

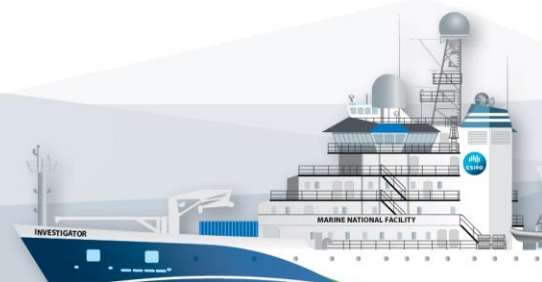
RV Investigator

ADCP Processing Report

Voyage ID:	in2021_e04
Voyage title:	Trials and Calibration
Mobilisation:	Hobart, 10-12 December 2021
Depart:	Hobart, 0800 AEDT Wednesday 15 December 2021
Return:	Hobart, 0800 AEDT Monday 20 December 2021
Demobilisation:	Hobart, 21 December 2021
Voyage Manager:	Claire Grubb
Chief Scientist:	Tara Martin, CSIRO

Document History

Date	Version	Author	Comments
7 January 2022	1.0	Richard Atkinson	Initial version



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1 Summary

Data was collected during in2021_e04 for sections of the voyage. Data was collected using UHDAS and post-processed using CODAS.

The RDI Ocean Surveyor 150kHz ADCP (os150) was run in broadband with 4m bins from the start of the voyage, while in relatively shallow water, from 2021-12-14 22:12Z. The os150 was turned off at 2021-12-15 21:17Z to avoid interference with other sounders data that were being collected. From 2021-12-16 10:50Z both the os150 and the RDI Ocean Surveyor 75kHz ADCP (os75) were run in narrowband with 8m bins. The os75 was switch off at 2021-12-19 21:10Z as the vessel entered shallower water. The os150 was switched off at the end of the voyage at 2021-12-19 12:45Z.

In summary, data were collected for the following time periods:

Transducer and mode	Start (UTC)	End (UTC)
os150 broadband 4m bins	2021-12-14 22:12	2021-12-15 21:17
os150 narrowband 8m bins	2021-12-16 10:50	2021-12-19 21:10
os75 narrowband 16m bins	2021-12-16 10:50	2021-12-19 12:45

Internal triggering was used.

The drop keel was 'flush with the gondola' at 1.19m below the waterline for the duration of the voyage.

See the voyage computing and electronics report for more details regarding data acquisition.

2 Processing Background

The University of Hawaii's CODAS software (codas_focal_20.04 2021-05-01) was used for data post-processing. (https://currents.soest.hawaii.edu/docs/adcp_doc/index.html)

3 Processing Notes

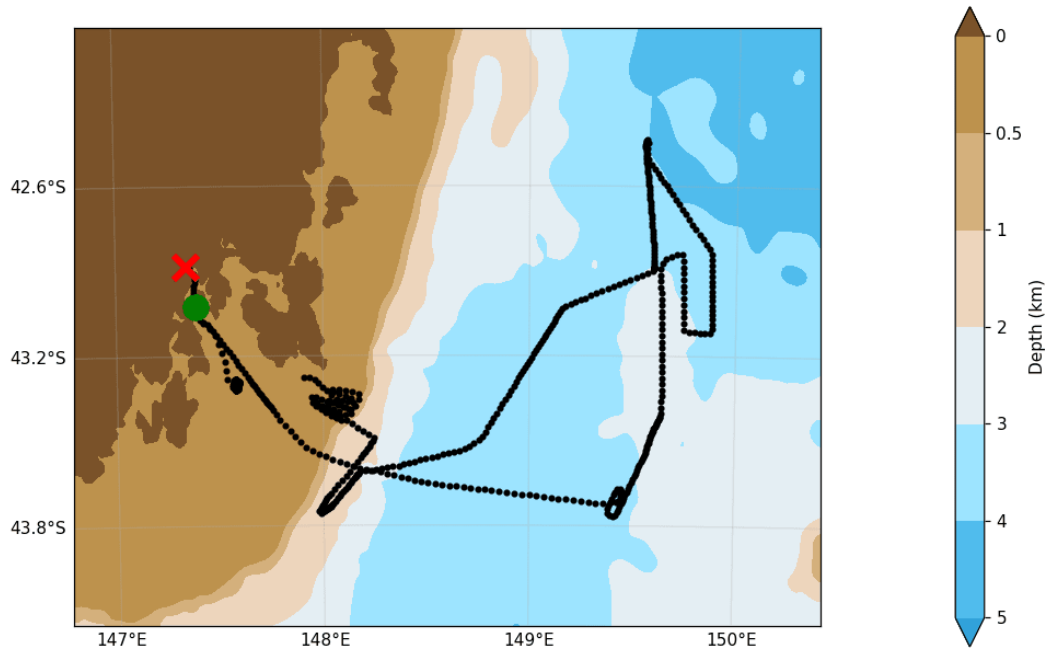
No heading correction were applied as all data were within acceptable limits.

No additional amplitude or phase adjustments were applied to the transducer angles of any of the data as they were all within acceptable limits.

Minor edits were applied to remove spurious data at the beginning and end of the voyage and where data were patchy at the depth limits of the transducers.

4 Area Covered

in2021_e04



Please see the webpy_bb and webpy_nb folders for plots of collected data.

5 netCDF Data Headers

5.1 os150 broadband

```
netcdf in2021_e04_os150bb {
dimensions:
    time = 278 ;
    depth_cell = 80 ;
variables:
    int trajectory ;
        trajectory:standard_name = "trajectory_id" ;
    double time(time) ;
        time:long_name = "Decimal day" ;
        time:units = "days since 2021-01-01 00:00:00" ;
        time:C_format = "%12.5f" ;
        time:standard_name = "time" ;
        time:data_min = 347.925208333333 ;
        time:data_max = 348.887002314815 ;
    double lon(time) ;
        lon:missing_value = 1.e+38 ;
        lon:long_name = "Longitude" ;
        lon:units = "degrees_east" ;
        lon:C_format = "%9.4f" ;
        lon:standard_name = "longitude" ;
        lon:data_min = 147.387077777778 ;
        lon:data_max = 147.593697222222 ;
    double lat(time) ;
        lat:missing_value = 1.e+38 ;
        lat:long_name = "Latitude" ;
        lat:units = "degrees_north" ;
        lat:C_format = "%9.4f" ;
        lat:standard_name = "latitude" ;
        lat:data_min = -43.3213638888889 ;
        lat:data_max = -43.0419777777778 ;
    float depth(time, depth_cell) ;
        depth:missing_value = 1.e+38f ;
        depth:long_name = "Depth" ;
        depth:units = "meter" ;
        depth:C_format = "%8.2f" ;
        depth:positive = "down" ;
        depth:data_min = 14.24f ;
        depth:data_max = 330.24f ;
    float u(time, depth_cell) ;
        u:missing_value = 1.e+38f ;
        u:long_name = "Zonal velocity component" ;
        u:units = "meter second-1" ;
        u:C_format = "%7.2f" ;
        u:data_min = -0.4632652f ;
        u:data_max = 0.3763531f ;
    float v(time, depth_cell) ;
        v:missing_value = 1.e+38f ;
        v:long_name = "Meridional velocity component" ;
        v:units = "meter second-1" ;
        v:C_format = "%7.2f" ;
        v:data_min = -0.1641727f ;
        v:data_max = 0.2961653f ;
    short amp(time, depth_cell) ;
        amp:missing_value = 32767s ;
        amp:long_name = "Received signal strength" ;
        amp:C_format = "%d" ;
        amp:data_min = 27s ;
        amp:data_max = 222s ;
    byte pg(time, depth_cell) ;
        pg:missing_value = -1b ;
```

```
pg:long_name = "Percent good pings" ;
pg:C_format = "%d" ;
pg:data_min = 0b ;
pg:data_max = 100b ;
byte pflag(time, depth_cell) ;
pflag:long_name = "Editing flags" ;
pflag:C_format = "%d" ;
pflag:data_min = 0b ;
pflag:data_max = 6b ;
float heading(time) ;
heading:missing_value = 1.e+38f ;
heading:long_name = "Ship heading" ;
heading:units = "degrees" ;
heading:C_format = "%6.1f" ;
heading:data_min = -179.9243f ;
heading:data_max = 179.9995f ;
float tr_temp(time) ;
tr_temp:missing_value = 1.e+38f ;
tr_temp:long_name = "ADCP transducer temperature" ;
tr_temp:units = "Celsius" ;
tr_temp:C_format = "%4.1f" ;
tr_temp:data_min = 15.37796f ;
tr_temp:data_max = 16.38993f ;
short num_pings(time) ;
num_pings:long_name = "Number of pings averaged per ensemble" ;
num_pings:units = "None" ;
num_pings:C_format = "%d" ;
num_pings:data_min = 136s ;
num_pings:data_max = 137s ;
float uship(time) ;
uship:missing_value = 1.e+38f ;
uship:long_name = "Ship zonal velocity component" ;
uship:units = "meter second-1" ;
uship:C_format = "%9.4f" ;
uship:data_min = -0.8507022f ;
uship:data_max = 4.40038f ;
float vship(time) ;
vship:missing_value = 1.e+38f ;
vship:long_name = "Ship meridional velocity component" ;
vship:units = "meter second-1" ;
vship:C_format = "%9.4f" ;
vship:data_min = -5.952173f ;
vship:data_max = 2.145856f ;

// global attributes:
:featureType = "trajectoryProfile" ;
:history = "Created: 2022-01-05 22:45:57 UTC" ;
:Conventions = "COARDS" ;
:software = "pycurrents" ;
:hg_changeset = "3159:c22d6c40e594" ;
:title = "Shipboard ADCP velocity profiles" ;
:description = "Shipboard ADCP velocity profiles from in2021_e04 using instrument
os150bb - Short Version." ;
:cruise_id = "in2021_e04" ;
:sonar = "os150bb" ;
:yearbase = 2021 ;
:ship_name = "RV Investigator" ;
:CODAS_variables = "\n",
    "Variables in this CODAS short-form Netcdf file are intended for most end-
user\n",
    "scientific analysis and display purposes. For additional information
see\n",
    "the CODAS_processing_note global attribute and the attributes of each\n",
    "of the variables.\n",
    "\n",
    "\n",
```

```

"====="
=====\\n",
"time          Time at the end of the ensemble, days from start of year.\\n",
"lon, lat      Longitude, Latitude from GPS at the end of the ensemble.\\n",
"u,v          Ocean zonal and meridional velocity component profiles.\\n",
"uship, vship  Zonal and meridional velocity components of the ship.\\n",
"heading       Mean ship heading during the ensemble.\\n",
"depth        Bin centers in nominal meters (no sound speed profile
correction).\\n",
"tr_temp      ADCP transducer temperature.\\n",
"pg           Percent Good pings for u, v averaging after editing.\\n",
"pflag        Profile Flags based on editing, used to mask u, v.\\n",
"amp          Received signal strength in ADCP-specific units; no
correction\\n",
"            for spreading or attenuation.\\n",
"====="
=====\\n",
"\\n",
"" ;
:CODAS_processing_note = "\\n",
"CODAS processing note:\\n",
"====="\\n",
"\\n",
"Overview\\n",
"-----\\n",
"The CODAS database is a specialized storage format designed for\\n",
"shipboard ADCP data.  \\nCODAS processing\\n" uses this format to hold\\n",
"averaged shipboard ADCP velocities and other variables, during the\\n",
"stages of data processing.  The CODAS database stores velocity\\n",
"profiles relative to the ship as east and north components along with\\n",
"position, ship speed, heading, and other variables.  The netCDF *short*\\n",
"form contains ocean velocities relative to earth, time, position,\\n",
"transducer temperature, and ship heading; these are designed to be\\n",
"\\nready for immediate use\\n".  The netCDF *long* form is just a dump of\\n",
"the entire CODAS database.  Some variables are no longer used, and all\\n",
"have names derived from their original CODAS names, dating back to the\\n",
"late 1980\\'s.\\n",
"\\n",
"Post-processing\\n",
"-----\\n",
"CODAS post-processing, i.e. that which occurs after the single-ping\\n",
"profiles have been vector-averaged and loaded into the CODAS database,\\n",
"includes editing (using automated algorithms and manual tools),\\n",
"rotation and scaling of the measured velocities, and application of a\\n",
"time-varying heading correction.  Additional algorithms developed more\\n",
"recently include translation of the GPS positions to the transducer\\n",
"location, and averaging of ship\\'s speed over the times of valid pings\\n",
"when Percent Good is reduced.  Such post-processing is needed prior to\\n",
"submission of \\nprocessed ADCP data\\n" to JASADCP or other archives.\\n",
"\\n",
"Full CODAS processing\\n",
"-----\\n",
"Whenever single-ping data have been recorded, full CODAS processing\\n",
"provides the best end product.\\n",
"\\n",
"Full CODAS processing starts with the single-ping velocities in beam\\n",
"coordinates.  Based on the transducer orientation relative to the\\n",
"hull, the beam velocities are transformed to horizontal, vertical, and\\n",
"\\nerror velocity\\n" components.  Using a reliable heading (typically
from\\n",
"the ship\\'s gyro compass), the velocities in ship coordinates are\\n",
"rotated into earth coordinates.\\n",
"\\n",
"Pings are grouped into an \\nensemble\\n" (usually 2-5 minutes duration)\\n",
"and undergo a suite of automated editing algorithms (removal of\\n",
"acoustic interference; identification of the bottom; editing based on\\n",
"thresholds; and specialized editing that targets CTD wire interference\\n",

```

```
"and \"weak, biased profiles\". The ensemble of single-ping velocities\n",  
"is then averaged using an iterative reference layer averaging scheme.\n",  
"Each ensemble is approximated as a single function of depth, with a\n",  
"zero-average over a reference layer plus a reference layer velocity\n",  
"for each ping. Adding the average of the single-ping reference layer\n",  
"velocities to the function of depth yields the ensemble-average\n",  
"velocity profile. These averaged profiles, along with ancillary\n",  
"measurements, are written to disk, and subsequently loaded into the\n",  
"CODAS database. Everything after this stage is \"post-processing\".\n",  
"\n",  
"note (time):\n",  
"-----\n",  
"Time is stored in the database using UTC Year, Month, Day, Hour,\n",  
"Minute, Seconds. Floating point time \"Decimal Day\" is the floating\n",  
"point interval in days since the start of the year, usually the year\n",  
"of the first day of the cruise.\n",  
"\n",  
"\n",  
"note (heading):\n",  
"-----\n",  
"CODAS processing uses heading from a reliable device, and (if\n",  
"available) uses a time-dependent correction by an accurate heading\n",  
"device. The reliable heading device is typically a gyro compass (for\n",  
"example, the Bridge gyro). Accurate heading devices can be POSMV,\n",  
"Seapath, Phins, Hydrins, MAHRS, or various Ashtech devices; this\n",  
"varies with the technology of the time. It is always confusing to\n",  
"keep track of the sign of the heading correction. Headings are written\n",  
"degrees, positive clockwise. setting up some variables:\n",  
"\n",  
"X = transducer angle (CONFIG1_heading_bias)\n",  
"    positive clockwise (beam 3 angle relative to ship)\n",  
"G = Reliable heading (gyrocompass)\n",  
"A = Accurate heading\n",  
"dh = G - A = time-dependent heading correction  
(ANCIL2_watrk_hd_misalign)\n",  
"\n",  
"Rotation of the measured velocities into the correct coordinate system\n",  
"amounts to  $(u+iv) * (exp(i*theta))$  where theta is the sum of the\n",  
"corrected heading and the transducer angle.\n",  
"\n",  
"theta = X + (G - dh) = X + G - dh\n",  
"\n",  
"\n",  
"Watertrack and Bottomtrack calibrations give an indication of the\n",  
"residual angle offset to apply, for example if mean and median of the\n",  
"phase are all 0.5 (then R=0.5). Using the \"rotate\" command,\n",  
"the value of R is added to \"ANCIL2_watrk_hd_misalign\".\n",  
"\n",  
"new_dh = dh + R\n",  
"\n",  
"Therefore the total angle used in rotation is\n",  
"\n",  
"new_theta = X + G - dh_new\n",  
"           = X + G - (dh + R)\n",  
"           = (X - R) + (G - dh)\n",  
"\n",  
"The new estimate of the transducer angle is: X - R\n",  
"ANCIL2_watrk_hd_misalign contains: dh + R\n",  
"\n",  
"=====\n",  
"\n",  
"Profile flags\n",  
"-----\n",  
"Profile editing flags are provided for each depth cell:\n",  
"\n",  
"binary    decimal    below    Percent\n",  
"value     value     bottom   Good      bin\n",
```



```
"-----+-----+-----+-----+\n",  
"000      0\n",  
"001      1                      bad\n",  
"010      2                      bad\n",  
"011      3                      bad\n",  
"100      4      bad\n",  
"101      5      bad                      bad\n",  
"110      6      bad      bad\n",  
"111      7      bad      bad      bad\n",  
"-----+-----+-----+-----+\n",  
" " ;
```

}

5.3 os150 narrowband

```
netcdf in2021_e04_os150nb {
dimensions:
    time = 989 ;
    depth_cell = 60 ;
variables:
    int trajectory ;
        trajectory:standard_name = "trajectory_id" ;
    double time(time) ;
        time:long_name = "Decimal day" ;
        time:units = "days since 2021-01-01 00:00:00" ;
        time:C_format = "%12.5f" ;
        time:standard_name = "time" ;
        time:data_min = 349.451585648148 ;
        time:data_max = 352.882546296296 ;
    double lon(time) ;
        lon:missing_value = 1.e+38 ;
        lon:long_name = "Longitude" ;
        lon:units = "degrees_east" ;
        lon:C_format = "%9.4f" ;
        lon:standard_name = "longitude" ;
        lon:data_min = 147.3386 ;
        lon:data_max = 149.887458333333 ;
    double lat(time) ;
        lat:missing_value = 1.e+38 ;
        lat:long_name = "Latitude" ;
        lat:units = "degrees_north" ;
        lat:C_format = "%9.4f" ;
        lat:standard_name = "latitude" ;
        lat:data_min = -43.7671777777778 ;
        lat:data_max = -42.4349888888889 ;
    float depth(time, depth_cell) ;
        depth:missing_value = 1.e+38f ;
        depth:long_name = "Depth" ;
        depth:units = "meter" ;
        depth:C_format = "%8.2f" ;
        depth:positive = "down" ;
        depth:data_min = 13.94f ;
        depth:data_max = 489.98f ;
    float u(time, depth_cell) ;
        u:missing_value = 1.e+38f ;
        u:long_name = "Zonal velocity component" ;
        u:units = "meter second-1" ;
        u:C_format = "%7.2f" ;
        u:data_min = -0.5163827f ;
        u:data_max = 0.4388249f ;
    float v(time, depth_cell) ;
        v:missing_value = 1.e+38f ;
        v:long_name = "Meridional velocity component" ;
        v:units = "meter second-1" ;
        v:C_format = "%7.2f" ;
        v:data_min = -0.7956916f ;
        v:data_max = 0.7306919f ;
    short amp(time, depth_cell) ;
        amp:missing_value = 32767s ;
        amp:long_name = "Received signal strength" ;
        amp:C_format = "%d" ;
        amp:data_min = 24s ;
        amp:data_max = 228s ;
    byte pg(time, depth_cell) ;
        pg:missing_value = -1b ;
        pg:long_name = "Percent good pings" ;
        pg:C_format = "%d" ;
        pg:data_min = 0b ;
        pg:data_max = 100b ;
    byte pflag(time, depth_cell) ;
```

```
pflag:long_name = "Editing flags" ;
pflag:C_format = "%d" ;
pflag:data_min = 0b ;
pflag:data_max = 6b ;
float heading(time) ;
heading:missing_value = 1.e+38f ;
heading:long_name = "Ship heading" ;
heading:units = "degrees" ;
heading:C_format = "%6.1f" ;
heading:data_min = -179.9562f ;
heading:data_max = 179.9447f ;
float tr_temp(time) ;
tr_temp:missing_value = 1.e+38f ;
tr_temp:long_name = "ADCP transducer temperature" ;
tr_temp:units = "Celsius" ;
tr_temp:C_format = "%4.1f" ;
tr_temp:data_min = 15.14496f ;
tr_temp:data_max = 17.08452f ;
short num_pings(time) ;
num_pings:long_name = "Number of pings averaged per ensemble" ;
num_pings:units = "None" ;
num_pings:C_format = "%d" ;
num_pings:data_min = 136s ;
num_pings:data_max = 251s ;
float uship(time) ;
uship:missing_value = 1.e+38f ;
uship:long_name = "Ship zonal velocity component" ;
uship:units = "meter second-1" ;
uship:C_format = "%9.4f" ;
uship:data_min = -5.050357f ;
uship:data_max = 4.425869f ;
float vship(time) ;
vship:missing_value = 1.e+38f ;
vship:long_name = "Ship meridional velocity component" ;
vship:units = "meter second-1" ;
vship:C_format = "%9.4f" ;
vship:data_min = -4.112892f ;
vship:data_max = 4.225998f ;

// global attributes:
:featureType = "trajectoryProfile" ;
:history = "Created: 2022-01-05 22:46:25 UTC" ;
:Conventions = "COARDS" ;
:software = "pycurrents" ;
:hg_changeset = "3159:c22d6c40e594" ;
:title = "Shipboard ADCP velocity profiles" ;
:description = "Shipboard ADCP velocity profiles from in2021_e04 using instrument
os150nb - Short Version." ;
:cruise_id = "in2021_e04" ;
:sonar = "os150nb" ;
:yearbase = 2021 ;
:ship_name = "RV Investigator" ;
:CODAS_variables = "\n",
    "Variables in this CODAS short-form Netcdf file are intended for most end-
user\n",
    "scientific analysis and display purposes. For additional information
see\n",
    "the CODAS_processing_note global attribute and the attributes of each\n",
    "of the variables.\n",
    "\n",
    "\n",
    "=====\n",
    "time          Time at the end of the ensemble, days from start of year.\n",
    "lon, lat      Longitude, Latitude from GPS at the end of the ensemble.\n",
    "u,v           Ocean zonal and meridional velocity component profiles.\n",
    "uship, vship  Zonal and meridional velocity components of the ship.\n",
```

```

"heading      Mean ship heading during the ensemble.\n",
"depth        Bin centers in nominal meters (no sound speed profile
correction).\n",
"tr_temp      ADCP transducer temperature.\n",
"pg           Percent Good pings for u, v averaging after editing.\n",
"pflag        Profile Flags based on editing, used to mask u, v.\n",
"amp          Received signal strength in ADCP-specific units; no
correction\n",
"             for spreading or attenuation.\n",
"=====
=====
\n",
" ";
:CODAS_processing_note = "\n",
"CODAS processing note:\n",
"=====\n",
"\n",
"Overview\n",
"-----\n",
"The CODAS database is a specialized storage format designed for\n",
"shipboard ADCP data. \"CODAS processing\" uses this format to hold\n",
"averaged shipboard ADCP velocities and other variables, during the\n",
"stages of data processing. The CODAS database stores velocity\n",
"profiles relative to the ship as east and north components along with\n",
"position, ship speed, heading, and other variables. The netCDF *short*\n",
"form contains ocean velocities relative to earth, time, position,\n",
"transducer temperature, and ship heading; these are designed to be\n",
"\"ready for immediate use\". The netCDF *long* form is just a dump of\n",
"the entire CODAS database. Some variables are no longer used, and all\n",
"have names derived from their original CODAS names, dating back to the\n",
"late 1980's.\n",
"\n",
"Post-processing\n",
"-----\n",
"CODAS post-processing, i.e. that which occurs after the single-ping\n",
"profiles have been vector-averaged and loaded into the CODAS database,\n",
"includes editing (using automated algorithms and manual tools),\n",
"rotation and scaling of the measured velocities, and application of a\n",
"time-varying heading correction. Additional algorithms developed more\n",
"recently include translation of the GPS positions to the transducer\n",
"location, and averaging of ship's speed over the times of valid pings\n",
"when Percent Good is reduced. Such post-processing is needed prior to\n",
"submission of \"processed ADCP data\" to JASADCP or other archives.\n",
"\n",
"Full CODAS processing\n",
"-----\n",
"Whenever single-ping data have been recorded, full CODAS processing\n",
"provides the best end product.\n",
"\n",
"Full CODAS processing starts with the single-ping velocities in beam\n",
"coordinates. Based on the transducer orientation relative to the\n",
"hull, the beam velocities are transformed to horizontal, vertical, and\n",
"\"error velocity\" components. Using a reliable heading (typically
from\n",
"the ship's gyro compass), the velocities in ship coordinates are\n",
"rotated into earth coordinates.\n",
"\n",
"Pings are grouped into an \"ensemble\" (usually 2-5 minutes duration)\n",
"and undergo a suite of automated editing algorithms (removal of\n",
"acoustic interference; identification of the bottom; editing based on\n",
"thresholds; and specialized editing that targets CTD wire interference\n",
"and \"weak, biased profiles\". The ensemble of single-ping velocities\n",
"is then averaged using an iterative reference layer averaging scheme.\n",
"Each ensemble is approximated as a single function of depth, with a\n",
"zero-average over a reference layer plus a reference layer velocity\n",
"for each ping. Adding the average of the single-ping reference layer\n",
"velocities to the function of depth yields the ensemble-average\n",

```

```
"velocity profile. These averaged profiles, along with ancillary\n",
"measurements, are written to disk, and subsequently loaded into the\n",
"CODAS database. Everything after this stage is \"post-processing\".\n",
"\n",
"note (time):\n",
"-----\n",
"Time is stored in the database using UTC Year, Month, Day, Hour,\n",
"Minute, Seconds. Floating point time \"Decimal Day\" is the floating\n",
"point interval in days since the start of the year, usually the year\n",
"of the first day of the cruise.\n",
"\n",
"\n",
"note (heading):\n",
"-----\n",
"CODAS processing uses heading from a reliable device, and (if\n",
"available) uses a time-dependent correction by an accurate heading\n",
"device. The reliable heading device is typically a gyro compass (for\n",
"example, the Bridge gyro). Accurate heading devices can be POSMV,\n",
"Seapath, Phins, Hydrins, MAHRS, or various Ashtech devices; this\n",
"varies with the technology of the time. It is always confusing to\n",
"keep track of the sign of the heading correction. Headings are written\n",
"degrees, positive clockwise. setting up some variables:\n",
"\n",
"\n",
"X = transducer angle (CONFIG1_heading_bias)\n",
"    positive clockwise (beam 3 angle relative to ship)\n",
"G = Reliable heading (gyrocompass)\n",
"A = Accurate heading\n",
"dh = G - A = time-dependent heading correction
(ANCIL2_watrk_hd_misalign)\n",
"\n",
"Rotation of the measured velocities into the correct coordinate system\n",
"amounts to (u+i*v)*(exp(i*theta)) where theta is the sum of the\n",
"corrected heading and the transducer angle.\n",
"\n",
"theta = X + (G - dh) = X + G - dh\n",
"\n",
"\n",
"Watertrack and Bottomtrack calibrations give an indication of the\n",
"residual angle offset to apply, for example if mean and median of the\n",
"phase are all 0.5 (then R=0.5). Using the \"rotate\" command,\n",
"the value of R is added to \"ANCIL2_watrk_hd_misalign\".\n",
"\n",
"new_dh = dh + R\n",
"\n",
"Therefore the total angle used in rotation is\n",
"\n",
"new_theta = X + G - dh_new\n",
"           = X + G - (dh + R)\n",
"           = (X - R) + (G - dh)\n",
"\n",
"The new estimate of the transducer angle is: X - R\n",
"ANCIL2_watrk_hd_misalign contains: dh + R\n",
"\n",
"=====\n",
"\n",
"Profile flags\n",
"-----\n",
"Profile editing flags are provided for each depth cell:\n",
"\n",
"binary    decimal    below    Percent\n",
"value     value     bottom   Good      bin\n",
"-----+-----+-----+-----+-----+\n",
"000        0\n",
"001        1                                bad\n",
"010        2                                bad\n",
"011        3                                bad    bad\n",
"100        4                bad\n",
```

```
"101      5      bad      bad\n",  
"110      6      bad      bad\n",  
"111      7      bad      bad      bad\n",  
"-----+-----+-----+-----+\n",  
" " ;
```

}

5.5 os75 narrow band

```
netcdf in2021_e04_os75nb {
dimensions:
    time = 888 ;
    depth_cell = 60 ;
variables:
    int trajectory ;
        trajectory:standard_name = "trajectory_id" ;
    double time(time) ;
        time:long_name = "Decimal day" ;
        time:units = "days since 2021-01-01 00:00:00" ;
        time:C_format = "%12.5f" ;
        time:standard_name = "time" ;
        time:data_min = 349.451585648148 ;
        time:data_max = 352.531458333333 ;
    double lon(time) ;
        lon:missing_value = 1.e+38 ;
        lon:long_name = "Longitude" ;
        lon:units = "degrees_east" ;
        lon:C_format = "%9.4f" ;
        lon:standard_name = "longitude" ;
        lon:data_min = 147.905691666667 ;
        lon:data_max = 149.887461111111 ;
    double lat(time) ;
        lat:missing_value = 1.e+38 ;
        lat:long_name = "Latitude" ;
        lat:units = "degrees_north" ;
        lat:C_format = "%9.4f" ;
        lat:standard_name = "latitude" ;
        lat:data_min = -43.767177777778 ;
        lat:data_max = -42.434955555556 ;
    float depth(time, depth_cell) ;
        depth:missing_value = 1.e+38f ;
        depth:long_name = "Depth" ;
        depth:units = "meter" ;
        depth:C_format = "%8.2f" ;
        depth:positive = "down" ;
        depth:data_min = 29.99f ;
        depth:data_max = 973.99f ;
    float u(time, depth_cell) ;
        u:missing_value = 1.e+38f ;
        u:long_name = "Zonal velocity component" ;
        u:units = "meter second-1" ;
        u:C_format = "%7.2f" ;
        u:data_min = -0.5378518f ;
        u:data_max = 0.4278482f ;
    float v(time, depth_cell) ;
        v:missing_value = 1.e+38f ;
        v:long_name = "Meridional velocity component" ;
        v:units = "meter second-1" ;
        v:C_format = "%7.2f" ;
        v:data_min = -0.8212254f ;
        v:data_max = 0.7510877f ;
    short amp(time, depth_cell) ;
        amp:missing_value = 32767s ;
        amp:long_name = "Received signal strength" ;
        amp:C_format = "%d" ;
```

```
    amp:data_min = 16s ;
    amp:data_max = 203s ;
byte pg(time, depth_cell) ;
    pg:missing_value = -1b ;
    pg:long_name = "Percent good pings" ;
    pg:C_format = "%d" ;
    pg:data_min = 0b ;
    pg:data_max = 100b ;
byte pflag(time, depth_cell) ;
    pflag:long_name = "Editing flags" ;
    pflag:C_format = "%d" ;
    pflag:data_min = 0b ;
    pflag:data_max = 6b ;
float heading(time) ;
    heading:missing_value = 1.e+38f ;
    heading:long_name = "Ship heading" ;
    heading:units = "degrees" ;
    heading:C_format = "%6.1f" ;
    heading:data_min = -179.9617f ;
    heading:data_max = 179.9645f ;
float tr_temp(time) ;
    tr_temp:missing_value = 1.e+38f ;
    tr_temp:long_name = "ADCP transducer temperature" ;
    tr_temp:units = "Celsius" ;
    tr_temp:C_format = "%4.1f" ;
    tr_temp:data_min = 15.2703f ;
    tr_temp:data_max = 17.2603f ;
short num_pings(time) ;
    num_pings:long_name = "Number of pings averaged per ensemble" ;
    num_pings:units = "None" ;
    num_pings:C_format = "%d" ;
    num_pings:data_min = 132s ;
    num_pings:data_max = 133s ;
float uship(time) ;
    uship:missing_value = 1.e+38f ;
    uship:long_name = "Ship zonal velocity component" ;
    uship:units = "meter second-1" ;
    uship:C_format = "%9.4f" ;
    uship:data_min = -5.046744f ;
    uship:data_max = 4.429965f ;
float vship(time) ;
    vship:missing_value = 1.e+38f ;
    vship:long_name = "Ship meridional velocity component" ;
    vship:units = "meter second-1" ;
    vship:C_format = "%9.4f" ;
    vship:data_min = -4.11907f ;
    vship:data_max = 4.228105f ;

// global attributes:
:featureType = "trajectoryProfile" ;
:history = "Created: 2022-01-05 22:46:44 UTC" ;
:Conventions = "COARDS" ;
:software = "pycurrents" ;
:hg_changeset = "3159:c22d6c40e594" ;
:title = "Shipboard ADCP velocity profiles" ;
:description = "Shipboard ADCP velocity profiles from in2021_e04 using instrument os75nb - Short Version." ;
```



```
:cruise_id = "in2021_e04" ;
:sonar = "os75nb" ;
:yearbase = 2021 ;
:ship_name = "RV Investigator" ;
:CODAS_variables = "\n",
    "Variables in this CODAS short-form Netcdf file are intended for most end-user\n",
    "scientific analysis and display purposes. For additional information see\n",
    "the CODAS_processing_note global attribute and the attributes of each\n",
    "of the variables.\n",
    "\n",
    "\n",
    "=====\n",
    "time      Time at the end of the ensemble, days from start of year.\n",
    "lon, lat  Longitude, Latitude from GPS at the end of the ensemble.\n",
    "u,v      Ocean zonal and meridional velocity component profiles.\n",
    "uship, vship  Zonal and meridional velocity components of the ship.\n",
    "heading   Mean ship heading during the ensemble.\n",
    "depth     Bin centers in nominal meters (no sound speed profile correction).\n",
    "tr_temp   ADCP transducer temperature.\n",
    "pg       Percent Good pings for u, v averaging after editing.\n",
    "pflag    Profile Flags based on editing, used to mask u, v.\n",
    "amp      Received signal strength in ADCP-specific units; no correction\n",
    "          for spreading or attenuation.\n",
    "=====\n",
    "\n",
    "" ;
:CODAS_processing_note = "\n",
    "CODAS processing note:\n",
    "=====\n",
    "\n",
    "Overview\n",
    "-----\n",
    "The CODAS database is a specialized storage format designed for\n",
    "shipboard ADCP data. \"CODAS processing\" uses this format to hold\n",
    "averaged shipboard ADCP velocities and other variables, during the\n",
    "stages of data processing. The CODAS database stores velocity\n",
    "profiles relative to the ship as east and north components along with\n",
    "position, ship speed, heading, and other variables. The netCDF *short*\n",
    "form contains ocean velocities relative to earth, time, position,\n",
    "transducer temperature, and ship heading; these are designed to be\n",
    "\"ready for immediate use\". The netCDF *long* form is just a dump of\n",
    "the entire CODAS database. Some variables are no longer used, and all\n",
    "have names derived from their original CODAS names, dating back to the\n",
    "late 1980's.\n",
    "\n",
    "Post-processing\n",
    "-----\n",
    "CODAS post-processing, i.e. that which occurs after the single-ping\n",
    "profiles have been vector-averaged and loaded into the CODAS database,\n",
    "includes editing (using automated algorithms and manual tools),\n",
    "rotation and scaling of the measured velocities, and application of a\n",
    "time-varying heading correction. Additional algorithms developed more\n",
    "recently include translation of the GPS positions to the transducer\n",
    "location, and averaging of ship's speed over the times of valid pings\n",
    "when Percent Good is reduced. Such post-processing is needed prior to\n",
    "submission of \"processed ADCP data\" to JASADCP or other archives.
```

"\n",
"Full CODAS processing\n",
"-----\n",
"Whenever single-ping data have been recorded, full CODAS processing\n",
"provides the best end product.\n",
"\n",
"Full CODAS processing starts with the single-ping velocities in beam\n",
"coordinates. Based on the transducer orientation relative to the\n",
"hull, the beam velocities are transformed to horizontal, vertical, and\n",
"error velocity components. Using a reliable heading (typically from\n",
"the ship's gyro compass), the velocities in ship coordinates are\n",
"rotated into earth coordinates.\n",
"\n",
"Pings are grouped into an ensemble (usually 2-5 minutes duration)\n",
"and undergo a suite of automated editing algorithms (removal of\n",
"acoustic interference; identification of the bottom; editing based on\n",
"thresholds; and specialized editing that targets CTD wire interference\n",
"and weak, biased profiles). The ensemble of single-ping velocities\n",
"is then averaged using an iterative reference layer averaging scheme.\n",
"Each ensemble is approximated as a single function of depth, with a\n",
"zero-average over a reference layer plus a reference layer velocity\n",
"for each ping. Adding the average of the single-ping reference layer\n",
"velocities to the function of depth yields the ensemble-average\n",
"velocity profile. These averaged profiles, along with ancillary\n",
"measurements, are written to disk, and subsequently loaded into the\n",
"CODAS database. Everything after this stage is post-processing.\n",
"\n",
"note (time):\n",
"-----\n",
"Time is stored in the database using UTC Year, Month, Day, Hour,\n",
"Minute, Seconds. Floating point time Decimal Day is the floating\n",
"point interval in days since the start of the year, usually the year\n",
"of the first day of the cruise.\n",
"\n",
"\n",
"note (heading):\n",
"-----\n",
"CODAS processing uses heading from a reliable device, and (if\n",
"available) uses a time-dependent correction by an accurate heading\n",
"device. The reliable heading device is typically a gyro compass (for\n",
"example, the Bridge gyro). Accurate heading devices can be POSMV,\n",
"Seapath, Phins, Hydrins, MAHRS, or various Ashtech devices; this\n",
"varies with the technology of the time. It is always confusing to\n",
"keep track of the sign of the heading correction. Headings are written\n",
"degrees, positive clockwise. setting up some variables:\n",
"\n",
"X = transducer angle (CONFIG1_heading_bias)\n",
" positive clockwise (beam 3 angle relative to ship)\n",
"G = Reliable heading (gyrocompass)\n",
"A = Accurate heading\n",
"dh = G - A = time-dependent heading correction (ANCIL2_watrk_hd_misalign)\n",
"\n",
"Rotation of the measured velocities into the correct coordinate system\n",
"amounts to $(u+i*v)*(exp(i*theta))$ where theta is the sum of the\n",
"corrected heading and the transducer angle.\n",
"\n",

```

"theta = X + (G - dh) = X + G - dh\n",
"\n",
"\n",
"Watertrack and Bottomtrack calibrations give an indication of the\n",
"residual angle offset to apply, for example if mean and median of the\n",
"phase are all 0.5 (then R=0.5). Using the \"rotate\" command,\n",
"the value of R is added to \"ANCIL2_watr_k_hd_misalign\".\n",
"\n",
"new_dh = dh + R\n",
"\n",
"Therefore the total angle used in rotation is\n",
"\n",
"new_theta = X + G - dh_new\n",
"      = X + G - (dh + R)\n",
"      = (X - R) + (G - dh)\n",
"\n",
"The new estimate of the transducer angle is: X - R\n",
"ANCIL2_watr_k_hd_misalign contains: dh + R\n",
"\n",
"=====\n",
"\n",
"Profile flags\n",
"-----\n",
"Profile editing flags are provided for each depth cell:\n",
"\n",
"binary  decimal  below  Percent\n",
"value  value  bottom  Good  bin\n",
"-----+-----+-----+-----+\n",
"000    0\n",
"001    1          bad\n",
"010    2          bad\n",
"011    3          bad  bad\n",
"100    4  bad\n",
"101    5  bad          bad\n",
"110    6  bad  bad\n",
"111    7  bad  bad  bad\n",
"-----+-----+-----+-----+\n",
"";

```

}