



B-12 Guidance on Crowdsourced Bathymetry

Chapter 2: Collecting Data

Discussion Topics



IHO

Previous edits (globally described, as agreed per CSBWG11)

International
Hydrographic
Organization

- (1) Focusing on echosounders in broad terms
- (2) Maintaining sufficient details (e.g. on optional inertial systems) without frightening the user about complexity
- (3) Focus on data collection – not on onboard data management (any details concerning loggers have been removed) and not on data transmission (role of Trusted Nodes are meant to be covered elsewhere in the document)



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Discussion Topic #1: Sensor offset – where to detail infos

From: 2.3 Relative location of the sensors

Original Text: If this offset is not automatically integrated, mariners should record their sensor offsets, plus the vertical measurement between the transducer and the waterline, and relay that information to their Trusted Node. .

Replaced With: If this offset is not automatically integrated, **most likely through the configuration options of the echosounder software**, mariners should record their sensor offsets, plus the vertical measurement between the transducer and the waterline, and relay that information to their Trusted Node.

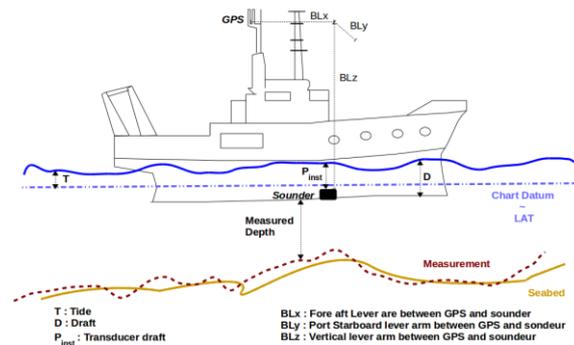
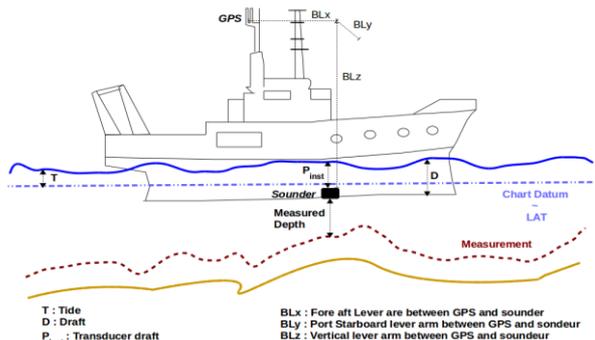
Decisions/Next Steps

- Consensus



From: 2.3 Relative location of the sensor within the acquisition platform frame

Following figures to be added (originating from the uncertainty section) to describe more explicitly the consequences of poor relative measurements of the sensors



Decisions/Next Steps

- Consensus
- Harmonisation of the Figure numbering



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Discussion Topic #3: Generalization of sensor offsets concept to more complex systems (i.e. Multibeam)

From: 2. Data Collection

Context: Concluding notes of the chapter with the intention to generalize to multibeam system

Proposed text: Note that when using a multibeam echosounder all the above elements remain to be considered. An extra complexity is added because of the angular offsets between the respective reference frames of the sounder, the inertial motion unit and the boat. The calibration of the different angles composing this integrated system can be done through the so-called “patch test calibration” process, which is beyond the scope of this document.

Decisions/Next Steps

- Consensus