present, and if the data is to be used with "near real time" visualization (i.e. Merlin), position data must also be present. For information on how to run **handleMessage**, see the section "Command references".

Library calls

Introduction

The library is written in the ANSI "C" programming language. The definition and prototyping is done in the ***.h** files:

- readWriteFile.h

- SurveyLines.h
- newFormat.h

The return structures that you need to know about are found in the **newFormat.h** file. This file is documented internally in the file, while the other *.h files not are intended to be read, just included to supply you with the structures required for some of the calls. These calls are described here, and the prototyping is found in the above listed header files.

Writing new files

For writing new files in SF the library **libRW** is supported. With this library you can open, write and close new files in SF.

Before a file (of any type) can be written, it must be opened by the appropriate open routine for this file type. The input parameters for these routines are:

- file directory,
- generic file name,
- sensor number (set to 0->zero)
- type specific header,
- a comment and a description of the process which created the file.

In addition file handler **newFilePnt** must be supported for each file (except for opening the index file) and one common write handler. E.g. this write handler is used for writing indices to files. To write new records to file, a set of writing routines are supported. All those writing routines have their specific record format, their file handler (except for writing pings) and the common write handler as parameters. When depth data or sidescan data is written, it must be specified which sounder (port or starboard for dual system or single for single system) the data comes from. To close the file (except the index file which is closed with a specific routine) the routine *closeNewFile* is called with the file handler as input.

All data are written to file in the native format (little or big Endian) in which the program is running. The index file (with ping data) is written every time the ping number changes. This is done automatically in **writeDepth** or **writePing**, which means that these routines must be called in order to let the index and ping records be written (ping number must be supplied and properly changed if not present in the raw datagram). Date and time must also be supplied for each record (ping and position) so that it will be possible to index a ping from position through data and time. When the index file is written, all indices are written including those for sidescan and position. As sidescan data only are accessible through the index file, all calls to either **writeDepth** or *writePing* must be made. Position data, on the other hand, may either be accessed via index (for "near real time") or via time. But in order to make indices for the position data correct, all data must be written in time sequence. The positions are also filtered for coarse jumps (i.e. more than one degree) and flagged accordingly before they are written. Available routines are described in the following paragraphs.

Open files

newIndexFile: Open and init index file

(IN: writeHandler, directory, fileName, sensor, pingHeader, comment, process)

newPosFile: Open and init position file

(IN: fileHandler, writeHandler, directory, fileName, sensor, posHeader, comment, process)

newDepthFile: Open and init depth file

(IN: fileHandler, writeHandler, directory, fileName, sensor, comment, process)

newSideFile: Open and init sidescan file

(IN: fileHandler, writeHandler, directory, fileName, sensor, sideHeader, comment, process)

newSvelFile: Open sound speed file

(IN: fileHandler, writeHandler, directory, fileName, sensor, comment, process)

newParaFile: Open parameter (start/stop/parameter) file

(IN: fileHandler, writeHandler, directory, fileName, sensor, comment, process)

Write files

writePos: – Write position data to file

(IN: fileHandler, writeHandler, positionRecord)

writeDepth: Write depth data to file (and possible also index and ping)

(IN: fileHandler, writeHandler, sounder, depthRecord)

writeSidescan: Write sidescan data to file

(IN: fileHandler, writeHandler, sounder, sidescanRecord)

writePing: Set current ping data, write ping and index data to file

(IN: writeHandler, sounder, pingRecord)

writeSvel: Write sound speed data to file

(IN: fileHandler, writeHandler, soundVelRecord)

writePara: Write parameter data to file

(IN: fileHandler, writeHandler, parameterRecord)

Close files

closeNewFile: Close a file

(IN: fileHandler)

closeIndexFile: Write last index/ping to file (if necessary), close index file

(IN: writeHandler)

Reading and updating survey data

For those who only want to read or update data on SF, the library *libRW* is supplied. With this library you can open, read, copy, update and close the files containing SF data.

Before anything can be done with a file, it must be opened by the appropriate opening routine. These routines have the parameters:

- 1 file mode (r or r+)
- 2 directory
- 3 file name
- 4 sensor number (set to 0)
- 5 file version number as input

In addition a file handler must be supported for each file. For the index file an index handler must also be supported. It is through this index handler that depth, sidescan and (for "near real time") position data are accessible. The different opening routines then return some type specific data (e.g. a file header and number of record). To open a file for reading, set file mode to **r** and for updating set file mode to **r+**.

If the data is written on a machine with little Endian and read on a machine with big Endian format (or vice versa), it is automatically swapped when read, or updated. If the file is copied, then it is always copied to the native format of the machine the program is running on.

Note

Compressed data can not be transferred between little Endian and big Endian machines.

Compressed data can not be transferred between little Endian and big Endian machines.

The data can be accessed in several different ways. Ping data, position data, sound speed data and parameter data are accessed via an index number which starts at 0 (zero) and goes up to the number of records (minus one) for each file. Depth data and sidescan data are accessed via the file index. This index is set with the **setFileIndexno** routine. If the depth and sidescan data were produced by a dual echo sounder system, the port and starboard can be accessed via the *port* and *stb* parameters; for single echo sounder system, the *sing* parameter is used.

To get an interpolated position for a ping, one must first call the routine **initPosInter**. This routine includes an index to the first position and number of positions as input parameters. This is because all indexing on a file within a region is based on the indices from the position file. The routine uses a handler **posSearchPnt** and returns the first valid ping index and number of indices within the positions. These parameters should then be used in the loop to access the ping, depth and sidescan data.

To get a ping with its position the routine **getPingPos** is used. This uses the parameter **indexHandler** set by **setFileIndexno**. You may also specify the maximum legal difference in time and in distance from the ping to the two nearest positions. If you only want ping data at a specific delta distance, this may also be set. If the routine returns with a negative number, no valid position exists for this ping. When finished, **freePosInter** is called.

To update a file, the file must be opened with file mode = r+. Then all the update routines can be used. Access through the index handler to depth and sidescan files must still be used. When the updating is finished, **updateHeader** must be called to set the right time and process for file updated. If you want to change other data in the files than flags, the file should be copied (with **copyFile**) before it is updated. The routine **copyFile** has as input parameter the file handler and the new directory, and it returns the new file version number.

To make a new position file from several position files (combine), the general file header must be copied with **copyHeader**. Then the copied file (header) must be opened with **openPosFileAppend** and position can be written (in sequence) with **updatePostion**.

There are also some convenience routines to update flags for position, ping and depth data. These routines read the data, check if some flags are changed and if so, write the changed data back. Modules that keep original survey data structures in memory, should use the ordinary update routines instead. It is however strongly recommended that you keep track of what flags (e.g. one variable that tells whether some of the depth flags for a ping are changed) that are changed, in order to minimize input/output. When depth flags are updated only those flags which are not equal NaN (Not a Number) are updated.

The module does also (for the time being) contain some routines to transform across- and along-data for each beam to either latitude and longitude or to UTM and to calculate the distance between two positions. Supplied routines are described in the following paragraphs.

Open files

openIndexFile Open index file

IN: fileHandler, indexHandler, fileMode, directory,
fileName, sensor, versionNumber,

OUT: pingHeader, sounderSystem, numbOfPing

openPosFile Open position file

IN: fileHandler, fileMode, directory, fileName, sensor,
versionNumber,

OUT: posHeader, numbOfPos

openDepthFile Open depth file

IN: fileHandler, fileMode, directory, fileName, sensor,
versionNumber

openSideFile Open sidescan file

IN: fileHandler, fileMode, directory, fileName, sensor,
versionNumber,

OUT: sideHeader

openSvelFile Open sound speed file

IN: fileHandler, fileMode, directory, fileName, sensor,
versionNumber,

OUT: numbOfSvel

openParaFile Open parameter file

IN: fileHandler, fileMode, directory, fileName, sensor,
versionNumber,

OUT: numbOfPara

openPosFileAppend Open position file for append

IN: fileHandler, directory, fileName, sensor,
versionNumber, posHeader)

Reading data

setFileIndexno Set index and get ping data

IN: fileHandler, indexHandler, pingIndex,

OUT: pingRecord

getDepth Get depth data

IN: fileHandler, indexHandler,

OUT: singDepthRecord, stbDepthRecord,
portDepthRecord

getSidescan Get sidescan data

IN: fileHandler, indexHandler,

OUT: singSidescanRecord, stbSidescanRecord, portSide-
scanRecord

getPosition Get position data

IN: fileHandler, posIndex,

OUT: positionRecord

getManyPos Convenience routine to get many
positions

IN: fileHandler, fromPosIndex, numbOfPos,

OUT: positionRecords

getSvel Get sound speed data

IN: fileHandler, svelIndex,

OUT: soundVelRecord

getPara Get parameter data

IN: fileHandler, paraIndex,

OUT: parameterRecord

getPosIndDateTime Get position indexes from date and time

IN: fileHandler, totNumbOfPos, fromDate, fromTime,
toDate, toTime

OUT: fromPosIndex, numbOfPos

initPosInter Initiate for accessing interpolated
positions for ping

IN: positionFileHandler, indexFileHandler, posSearchPnt,
posHeader, fromPosIndex, numbOfPos, totalNumbOfPing,

OUT: fromPingIndex, numbOfPing

getPingPos Get ping with interpolated position
IN: indexFileHandler, indexHandler, posSearchPnt,
pingIndex, deltaDistance, maximumDistance, maximumTimeDifference,
OUT: pingRecord, positionRecord

freePosInter Free data for position interpolation
IN: posSearchPnt

getManyIndex- Get noPing pings from fromPing
IN: indexFileHandler, fromPing, noPing,
OUT: indexes

getNoPing- Get number of ping in file
IN: indexFileHandler,
OUT: noPing

getInterPos Interpolate position from time and date
IN: positionFileHandler, indexFileHandler, posHead,
maxDist, maxTimeDiff,
OUT: newPos

getPosList Get position data into position list
IN: positionFileHandler, posHead, fromPos, noPos,
deltaDist, maxDist,
OUT: pingPosList

getPingList Get position data into ping list
IN: pingHead, posSearch, fromPing, noPing, deltaDist,
maxDist, maxTimeDiff,
OUT: pingPosList

getFromNoOfPing Get fromping and no of pings for pings
that are between two valid positions
IN: positionFileHandler, indexFileHandler, fromPos,
noPos, totPing,
OUT: fromPing, noPing

flagPosJump Mark all position with pos_jump_flag
which are outside a given range from the
median of the surrounding positions
IN: posHead, noPos, pos, medianFilterType, maxDist

Copy file

copyFile Copy file
IN: fileHandler, directory,

OUT: versionNumber

copyHeader Copy general file header

IN: fileHandler, directory,

OUT: versionNumber

Update file

updatePing Update ping data and set index

IN: fileHandler, indexhandler, pingIndex, pingRecord

updateDepth Update depth data

IN: fileHandler, indexHandler, singDepthRecord,
stbDepthRecord, portDepthRecord

updateSidescan Update sidescan data

IN: fileHandler, indexHandler, singSidescanRecord, stbSi
descanRecord, portSidescanRecord

updatePosition Update position

IN: fileHandler, posIndex, positionRecord

updateHeader Update file header after updating file

IN: fileHandler, process, comment

Update flags

updatePosFlag Update position flag

IN: fileHandler, posIndex, positionFlag

updatePingFlag Update ping flag and set index

IN: fileHandler, indexHandler, pingIndex, pingFlag

updateDepthFlag Update depth flag for current index

IN: fileHandler, indexHandler, singDepthFlagList,
stbDepthFlagList, portDepthFlagList

Close file

closeFile Close a file

IN: fileHandler

Convenience routines

Some routines has been developed to make life easier for the programmers. These functions are listed below.

Transform

toLL Transform each beam to latitude and longitude

IN: positionRecord, posHeader, gyroHeading,
depthRecord,

OUT: latLongPositions

toUTM Transform each beam to UTM
IN: utmSone, positionRecord, posHeader, gyroHeading, depthRecord,
OUT: utmPositions

getDiffDist Calculate distance between to positions (in centimetres)
IN: fromPositionRecord, toPositionRecord, posHeader
OUT: distance

calcDirection Calculate the direction from one position to another (in milli-degrees)
IN: fromPositionRecord, toPositionRecord, posHeader
OUT: direction

Header files

For each file there is a description on what it contains. The documentation is on the header file itself, and the user should consult this file. It is found in the IO library distribution.

For each file there is a description on what it contains. The documentation is on the header file itself, and the user should consult this file. It is found in the IO library distribution.

readWriteFile.h Handlers and prototypes for readWriteFile.c

newFormat.h Definition of survey format.

process.h Process id. description

datum.h List of datums

cdefine.h Definitions of some C programming definitions used in the programs.

general.h Definition of some general structures that are used several places in the code.

SurveyLines library

This file is important for all the processing. It includes all the lines of the survey, and identifies which versions are the most recent. The file is binary and is located on the \$PROCHOME/<SurveyName> directory.

The file **survey.lines** is an index of all existing SF data files on current directory. The file **current.line** identifies the line currently being processed. These two files must be updated by the modules writing or updating SF files. All modules reading SF files get a list of existing survey format files by reading the **survey.lines** file. The sensors that exists for the different lines are also listed on a specific file. This is the **line.sensors** file. In addition a file called **adm.data** contains the sensors of the survey with their name and their id numbers.

Writing and updating

The following routines are supplied:

```
int SIAdd (  
  s110FileType ioFileType          /* IN:  SL_SURVEY_L or SL_CURRENT_L */  
  char *dir,                      /* IN:  Directory name */  
  char *prefix,                   /* IN:  File name prefix */  
  SlsurveyFileType survFileType /* IN:  SL_POS, SL_INDEX, SL_DEPTH, or  
                                   SL_SIDESCAN */  
  int version,                    /* IN:  File version */  
  ProDescType lastProc            /* IN:  Process identification */  
)
```

This function adds a new record to the **survey.lines** file. If a record for the directory/file name prefix combination of current interest already exists, this record is updated and no new record is added. For **current.line** SIAdd has the same functionality as for **survey.lines**, except that when a new record is added, the previous record is deleted.

```
int SIUpdate (  
  SIloFileType ioFileType,        /* IN:  SL_SURVEY_L or SL_CURRENT_L */  
  char *dir,                      /* IN:  Directory name */  
  char *prefix,                   /* IN:  File name prefix */  
  SlsurveyFileType survFileType /* IN:  SL_POS, SL_INDEX, SL_DEPTH, or  
                                   SL_SIDESCAN */  
  int version,                    /* IN:  File version */  
  ProDescType lastProc            /* IN:  Process identification */  
)
```

This function is equal to the SIAdd function, except that the current directory/file name prefix combination must exist. If the new version number is lower than the version number on the **survey.lines** file, then the datafiles (.pos, .ind, .depth, or .sidescan) with version number higher than the new version number will be deleted.

```
int SIDelete(  

```

```
SIloFileType ioFileType,      /* IN:  SL_SURVEY_L or SL_CURRENT_L */
char *dir,                    /* IN:  Directory name */
char *prefix,                 /* IN:  File name prefix */
SISurveyFileType survFileType, /* IN:  SL_POS,SL_INDEX,SL_DEPTH, or
                               SL_SIDESCAN */
ProDescType lastPro          /* IN:  Process identification */
)
```

Delete a survey format file by setting the version equal to 0.
The record is deleted in the **survey.lines** file. The datafile (.pos, .ind, .depth, or .sidescan) will be deleted.

```
int SIDeleteLine(
    SIloFileType ioFileType,      /* IN:  SL_SURVEY_L or SL_CURRENT_L */
    char *dir,                    /* IN:  Directory name */
    char *prefix,                 /* IN:  File name prefix */
    ProDescType lastPro          /* IN:  Process identification */
)
```

Deletes all survey format files for a line by setting the versions equal to 0. The datafiles (.pos, .ind, .depth, and .sidescan) will be deleted and the file [<dir>/]<prefix>_00_01.para will be deleted

Reading

The following functions return information in a SIList structure (See the SurveyLines.h file for information about the structure). The following routines are supplied:

```
SISList *SICreateList (
    SIloFileType ioFileType,      /* IN:  SL_SURVEY_L or SL_CURRENT_L */
)
```

Function for reading **survey.lines** and **current.line**. SICreateList returns a SIList structure.

```
int SIUpdateList (
    SIioFileType ioFileType,      /* IN:  SL_SURVEY_L or SL_CURRENT_L */
    SIList *ioList                /* IN:  Pointer to structure from the
                                   SICreateList function */
)
```

SIUpdateList updates an existing SIList structure. Use SICreateList once to create the list. Then call SIUpdateList repeatedly to get information on changes made to the survey.lines or current.line.

Header files

This is where the programmers can find the definitions of the structures of this library. The actual header files are:

SurveyLines.h	Survey line and current line structures.
lineSensors.h	Structures and routines for the line.sensors file.

Administration file I/O

File format

The **adm.data** file contains the names of the different sensors. The file is an ASCII file named where for each sensor the following data are written:

sensor <sensorType1> <N1> <name1>

sensor <sensorType2> <N2> <name2>

sensor <sensorType1> <N3> <name3>

where **N_x** is the sensor number on the Survey Format files, and **namex** is the name of the sensor. The **sensorType_x** is position or depth. This is when more than the usual EM sensor exists. The Merlin logging system will build this file and the **survey.lines** file automatically, and the default EM sensor is given by:

sensor position 0 undefined

Reading

To read the file, the following routine is called:

AdReadAdm (EvHandler *evHand)

And to fetch the sensors read:

AdGetSensors (int *noSensors, SensorPnt *snrPnt)

Structures and files

The structures are defined in the **adm.h** file.

10.5 Survey Predefined Files

Introduction

When you define and run a survey, you will always need information describing basic data or set-up, such as:

- projection data
- user defined colours
- user defined show/hide settings
- coastline contours
- course deviation

The **Survey Predefined Files** function allows you to build a set of templates to hold this kind of information.

File locations

The Survey Predefined Files are located in the `$SHAREDHOME` directory. In this directory, you can create subdirectories defining specific survey types, where the type can be defined by your own choice. You can for example create sets of files to match specific bottom conditions or geographical locations.

The result may be (for example):

```
$SHAREDHOME/Oslofjord/*.*
```

```
$SHAREDHOME/Mercator_30_degrees/*.*
```

In order to create the file structure, and to copy in the files you wish to use, you need to open a terminal window on your Operator Station and use the standard Unix commands.

→ *Refer to the applicable instruction manual(s) for a description of the terminal window and the Unix commands.*

Using the Survey Predefined Files

When you define a new survey using the options on the EM 3000 launchpad, you are asked which of the Survey Predefined Files you will use. When you select any of the templates on the list, the files in that directory are copied over to the survey directory on `$PROCHOME`.

10.6 Projection data

Scope and purpose

This document defines the interfaces and use of the component **Projection**. The purpose with the document is to describe how the component interfaces with other components, and how the component is to be used.

Projection overview

Each and every survey should have a well defined projection. The Kongsberg Maritime Software will use the defined projection in all geographic displays and in many other programs where a projection is needed.

There are three major different ways to define a projection in the Kongsberg Maritime Software:

- 1 You have full access to the library PROJ.4 from USGS.
- 2 You can give Kongsberg Maritime the source code (in “C”) to his preferred projection, and make that projection a permanent part of all Kongsberg Maritime Software.
- 3 You can program your own projections into the shared library (libsharedProj.so) which is used in all Kongsberg Maritime Software. A template of the source code is supplied by Kongsberg Maritime.

It should be noted that Kongsberg Maritime knows nothing about what goes on inside your projection routines. Some of these routines may contain datum transformations which should be known to the system operator.

Projection protocol

You should for each and every survey define your preferred projection. The projection used in a survey is defined in the file \$PROCHOME/<survey>/projection.data

The first word in the first line defines which projection to use. The file may look like this:

- 1 If the first word is “RijksDriehoksnet”, the preferred projection for the Netherlands is used.
- 2 If the first word is “utm”, a UTM-projection is used. Setting the UTM zone is however a little tricky:

```
utm
0 3
```

0 3

If the file looks like the above, UTM zone 31 is selected.
The number 3 is the longitude.

- 3 If the first word is “sharedlib”, the projection from the shared library libsharedProj.so is used
- 4 If the first word is “user_defined”, a user defined projection from the USGS PROJ.4 library is used.
The file \$PROCHOME/<survey>/projection.data may then look like this:

```
user_defined      defaultProjections:proj1
```

This means that the user defined projection using PROJ.4 is found in the file \$PROJ_LIB/defaultsProjections and that the setup for the projection is taken from <proj1>.

The file \$PROJ_LIB/defaultsProjections may look like this:

(which is standard PROJ.4, ref. [1], [2] and [3]):

```
<proj1>
proj=stere
x_0=155000
y_0=463000
k=0.9996
lat_0=52.156160556
lon_o=5.387638889
<proj2>
proj=utm
zone=31
```

- 5 If the first word is “GK_AUSTRIA”, the preferred projection for Austria is selected. There are 16 parameters which controls this projection and they are all kept in the same file. These 16 parameters must be in the specified order in the file, the rest of the file is comments. As we can see this projection performs a datum transformation from WGS 84 to Bessel (Europe) prior to the projection. The projection itself is a Gauss-Krüger.

\$PROCHOME/<survey>/projection.data may look like this:

```
GK_AUSTRIA
-563.9
-82.3
-463.4
4.47
4.85
```

1.88
4.46
6377397.155
299.15281285
16.3333333333333
6378137.0
298.257223563
0
-5000000
500
! Line1: GK_AUSTRIA tells Simrad Software
! to use Gauss-Kruger for Austria.
! Transformationsparameter
! für die Umwandlung von WGS84-Koordinaten
! nach Gauss-Krüger-Koordinaten bezogen
! auf das Datum MGI
! Zeile 1: Translation in x [m]
! Zeile 2: Translation in y [m]
! Zeile 3: Translation in z [m]
! Zeile 4: Maßstab
! Zeile 5: Rotation in x ["]
! Zeile 6: Rotation in y ["]
! Zeile 7: Rotation in z ["]
! Zeile 8: große Halbachse [m]
! Nutzersystem (z.B. Bessel)
! Zeile 9: Abplattung Nutzersystem
! (z.B. Bessel)
! Zeile 10: Zentralmeridian Nutzersystem
! (z.B. Bessel)
! Zeile 11: große Halbachse [m] WGS84
! Zeile 12: Abplattung WGS84
! Zeile 13: Zuschlag Rechtswert
! Zeile 14: Zuschlag Hochwert
! Last line: Fixed height used in
! projections.

Notes

The setup of the projection is quite important to do right which means that this should be done by qualified persons only. In the Neptune/Survey Display system it is possible to set up default surveys that you can use as templates for new surveys. These default surveys can then be set up with the correct projections and given names which makes it easy for the operator to choose a default survey of the correct type.

There is already a file \$PROJ_LIB/defaultsProjections which is in use if some of the standard default surveys are used.

10.7 Dynamic Projection Library

Introduction

This chapter defines the interfaces and use of the component Dynamic Projection Library.

The purpose is to describe how the component interfaces with other components and how the component is to be used.

Overview

There need to be defined a shared library where the customer can implement his own projection routines to use with Kongsberg Maritime's Graphic System. This shared library will then be a permanent part of all graphic windows.

Dynamic projection library definitions

In the graphic system today you can set projection and some projection parameters in the file

`$PROCHOME/<survey>/projection.data`.

This file will also be used when you specify that projections shall be taken from the shared library **libsharedProj.so**. The shared library for customer defined projections, **libsharedProj.so**, must be put somewhere where the loader will find it at startup, `/usr/lib/libsharedProj.so`.

Dynamic projection library protocol

When you wish to use a projection defined in the shared library, the first line in the file

`$PROCHOME/<survey>/projection.data` must look like this:
`sharedlib 5`

The number (here: 5) is defined by you.

When the program (i.e. Survey, Merlin, GridDisplay) starts, it will look for the file

`$PROCHOME/<survey>/projection.data`. When it finds the word **sharedlib** as the first word in the file, the next word is read as an integer which identifies which projection will be used.

The **initUserProjection** routine is then called with this number as a parameter. This enables you to do additional initialisation to the projection. Since only the first line in `$PROCHOME/<survey>/projection.data` is used by the system, you can freely use the rest of this file for additional parameters to be read at startup time.

Each and every projection should be associated with a name. This name will appear when you wish to plot something on a plotter. For Kongsberg Maritime's Graphic System to get this name, you must supply a routine **getUserProjectionName** which also has the number as an input parameter and returns a string with the name to be used for the projection.

When Kongsberg Maritime's Graphic System is set up to use projection routines from the shared **library libsharedProj.so**, it will do so by calling two routines. The routine used for projection is **userProjectionLatLongToNorthEast**, and the routine used for the reverse projection is **userProjectionNorthEastToLatLong**.

Example

This is an example of how the codes for

- `initUserProjection`
- `getUserProjectionName`
- `userProjectionLatLongToNorthEast`
- `userProjectionNorthEastToLatLong`

should look like:

```
/* **FILEHEADER**
** $Id: dummyRoutines.c,v 1.1.1.1
** 1997/01/23 08:45:44 tp Exp $
**
** Filename: dummyRoutines.c
** Date of creation: 23 Jan 1997
** Creator: Terje Pedersen
** Purpose: Dummy-routines for the shared
**   library libsharedProj.so
**   which can be changed by the customer.
** Copyright: Kongsberg Simrad AS
** **_FILEHEADER */
#include <stdlib.h> /*calloc-function*/
#include <string.h> /*memcpy-function*/
/* **S*****
* Routine:
*   initUserProjection
* Purpose:
*   Initialize the user's preferred
```



```
*      projection. The programmer has access to
*      the file projection.data in current
*      directory which the user controls.
* Parameters:
*      int userProjectionNumber (input)
*      This is the number found in
*      projection.data
*      where the first line looks like this:
*      sharedlib 4
*      In this case userProjectionNumber will be
*      4.
* Return values:
*      0 on success, -1 on error.
* References:
*      The Component Interface
*      Document: Neptune/UserProjections.
* Changes:
* **_S** *****/
int initUserProjection(int
userProjectionNumber)
{
    switch (userProjectionNumber){
    case 1:
        break;
    default:
        return -1;
    }/*switch*/
    return 0;
}/*initUserProjection*/
/* **S*****/
* Routine:
*      getUserProjectionName
* Purpose:
*      Get the name to display in the
*      menus for this user projection.
* Parameters:
*      int userProjectionNumber (input):
*      This is the number found in
*      projection.data
*      where the first line looks like this:
*      sharedlib 4
*      In this case userProjectionNumber will
```

```
*      be 4.
* Return values:
*      A dynamically allocated character array
*      containing the name of the projection to
*      use. On error NULL is returned.
* References:
*      The Component Interface Document:
*      Neptune/UserProjections.
* Changes:
* **_S** *****/
char *getUserProjectionName(int
userProjectionNumber)
{
    char *p;
    if ((p = calloc(20,sizeof(char)))==NULL)
return NULL;
    switch (userProjectionNumber){
    case 1:
        memcpy(p,"User Projection 1",18);
        break;
    default:
        free(p);
        return NULL;
    }/*switch*/
    return p;
}/*getUserProjectionName*/
/* **S** *****/
* Routine:
*      userProjectionLatLongToNorthEast
* Purpose:
*      This routine is called to get the
*      projection coordinates from the
*      geographic coordinates.
* Parameters:
* int userProjectionNumber (input):
*      See initUserProjection.
* double latitude, double longitude (input):
*      latitude and longitude in decimal
*      degrees.
* double *north, double *east (input/output):
*      pointers to doubles where to store the
*      projection coordinates north and east
```

```
*      (in meters).
* Return values:
*      0 on success, -1 on error.
* References:
*      The Component Interface Document:
*      Neptune/UserProjections.
* Changes:
* **_S** *****/
int userProjectionLatLongToNorthEast(int
userProjectionNumber,
    double latitude, double longitude,
    double *north, double *east)
{
    if (north == NULL || east == NULL) return
-1;
    switch (userProjectionNumber){
    case 1:
        break;
    default:
        return -1;
    }/*switch*/
    return 0;
}/*userProjectionLatLongToNorthEast*/
/* **S** *****/
* Routine:
*      userProjectionNorthEastToLatLong
* Purpose:
*      This routine is called to get the
*      geographic coordinates from the
*      projection coordinates.
* Parameters:
* int userProjectionNumber (input):
*      See initUserProjection.
* double north, double east (input):
*      Projection coordinates (meters)
* double *latitude, double *longitude
* (input/output):
*      Pointers to doubles where to store the
*      geographic coordinates latitude and
*      longitude (desimal degrees).
* Return values:
*      0 on success, -1 on error.
```

```
* References:
*   The Component Interface Document:
*   Neptune/UserProjections.
* Changes:
* **_S** *****/
int userProjectionNorthEastToLatLong(int
userProjectionNumber,
    double north, double east,
    double *latitude, double *longitude)
{
    if (latitude == NULL || longitude == NULL)
return -1;
    switch (userProjectionNumber){
    case 1:
        break;
    default:
        return -1;
    }/*switch*/
    return 0;
}/*userProjectionNorthEastToLatLong*/
```

The makefile on a DEC OSF1 UNIX workstation looks like this:

```
# $Id: Makefile,v 1.1 1997/01/23 11:12:07 tp
Exp $
# Makefile to create libsharedProj.so.
#
# 23 Jan 1997, Terje Pedersen
#
# Copyright: Kongsberg Simrad AS
#
#
.PHONY:install lib clean
CC=cc
LD=ld
LDFLAGS=-shared -no_archive
INSTALL=/usr/local/lib
dummyRoutines.o: dummyRoutines.c
@$(CC) -c $<
lib: dummyRoutines.o
```

```
@$(LD) $(LDFLAGS) -o libsharedProj.so  
dummyRoutines.o -lc  
  
install: lib  
@cp libsharedProj.so  
$(INSTALL)/libsharedProj.so  
@cp dummyRoutines.h  
$(NEPTUNEHOME)/include/simrad/.  
@ls -l $(INSTALL)/libsharedProj.so  
@ls -l  
$(NEPTUNEHOME)/include/simrad/dummyRoutines.h  
  
clean:  
@rm dummyRoutines.o libsharedProj.so
```

The makefile is probably very similar on other platforms.

Notes

There are some restrictions on shared libraries on every platform. You should be aware of this. When upgrading Kongsberg Maritime Software the customer's shared library should be reinstalled to make sure it is the one being used. You are encouraged to use the initialisation routine to test that the projection is working.

Heights are not used in Kongsberg Maritime's Graphic system. It is not necessary in the projections since the height varies very little within one survey that a fixed height will suffice. This can be a parameter in \$PROCHOME/<survey>/projection.data that you can read at startup time and use in the projections internally.

11 SPARE PARTS

11.1 Overview

This chapter contains an illustrated presentation of the spare parts available for the EM 3000 multibeam echo sounder. All the parts are not listed her, only those defined as Line Replaceable Units (LRU) to be changed by the on-board maintenance personnel.

11.2 Spares data presentation

Spares table

The parts are presented in a table format ("5008") specified by the Royal Norwegian Navy.

An example is shown below.

10 SNo	11 Drawing ref	13 Prod.p.no	15 Article name	18 Price	21 Unit	22 Quantity
	12 Other ref.	14 TM part.no	16 Technical data	19 TM code	26 User-spares	27 Base spares
	24 Date	17 NATO No		23 Status	20 Comp	25 Ser.no.
1	Fig.1 - 05.03.97	290-085827 - -	Powec Power Supply PMP 4M.02	- - -	EA 0 C	1 0 N/A
2	Fig.1 05.03.97	299-049179 - -	Fan Drawer Assembly	- - -	EA 0 C	3 0 N/A

The parts information in this table also conforms to the civilian standard **NS 5820** specified by the Norwegian Standardisation Society (Norges Standardiserings Forbund).

Parts list codes

These are the code descriptions for the information in the table.

Key codes to the parts list		
No	Caption	Description
10	Serial no.	Row number in list.
11	Drawing no. & item no.	The number of the drawing, and the position on that drawing, of the part.
12	Other references	Any other applicable references are included here.
13	Producer's part no.	The part number to be used when ordering spares from Kongsberg Maritime AS.
14	True manufacturer's part no.	Part number designated by manufacturer of part. Will be same as (13) if part is manufactured or assembled by Kongsberg Maritime AS.
15	Article name	The name of the unit or part.
16	Technical data	Any additional technical information which may be relevant.
17	NATO catalogue no.	The NATO stock number will be added where appropriate.
18	Currency/unit price	Price of the part, and the applicable currency
19	True manufacturer's code	This is a code number to identify the suppliers of the parts to enable you to order directly from the suppliers in an emergency.
20	Component	<p>Component definition.</p> <p>C = a component which cannot be broken down into smaller units.</p> <p>P = a part which may contain separately replaceable components.</p> <p>S = a set of parts.</p>
21	Unit	The SI units applicable to the component. E.G. m = metric units for bolts etc.
22	Quantity	The total number of that particular part included in the system.
23	Status	Code for use by the Navy. Will be completed by the Navy
24	Date	This is the date the row was last updated.
25	Serial number	The component serial number where applicable.
26	User spares	The suggested number of spares to be held by the user.
27	Spares at base	The suggested number of spares to be held at the user's home base.

11.3 Operator Station (HWS 10) spare parts

The line replaceable units in the HWS10 Operator Station are circuit boards, fans and power supply

Commercial items can be replaced by other manufacturers than the ones listed here. But be sure of compability.

SNo	Drawing ref	Prod.p.no	Article name	Price	Unit	Quantity
	Other ref.	TM part.no	Technical data	TM code	User-spares	Base spares
	Date	NATO No	Other information	Status	Comp	Ser.no.
1	Fig.-	719-099078	Motherboard	-	EA	1
	-	PC-DL DELUXE	-	-	0	0
	01.04.04	-	Commercial item (ASUS)	-	C	N/A
2	Fig.-	719-099080	Memory PC2700, 512 MB	-	EA	4
	-	CT6472Z335	DDR DIMM, Unbuffered, ECC	-	0	0
	01.04.04	-	Commercial item (Crucial)	-	C	N/A
3	Fig.-	719-099079	Processor	-	EA	1 (or 2)
	-	BX80532KE2800B	Intel 2.8 GHz Xeon (PC533)	-	0	0
	01.04.04	-	(mounted on the motherboard)	-	C	N/A
4	Fig.-	719-099081	Graphics card	-	EA	1
	-	V9560XT	Nvidia FX5600XT 128 MB	-	0	0
	01.04.04	-	Commercial item (ASUS)	-	C	N/A
5	Fig.-	719-099093	Hard disk	-	EA	1
	-	WD1200JD	IDE, Caviar 120 GB, S-ATA	-	0	0
	01.04.04	-	Comm. item (Western Digital)	-	C	N/A
6	Fig.-	719-099082	Hard disk	-	EA	2
	-	WD360GD	Raptor 36.7 GB S-ATA	-	0	0
	01.04.04	-	Comm. item (Western Digital)	-	C	N/A
7	Fig.-	719-099085	Hot-Swap drive enclosure	-	EA	2
	-	SuperSwap 1100	Disk enclosure for S-ATA disk	-	0	0
	01.04.04	-	Commercial item (Promise)	-	C	N/A
8	Fig.-	719-099083	DVD recorder	-	EA	1
	-	PX-708A/T3B	8 x DVD+R	-	0	0
	01.04.04	-	Commercial item (Plextor)	-	C	N/A
9	Fig.-	719-099090	3.5" floppy disk	-	EA	1
	-	MPF-920-Z/121	-	-	0	0
	01.04.04	-	Commercial item (Sony)	-	C	N/A
10	Fig.-	719-099133	Ethernet card	-	EA	1
	-	PILA8460BN	10/100 Mbs	-	0	0
	01.04.04	-	Commercial item (Intel)	-	C	N/A
11	Fig.-	719-099084	SCSI card	-	EA	1
	-	DC-315U Ultra	Ultra narrow	-	0	0
	01.04.04	-	Commercial item (Tekram)	-	C	N/A
12	Fig.-	719-099086	Power supply	-	EA	1
	-	EG465AX-VE(W)	ATX 460W PFC	-	0	0
	01.04.04	FM 24P	Commercial item (Enermax)	-	C	N/A
13	Fig.-	-	Fan	-	EA	1
	-	FD121225HB	80mm, 12Vdc	-	0	0
	01.04.04	-	Commercial item	-	C	N/A
14	Fig.-	-	Fan	-	EA	1
	-	KM128025HB	120mm, 12Vdc	-	0	0
	01.04.04	-	Commercial item	-	C	N/A

11.4 Processing Unit spare parts

The line replaceable units in the EM 3000 Processing Unit are:

- Circuit boards
- Fans
- Power supply

Note

The AUV Processing Unit does not contain a power supply and serial board.

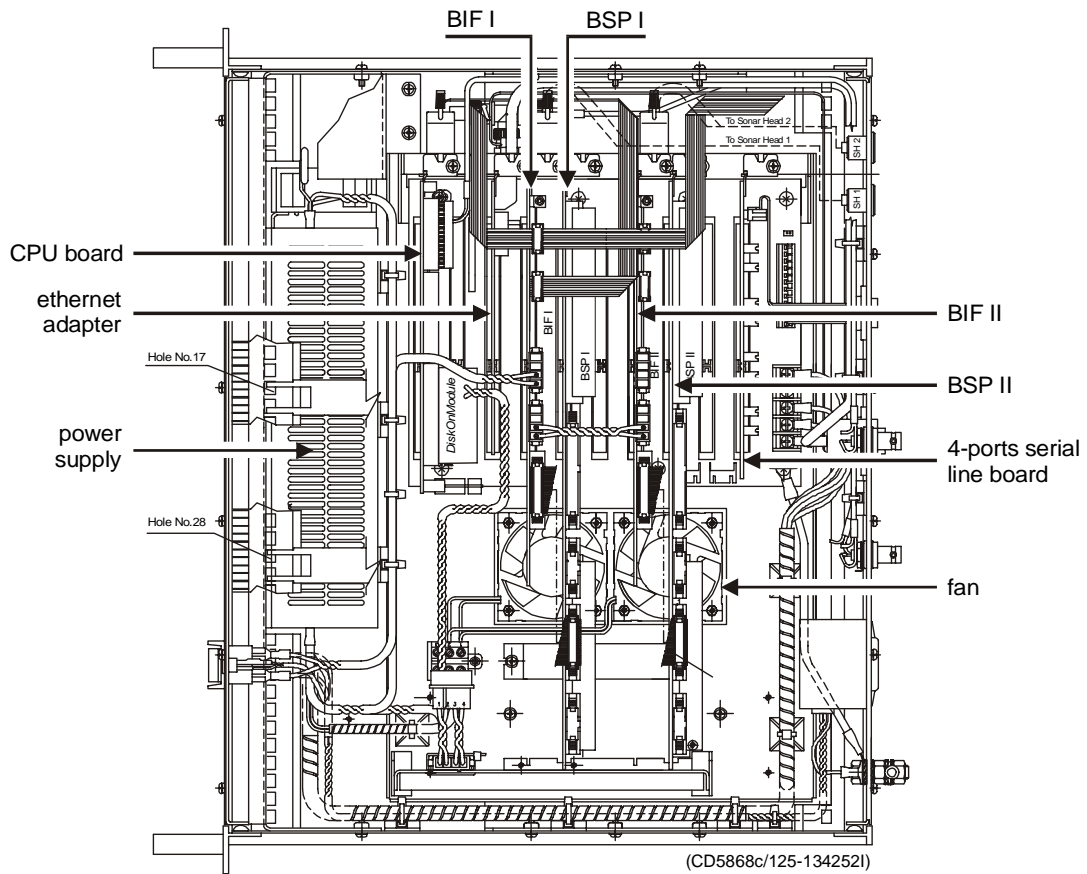


Figure 29 The Processing Unit, spare parts

The spare parts in The Processing Unit are those circuit boards used in the chassis.

Standard Processing Unit spare parts

SNo	Drawing ref	Prod.p.no	Article name	Price	Unit	Quantity
	Other ref.	TM part.no	Technical data	TM code	User-spares	Base spares
	Date	NATO No	Other information	Status	Comp	Ser.no.
3	Fig.29	719-098382	4-ports Serial Line Board	-	EA	1
		-	CI-104JS	-	1	0
	21.06.02	-		-	C	N/A
3	Fig.29	719-087002	4-ports Serial Line Board	-	EA	1
		-	C114P	-	1	0
	21.06.02	-		-	C	N/A
3	Fig.29	382-214580	Beamformer & Signal Processor	-	EA	2
		-	(BSP, Old PU)	-	0	1
	21.06.02	-		-	C	N/A
3	Fig.29	382-218016	Beamformer & Signal Processor	-	EA	2
		-	(BSP, New PU)	-	0	1
	21.06.02	-		-	C	N/A
3	Fig.29	382-211722	Beamformer Interface (BIF B)	-	EA	2
		-		-	0	1
	21.06.02	-		-	C	N/A
5	Fig.29	719-087003	Ethernet Adapter	-	EA	1
		-		-	0	1
	21.06.02	-	Commercial item	-	C	N/A
3	Fig.29	719-097597	Disk On Module	-	EA	2
		-	(mounted on the Processor board)	-	0	1
	21.06.02	-		-	C	N/A
2	Fig.29	719-087004	Passive Backplane	-	EA	1
		-		-	0	0
	21.06.02	-	Commercial item	-	C	N/A
2	Fig.29	719-098108	Processor Board VIPer	-	EA	1
		-		-	0	0
	21.06.02	-	Commercial item	-	C	N/A
2	Fig.29	719-097239	Processor Board SSC	-	EA	1
		-		-	0	0
	21.06.02	-	Commercial item	-	C	N/A
2	Fig.29	290-133924	Power Supply	-	EA	1
		-		-	0	0
	21.06.02	-		-	C	N/A
6	Fig.29	129-096870	Fan, axial, 12 Vdc	-	EA	2
		-		-	0	1
	21.06.02	-	Commercial item	-	C	N/A
6	Fig.29	129-096790	Fan, axial, 24 Vdc	-	EA	2
		-		-	0	1
	21.06.02	-	Commercial item	-	C	N/A

AUV Processing Unit spare parts

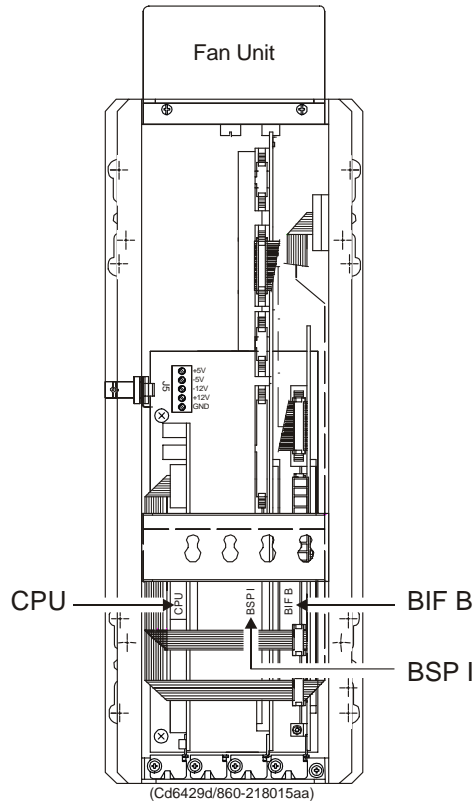


Figure 30 The AUV Processing Unit, spare parts

SNo	Drawing ref	Prod.p.no	Article name	Price	Unit	Quantity
	Other ref.	TM part.no	Technical data	TM code	User-spares	Base spares
	Date	NATO No	Other information	Status	Comp	Ser.no.
1	Fig.30	719-097988	Processor Board	-	EA	1
	12.03.02	-	Commercial item	-	0	0
		-		-	C	N/A
2	Fig.30	382-211722	Beamformer Interface (BIF B)	-	EA	1
	12.03.02	-	Commercial item	-	0	1
		-		-	C	N/A
3	Fig.30	382-218016	Beamformer & Signal Processor (BSP)	-	EA	1
	12.03.02	-	Commercial item	-	0	1
		-		-	C	N/A
4	Fig.30	382-215857	Passive Backplane	-	EA	1
	12.03.02	-		-	0	0
		-		-	C	N/A
5	Fig.30	719-097987	Disk On Module (mounted on the Processor board)	-	EA	1
	12.03.02	-		-	0	N/A
		-		-	C	
6	Fig.30	129-098158	Fan, axial, 5 Vdc	-	EA	1
	21.06.02	-	Commercial item	-	0	
		-		-	C	N/A

11.5 Sonar Head spare parts

The line replaceable units in the EM 3000 Sonar Head are:

- Circuit boards
- Cable

SNo	Drawing ref	Prod.p.no	Article name	Price	Unit	Quantity
	Other ref.	TM part.no	Technical data	TM code	User-spares	Base spares
	Date	NATO No	Other information	Status	Comp	Ser.no.
1	- - 15.01.04	382-210927 - -	HCT board	- - -	EA 1 C	1 0 N/A
2	- - 15.01.04	382-112338 - -	HRX board	- - -	EA 0 C	1 0 N/A
3	- - 15.01.04	380-133240 - -	Sonar Head cable	- - -	EA 0 C	1 0 N/A

12 DRAWING FILE

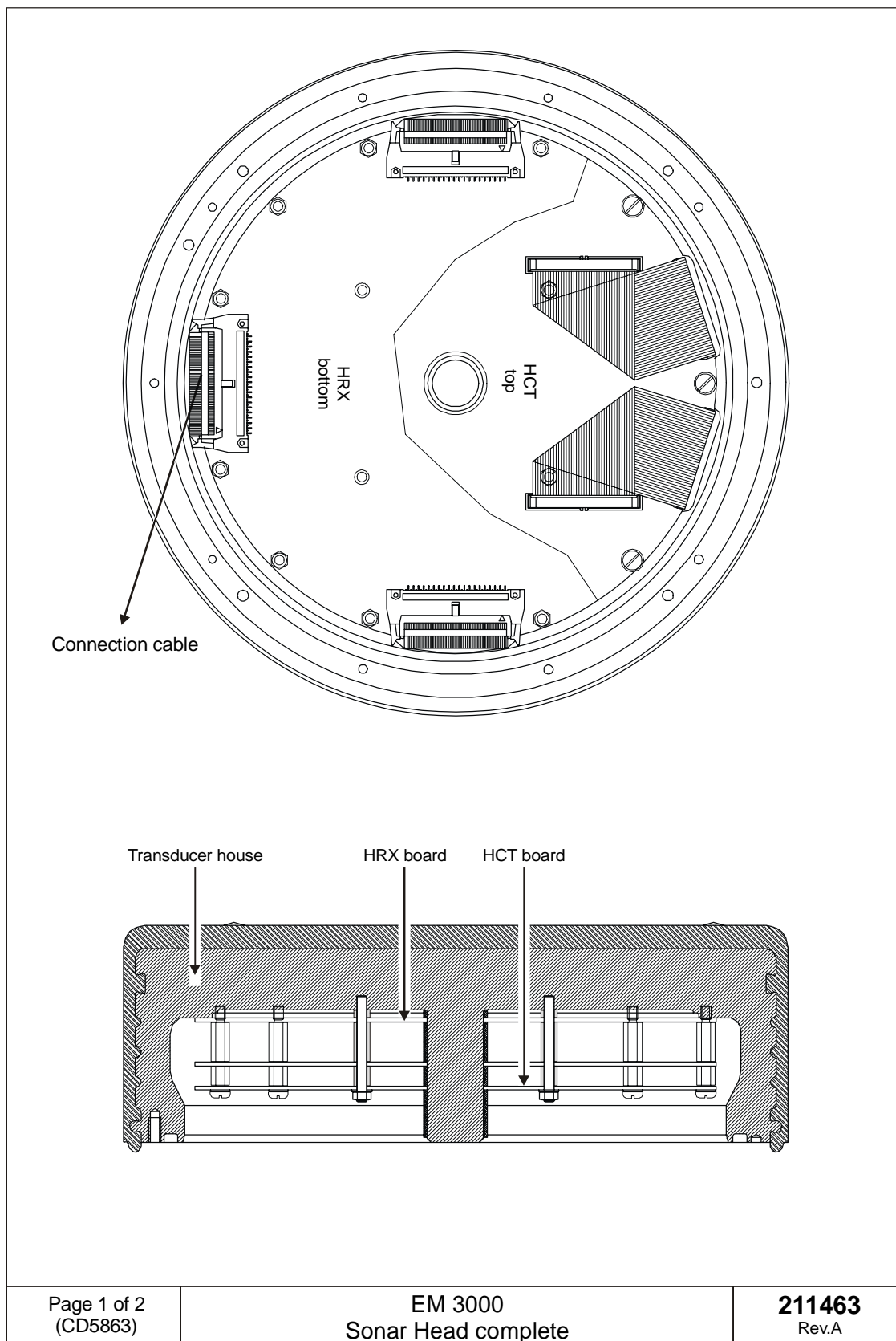
12.1 Introduction

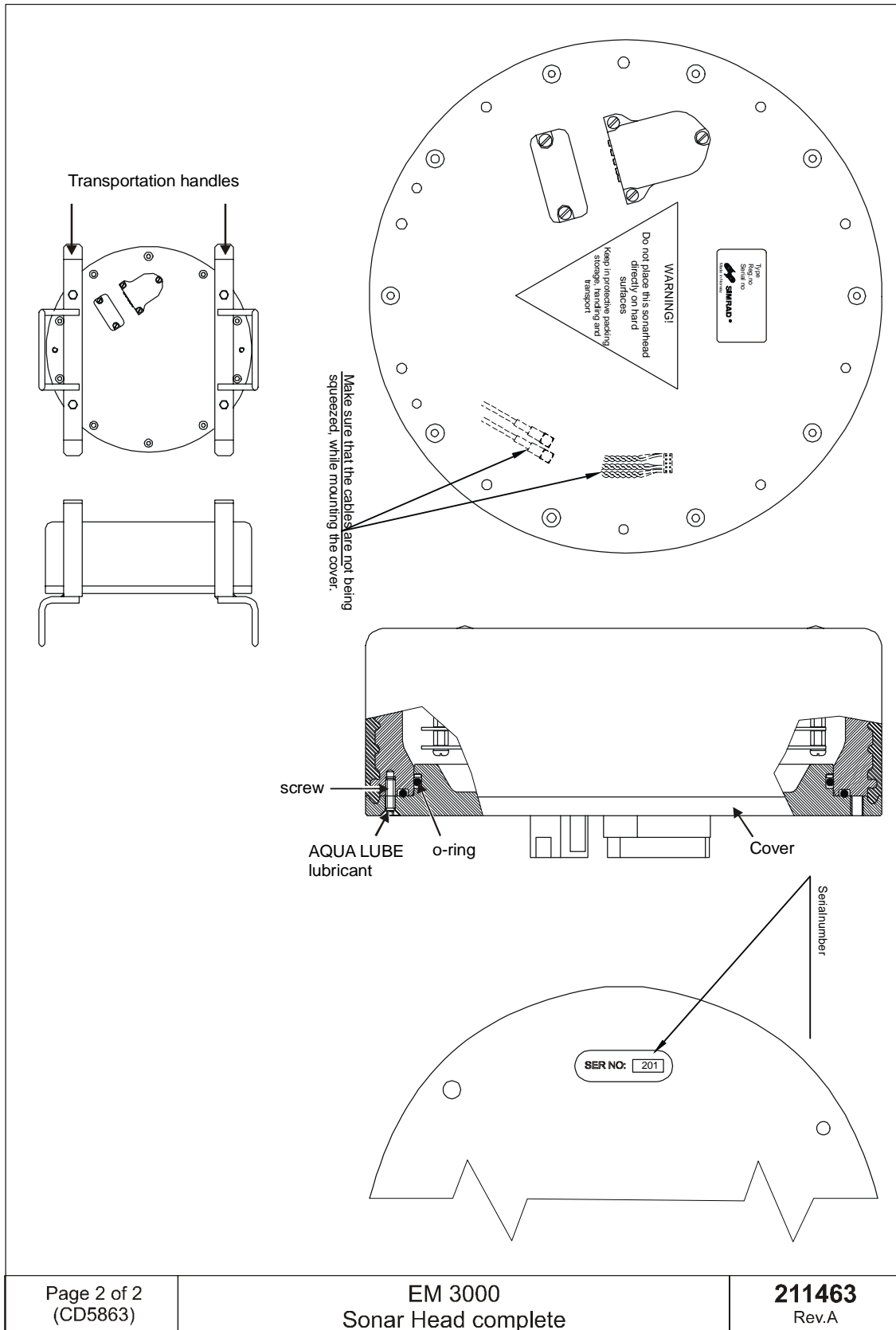
This chapter holds drawings that are in addition to the illustrations in the manual.

12.2 Drawing list

The following drawings are included:

860-211463 (Rev. A)
Sonar Head, complete 1/2 (page 255)
869-211463 (Rev. A)
Sonar Head, complete 2/2 (page 256)





Blank page

EM 3000
Maintenance manual / Base version

EM 3000
Maintenance manual / Base version

EM 3000
Maintenance manual / Base version

EM 3000
Maintenance manual / Base version