

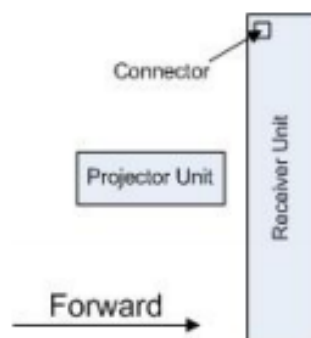
Reson 7125

SEABAT 7125 OPERATOR'S MANUAL

https://wiki.oceannetworks.ca/download/attachments/23756860/SeaBat_7125_Operator_Manual_300.pdf?api=v2

4.03.06 SeaBat 7125 Transducer Orientation

The Sonar Head Assembly should be mounted with the faces of the arrays oriented vertically downwards. In the ideal configuration, the Receive Array will be mounted across-track, while the Transmit Array will be mounted along track and aft of the Receive Array.



If necessary, the projector may be oriented forward or the head rotated away from vertical, however allowances must be made in the processor setup. In addition, an alternate mounting makes the head more susceptible to impact damage and collection of trailing debris.

The Receiver Unit and Projector Unit(s) should be within ± 250 mm of each other in all three planes. The Projector Unit should be aligned perpendicular to the Receiver Unit (within $\pm 0.5^\circ$).

NOTE: Refer to the 7k Data Format Definition for information regarding the records you require.



2.3 Vessel Axes

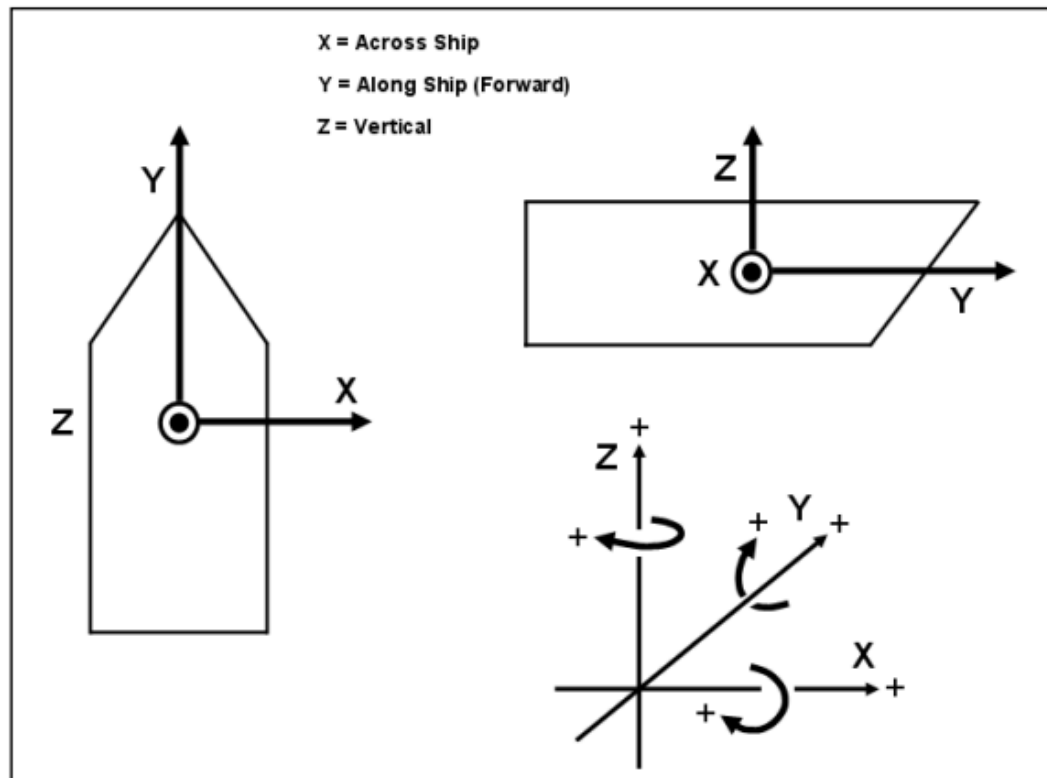


Figure 2-1: Vessel Axes

2.4 Sonar Reference Point

The following axis convention is applied for the sonar reference point convention:

X = across ship, points to starboard

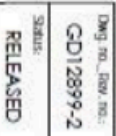
Y = along ship points forward

Z = vertical, points up.

The sonar reference point is in the center of the receiver face in both X and Z directions and in the center of the projector in the Y direction.

The Tx offset is defined as the separation of the projector (Tx) reference point from the Receiver (Rx) point.

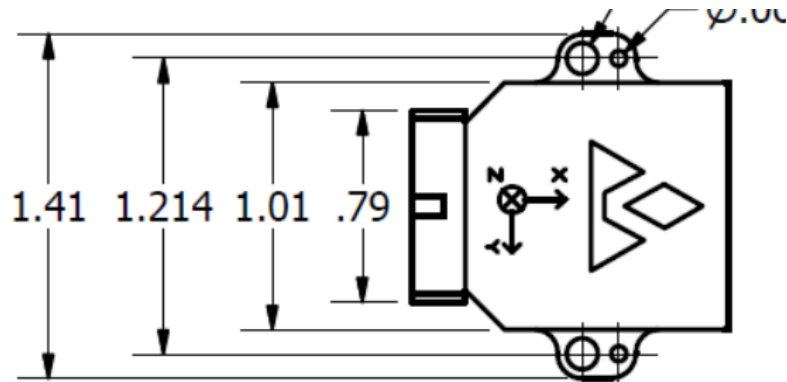
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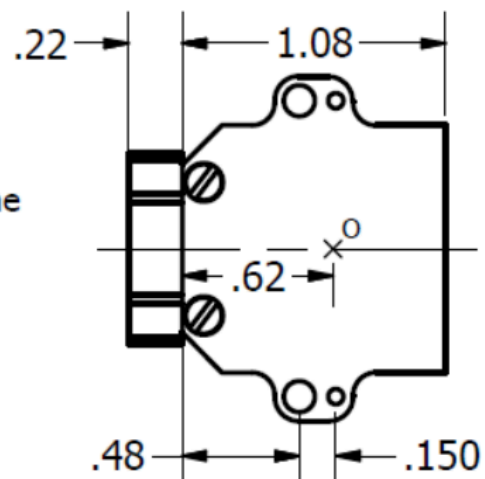
VN-100

<https://www.vectornav.com/products/vn-100/documentation>

[https://www.vectornav.com/docs/default-source/documentation/vn-100-documentation/vn-100-user-manual-\(um001\).pdf?sfvrsn=b49fe6b9_32](https://www.vectornav.com/docs/default-source/documentation/vn-100-documentation/vn-100-user-manual-(um001).pdf?sfvrsn=b49fe6b9_32)



Note: Origin O for the sensor's coordinate system is located on the bottom face.

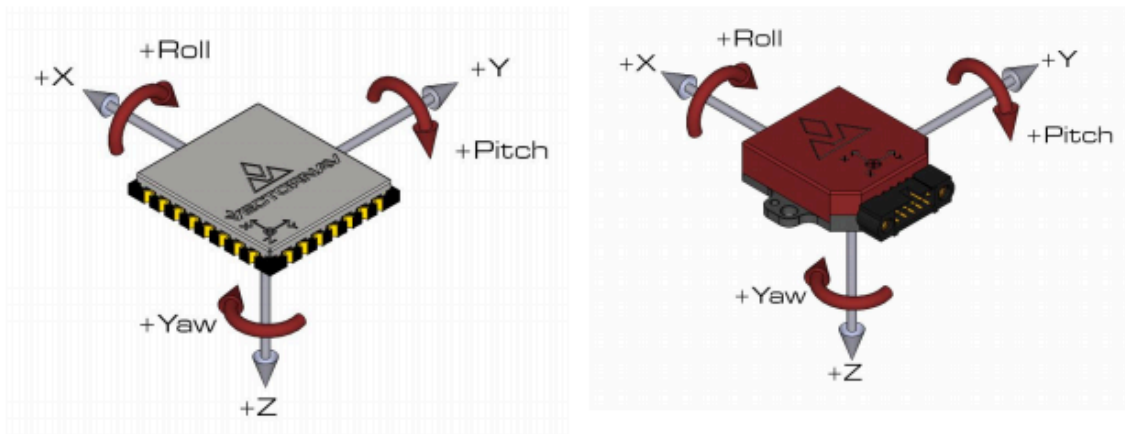


2.6 Sensor Coordinate System

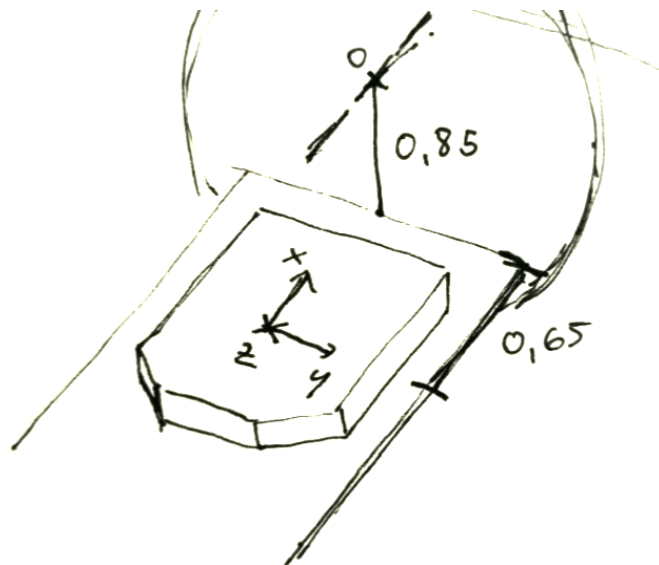
2.6.1 Sensor Coordinate Frame

The VN-100 uses a right-handed coordinate system. A positive yaw angle is defined as a positive right-handed rotation around the Z-axis. A positive pitch angle is defined as a positive right-handed rotation around the Y-axis. A positive roll angle is defined as a positive right-handed rotation around the X-axis. The axes direction with respect to the VN-100 module is shown in the figure below.

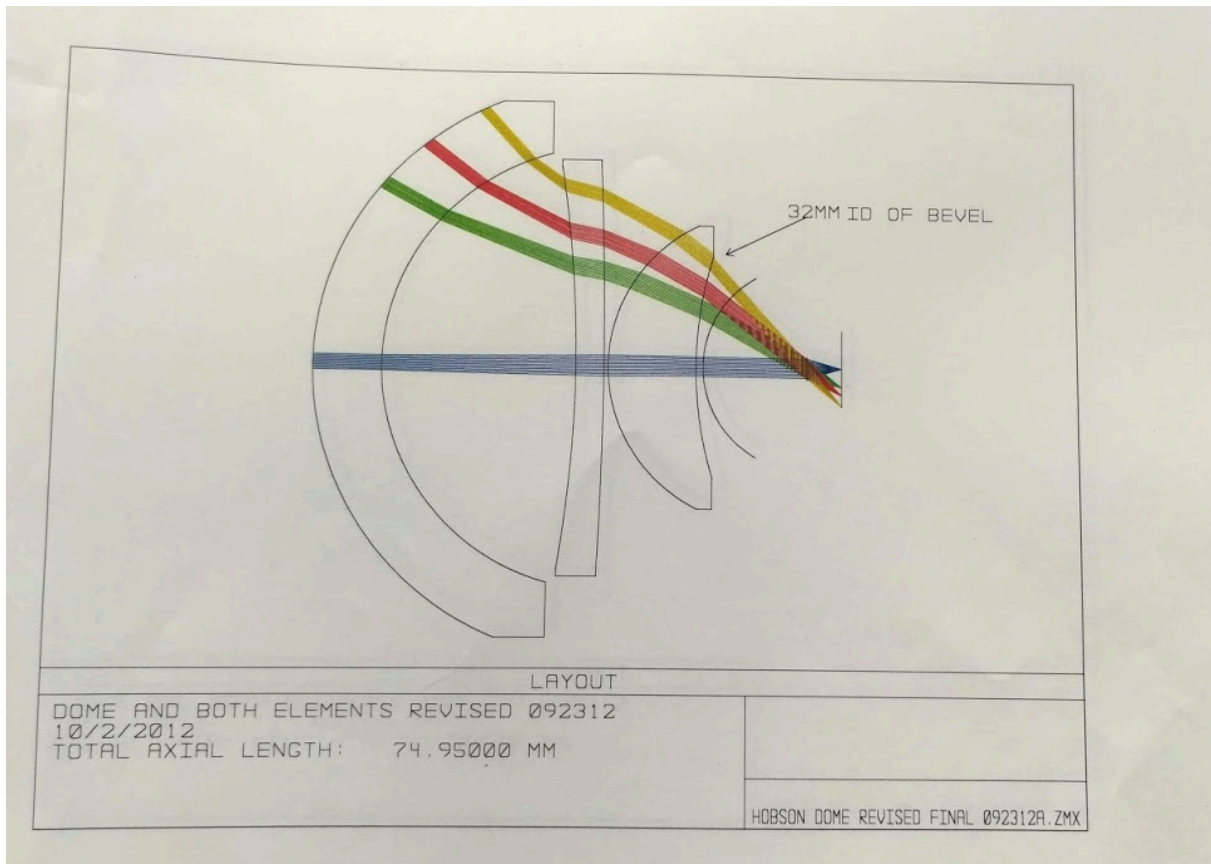
VN-100 Coordinate System



Referred to the cap of can:



Cameras:



Distance between the glass sphere and the image plan: 74.95 mm (2.9508 inch). Center on axis of cylinder.

CTD: SBE 49

<https://www.seabird.com/moving-platform/sbe-49-fastcat-ctd-sensor/family?productCategoryId=54627473793>

Benjamin Crossen techsupport@seabird.com a través de uc.cl

para jgmartin@uc.cl ▾

🌐 inglés ▾ > español ▾ [Traducir mensaje](#)

Good Morning,

The Pressure sensor on the 49 is located by the bulkhead connector. It resembles a flat head screw. It should be plastic and white in color.

Best Regards,

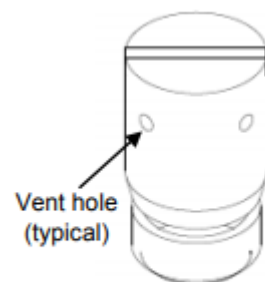
Ben

ref:_00D7096pT._5000g26NF7m:ref

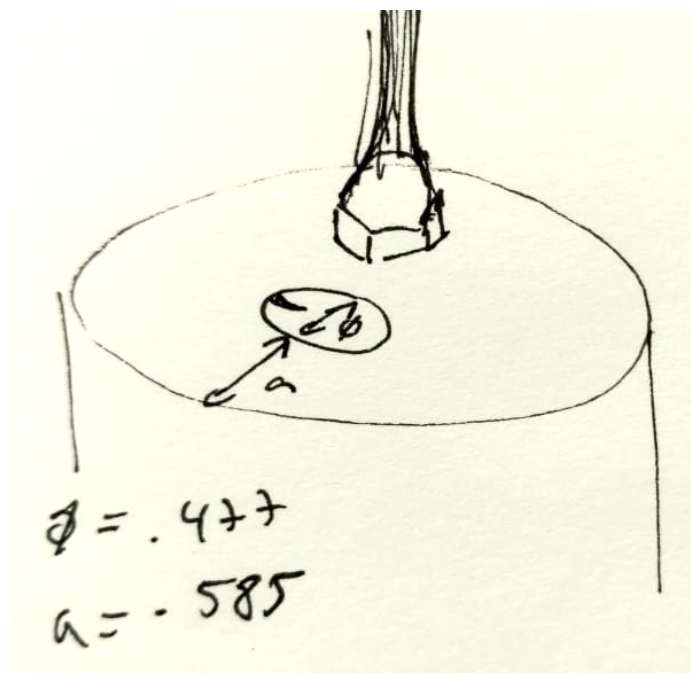
>> Reference point is in the face.



Standard pressure sensor port plug.
(Note: Photo is SBE 37-SM. Pressure port details are similar for all instruments included in this application note)



High-Head
Pressure Port Plug,
Part Number 233186



this may be important:



Paroscientific

http://paroscientific.com/pdf/8819-001_Digiquartz_Operations_Manual_for_RS_485_RS_232_Products_715_Display.pdf

