

WinFrog Device Group:	GENERIC																				
Device Name/Model:	GENERIC																				
Device Manufacturer:																					
Device Data String(s) Output to WinFrog:	User Configurable, see Telegram Specification section below.																				
WinFrog Data String(s) Output to Device:	N/A																				
WinFrog Data Item(s) and their RAW record:	Data Items and RAW records are dependant on the User configuration of this device. Some of the available data items include; <table> <tr><td>POSITION</td><td>303</td></tr> <tr><td>HEADING</td><td>910</td></tr> <tr><td>VELOCITY</td><td>900</td></tr> <tr><td>ELEVATION</td><td>372</td></tr> <tr><td>ATTITUDE</td><td>413</td></tr> <tr><td>ROVDATA</td><td>496-003-W</td></tr> <tr><td>MAGNETOMETER</td><td>800-001</td></tr> <tr><td>COUNT</td><td>492-001</td></tr> <tr><td>BOTTOMDEPTH</td><td>411</td></tr> <tr><td>WIND</td><td>373</td></tr> </table>	POSITION	303	HEADING	910	VELOCITY	900	ELEVATION	372	ATTITUDE	413	ROVDATA	496-003-W	MAGNETOMETER	800-001	COUNT	492-001	BOTTOMDEPTH	411	WIND	373
POSITION	303																				
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ATTITUDE	413																				
ROVDATA	496-003-W																				
MAGNETOMETER	800-001																				
COUNT	492-001																				
BOTTOMDEPTH	411																				
WIND	373																				

DEVICE DESCRIPTION:

The Generic device is a driver written to give WinFrog flexibility for data input. This device is especially useful for interfacing peripheral devices with known output parameters that do not have device drivers written specifically for them. You can configure the input string and related data items as required. The configuration, along with serial communication settings, can be saved and loaded to and from files for easy setup and transfer of repeated settings.

DEVICE CONFIGURATION INSTRUCTIONS

WINFROG I/O DEVICES > EDIT I/O:

Serial

Configurable Parameters

A dialog appears in which to change the name of the device if desired.

WINFROG I/O DEVICES > CONFIGURE DEVICE:

This device must be configured at the I/O Device window level. In the I/O Devices window, click the device name to select it, then right-click and select Configure Device. The Config Generic Input String dialog box appears, as seen below.

Config Generic Input String

Input Data Types (max 30)

- Dummy
- POS - Latitude
- POS - Longitude
- NAV - Heading
- ROV - Water Depth From ROV
- NAV - Speed**

Available Items

- MAGNETOMETER - Field
- MAGNETOMETER - Signal
- MAGNETOMETER - Depth
- MAGNETOMETER - Altitude
- MAGNETOMETER - Tuning
- MAGNETOMETER - Voltage
- NAV - Tides**
- NAV - Water Depth
- NAV - Wind Speed
- NAV - Wind Direction
- POS - Northing
- POS - Easting
- ROV - Heading

☒ Edit Mode (Advanced)

Header Data

☐ Header Used (max 8 chars)

Checksum

☒ No/Ignore CheckSum
☐ Use CheckSum

Control Characters

☐ LineFeed
☒ Carriage Return
☐ Use start/stop control characters

Delimiter

☒ Comma ☐ Tab
☐ Space
☐ Fixed

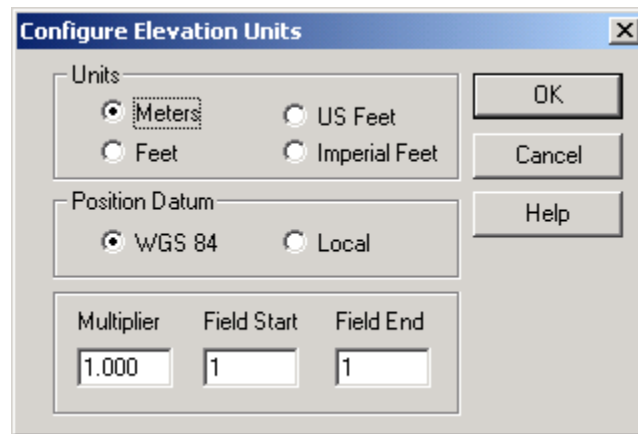
Note

If there is only one data field, select either comma or space in the delimiter group box. Use header as required.

Load/Save Settings

The default mode disables any configuration options. All options are grayed out and cannot be accessed. To configure an input string you must first enable the Edit Mode (Advanced) option. Once this option is enabled you can access the available configurations from the Available Items list on the right. Typically the desired input data string is already known or can be determined from HyperTerminal. You can also configure other data string parameters such as the Header Data, Checksum, Control characters and Delimiters by selecting the appropriate options. Refer to the Telegram Specification section at the end of this document for a list of the data types supported by this device.

Many of the Available Items also have configuration options available for units, datums, multipliers, field start, field end and so on, depending on the data type chosen. These configuration option dialog boxes open automatically when the Available Items are selected to be included in the Input Data Type(s). For example when the Tides Item is selected to be moved from the Available Items to the Input Data Types the following dialog box appears.



The desired configuration options must be known (i.e., the units, etc., contained in the desired data string) before these devices can be properly configured.

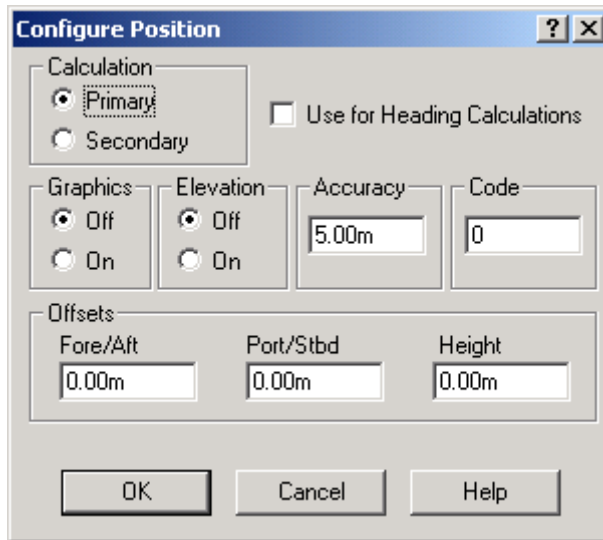
By selecting Save Settings on the Config Generic Input String dialog box, you can save the configuration to an *.icf file. This file can then be loaded at a later date either on this WinFrog installation, or any other. This feature can save time when a similar configuration has to be repeated on many different setups.

WINFROG VEHICLE > CONFIGURE VEHICLE DEVICES > DEVICE DATA ITEM > EDIT:

Adding the GENERIC device creates the NONE data item. This data item itself has no function. However, by configuring the input string as discussed above, standard data items are created that can be added to the vehicles in WinFrog.

Data item: GENERIC, GENERIC, POSITION

The Position data item must be edited once it is added to a vehicle's device list. Highlight the POSITION data item in the vehicle's device list and click the Edit button. The Configure Position dialog box appears as seen below.



Calculation:

Set the Calculation selection to Primary or Secondary. Devices set to Primary calculation are used to provide a vessel position. Note that more than one Primary positioning device can be added to a vehicle's device list; data from these devices will be combined in a weighted mean solution. (See the paragraph on Accuracy below for more on the weighting of Primary calculation device data).

If the Calculation type is set to Secondary, WinFrog will simply monitor the device's data. WinFrog will not use the position data from the device in the final solution of the vehicles' position.

Note: In the case of Primary device failure, WinFrog will not automatically use the Secondary devices for the vessel's position computation. Instead, the vehicle's positioning will go to dead reckoning (if dead reckoning is turned on). You must manually change a Secondary device to Primary in order for the data to be utilized.

Use For Heading Calculations:

Select this checkbox if the device is to be used in conjunction with another GPS device for determination of the heading of the vessel. The vessel's heading will be derived by the inverse of the GPS antenna coordinates.

Graphics:

If On is selected, a labeled square will show the raw (offset but unfiltered) location of the GPS antenna in the Graphics and Bird's Eye windows. This provides a means of comparing raw device and filtered vehicle positions.

Elevation:

Setting the Elevation option to On will result in the elevation determined by GPS to be used as the elevation of the vessel referencing the GPS (WGS84) Ellipsoid. The sounder data recorded in WinFrog's .RAW data files will not be affected.

This option is meant only for those applications where there is no fixed vertical reference (i.e., mean sea level), such as on a river. For acceptable results, this option requires the use of high accuracy “RTK” GPS data.

Accuracy:

The Accuracy value entered provides WinFrog with the expected accuracy of the position from this device. This value is used in the weighting of this device compared to other positioning devices that may be added to the vehicle’s device list. The smaller the value entered, the more accurate it is considered to be, and hence the more weight that will be applied to the device’s data. The Accuracy parameter can be changed from the suggested values; changes should be made with caution, however, as they will affect the final filtered position of the vehicle.

Code:

This field is used when the GPS data is being received by a remote GPS receiver connected via telemetry link. If this is the case, set the Code to coincide with the code parameters associated with the GPS unit being used. For all other applications, the Code entry must be set to 0.

Offsets:

Offsets are required to associate the GPS antenna position with the vessel’s Common Reference Point (CRP). The offsets are applied *from* CRP (of the vehicle) *to* the GPS antenna location.

Forward Offsets are entered as positive values.

Aft Offsets are entered as negative values.

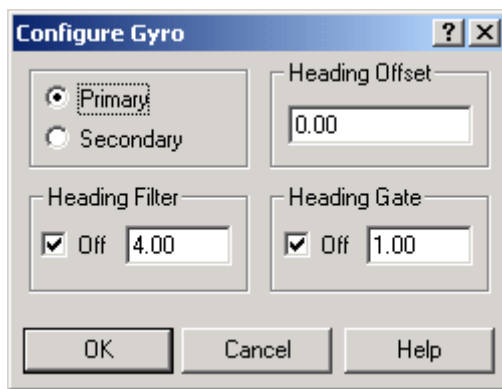
Starboard Offsets are entered as positive values.

Port Offsets are entered as negative values.

Height Offsets are positive upwards. (It is suggested that the vessel’s Height origin should be at the water line.)

Data item: **GENERIC, GENERIC, HEADING**

The Heading data item must also be edited once it is added to a vehicle's device list. Highlight the HEADING data item in the vehicle's device list and click the Edit button. The Configure Gyro dialog box appears as seen below.



Calculation (Primary/Secondary):

Set the type of calculation to Primary or Secondary by selecting the appropriate radio button. Devices set to Primary are used to provide the vehicle with heading information. However, unlike the Position data items, WinFrog does not calculate a weighted mean solution for multiple Heading data items. If more than one Heading data item is set to primary, the vessels heading, in WinFrog, will jump back and forth between the two. Devices set to Secondary are simply monitored, and are not used in the vehicle's calculations.

In the case of Primary device failure, WinFrog will not automatically use the Secondary device(s). You must manually change a Secondary device to Primary status in order for it to be used in the vehicle's calculations.

Heading Offset:

A correction value (as determined from a gyro calibration) can be input in the Heading Offset box. This value is added to the heading value from the Device to provide a corrected heading for the vehicle. Note that positive or negative values can be entered.

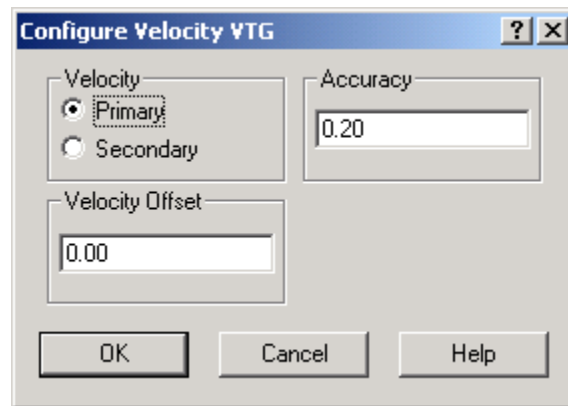
Heading Filter/Heading Gate:

The Heading Filter is used to "smooth" heading values used by the vehicle. The value entered in the Heading Filter indicates the number of headings that will be used to predict the next heading value. The larger the value entered, the "heavier" the filter will be - i.e. the slower the vehicle's heading will respond to changes.

The Heading Gate defines a tolerance value to limit the use of anomalies in gyro readings. If the next observed gyro value received falls outside the specified range of predicted values (i.e. plus or minus the entered value), the value will not be used.

Data item: GENERIC, GENERIC, VELOCITY

The Velocity data item may also be edited once it is added to a vehicle's device list. Highlight the Velocity data item in the vehicle's device list and click the Edit button. The Configure Velocity VTG dialog box appears as seen below.

The image shows a Windows-style dialog box titled "Configure Velocity VTG". It has a standard title bar with a question mark icon and a close button (X). The dialog contains three main input areas: 1. "Velocity": A group box containing two radio buttons, "Primary" (which is selected) and "Secondary". 2. "Accuracy": A text input field containing the value "0.20". 3. "Velocity Offset": A text input field containing the value "0.00". At the bottom of the dialog are three buttons: "OK", "Cancel", and "Help".

Velocity

You can select Primary if this Velocity device is to be used to calculate the vessel's velocity. The default setting is Secondary.

Accuracy

The Accuracy dialog box is where you can specify the expected accuracy, expressed in m/s, of the velocity component from this device.

Velocity Offset

The Velocity Offset is entered in m/s and is added to the velocity input from the Device.

Data item: **GENERIC, GENERIC, ELEVATION**

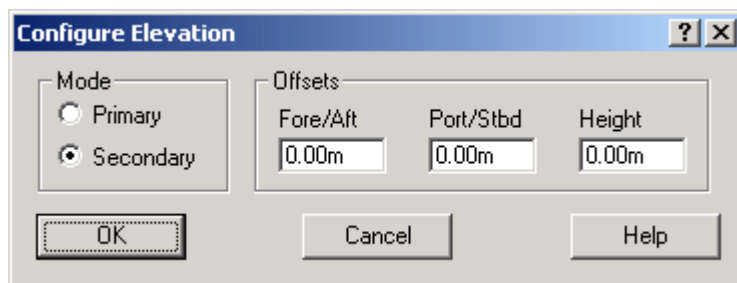
The elevation device does not provide an absolute elevation. If there is data being received from the elevation device, a flag is passed to the assigned vehicle. This flag is checked and will prevent the use of the data for vehicle elevation. It also prevents you from setting the data item to *Primary*. The elevation device is used as a data source for barometric relative heighting, and this is performed at the device level. The device therefore does not need to be added to a vehicle.

The **only** reason for adding the elevation data item to a vehicle is the resulting logging of the data to the raw file as a 372 record. The format for this record is as follows:

372, name, time, elevation, status, center elevation, raw data, temperature, relative humidity *where*:

- 372 is the raw data record identifier for an ELEVATION data type
- *name* is the operator assigned device name
- *time* is the computer time for the data
- *elevation* is the elevation in meters, which in some cases is always 0
- *status* is the status flag for the data, 1 = OK, 0 = Bad
- *center elevation* is the elevation reduced to the CRP, which in some cases is always 0
- *raw data* is the raw elevation data
- *temperature* is the temperature in Celsius
- *relative humidity* is the relative humidity in units of 0-1.0 (i.e. % * 100)

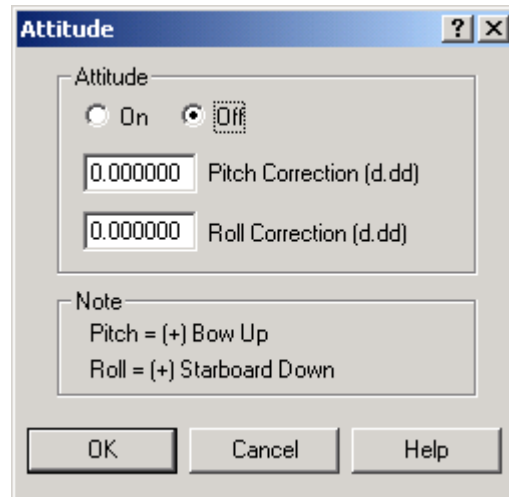
If the device is added to a vehicle, the following configuration dialog is available by highlighting the Elevation data item in the vehicle's device list and clicking Edit. The dialog box appears as seen below.



As mentioned previously, the Mode can only be set to Secondary (unless no data is being received). Sensor offsets can be applied for the unit similar to other devices.

Data item: **GENERIC, GENERIC, ATTITUDE**

The Attitude data item must also be edited once it is added to a vehicle's device list. Highlight the Attitude data item in the vehicle's device list and click the Edit button. The Attitude dialog box appears as seen below.



Attitude

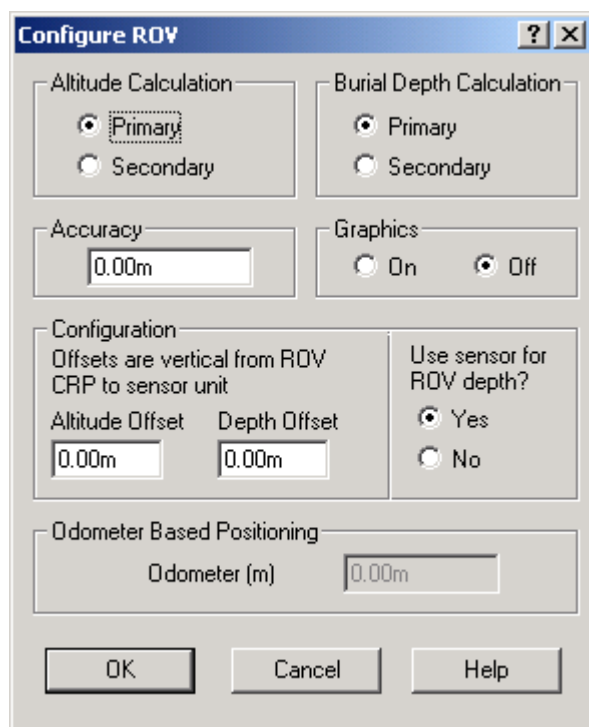
By default, the sensor mode is off, meaning that data from the Attitude device will not be used in the vehicle's calculations. To turn the sensor on, and begin using the inclination corrections in the position output, click the '**On**' radio button.

Correction values can also be added in this section of the dialog. The correction values (entered in units of degrees-decimal degrees) are added to the raw pitch and roll values received from the Attitude device before the data is applied to the vehicle's calculations.

Ensure that entered values adhere to the sign convention used by WinFrog. You can verify that the corrections are entered properly by viewing the pitch and roll values in the I/O Device window and the Vehicle Text window.

Data item: **GENERIC, GENERIC, ROVDATA**

The ROVDATA data item must also be edited once it is added to a vehicle's device list. Highlight the ROVDATA data item in the vehicle's device list and click the Edit button. The Configure ROV dialog box appears as seen below.

The image shows a Windows-style dialog box titled "Configure ROV". It has a standard title bar with a question mark icon and a close button. The dialog is organized into several sections. The "Altitude Calculation" section has two radio buttons: "Primary" (selected) and "Secondary". The "Burial Depth Calculation" section also has two radio buttons: "Primary" (selected) and "Secondary". The "Accuracy" section contains a text input field with "0.00m". The "Graphics" section has two radio buttons: "On" and "Off" (selected). The "Configuration" section includes a label "Offsets are vertical from ROV CRP to sensor unit", two text input fields for "Altitude Offset" and "Depth Offset" (both containing "0.00m"), and a section titled "Use sensor for ROV depth?" with "Yes" (selected) and "No" radio buttons. At the bottom, the "Odometer Based Positioning" section has a label "Odometer (m)" and a text input field with "0.00m". At the very bottom are three buttons: "OK", "Cancel", and "Help".

Altitude Calculation

Primary will result in this vehicle's altitude being determined from the observed altitude value found in the string from this device minus the altitude offset also found on this dialog. This value can be displayed in the vehicle text window as ROV Alt.

Secondary will result in no calculation or assignment of the vehicle's altitude from this device. The raw data is still always recorded.

Burial Depth Calculation

Primary will result in the burial depth (if applicable) being determined from the observed burial depth value found in the string from this device minus the Depth Offset also found on this dialog.

Secondary will result in no calculation or assignment of the burial depth from this device. The raw data is still always recorded.

Accuracy

A realistic accuracy of the positioning system utilized should be input. Changing of the default value should be performed with caution, as this will affect the Kalman-filtered position of the vehicle.

Graphics

Turning on the Graphics will display the device name and a square at the location of the hydrophone, within the Graphics and Bird's Eye windows.

Configuration

Vertical offsets of the altitude and depth sensors, relative to the CRP, can be input here. The Altitude Offset is the vertical distance (positive up) from the ROV's CRP to the acoustic beacon tracking the seafloor. The Depth Offset would be the vertical distance (positive down) from the ROV's CRP to the sensor that provides depth information of the ROV. The water column depth would be the sum of the depth reading, the two offsets, and the altitude value.

ROV depth

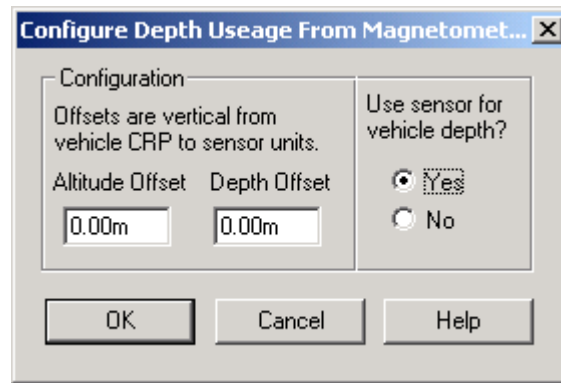
The real-time depth of the ROV can be determined from the depth (pressure) sensor, if one is installed on the ROV.

Odometer Based Positioning

Not used by this device.

Data item: **GENERIC, GENERIC, MAGNETOMETER**

Once the MAGNETOMETER data item has been added to the vehicle device list it must be edited to suit the application. Highlight the MAGNETOMETER data item in the vehicle's device list and click the Edit button. The Configure Depth Usage From Magnetometer dialog box appears as seen below.



This data item must be added to a vehicle for data recording and storage to occur. After the data items are attached to a vehicle, the type 800 Raw Data Record is saved for post processing options.

It should be noted that both of the offset options are vertical offsets measured from the CRP of the vessel to the respective sensors with up being positive.

The “Use sensor for vehicle depth?” option allows you to display the vehicle depth (depth sensor measured + offset) in the Vehicle Text window by selecting “yes”. If “no” is selected and no other depth sensor devices are added to this vehicle, the depth will be displayed as zero in the Vehicle Text window.

Data item: **GENERIC, GENERIC, COUNT**

This data item configuration dialog has two tabs, the Reference Counters and Real-Time Navigation Updates.

The screenshot shows the 'Configure Counter' dialog box with the 'Reference Counters' tab selected. The dialog has a title bar with a question mark and a close button. Inside, there are two tabs: 'Reference Counters' and 'Real-Time Navigation Updates'. The 'Reference Counters' tab contains several sections for configuring a counter. The first section, 'Choose Reference Counter to Modify', has a dropdown menu showing 'Counter# 1' and a 'Direction' button with 'Up / Down' text. The second section, 'Set Specific Cable Count', has a text input field with '1000' and a 'SET' button. The third section, 'Set Counter Scale', has a text input field with '1.0000000' and a 'New Counter Scale from Cable Count' section with a text input field '0.0' and a 'SET' button. The fourth section, 'Set Counter Offset', has a text input field '0.0' and a 'SET' button. The fifth section, 'Counter Name', has a text input field 'Counter# 1' and a 'SET' button. At the bottom of the dialog are 'OK' and 'Cancel' buttons.

Reference Counters tab

This tab is used in conjunction with the Calculations window to maintain up to five reference counts based on the Channel One (cable) count. These reference counts are not used for any real-time calculations and are not logged to any file – they are intended for reference purposes only.

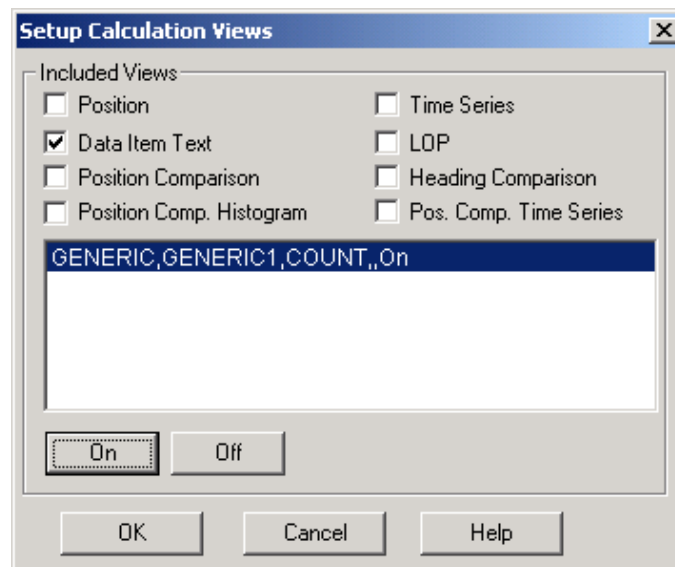
One common use for the Reference Counters tab is to have a 'count down' between cable body deployment. This is accomplished by entering the cable spans between cable bodies in the 'Set Specific Cable Count' field(s), selecting the 'Direction' as

'Down' and exiting with OK when the first cable body is launched. The results of this configuration are typically viewed in a Calculations window.

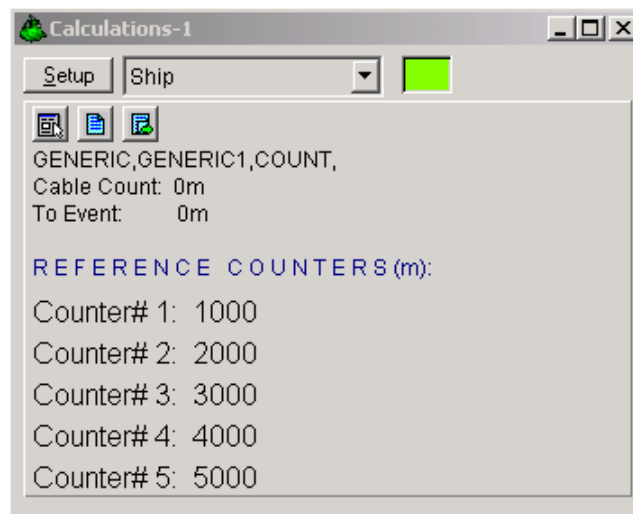
View and configure the Calculations window by completing the following steps.

Note: To view the reference counts the COUNT data item must be attached to the vehicle.

1. Select View > Calculations to open the Calculations window.
2. In the Calculations window, select the appropriate vehicle from the dropdown list box and click the Setup button to open the Setup Calculation Views dialog box.



3. In the Setup Calculation Views dialog select the Data Item Text checkbox. Then to turn On the COUNT data item, select the COUNT data item from the list and click the On button.
4. Click OK and the Calculations window opens as seen below.



Once the Calculations window has been opened and configured, the five reference counters can be modified using the Reference Counters tab of the Configure Counter dialog. (Note: the Configure Counter dialog can be directly accessed from the Calculations window by clicking the  icon in the Calculations window.)

The Reference Counter tab allows the reference counters to be modified in a number of ways, as described below. Start by selecting the reference counter you want to modify from the dropdown list box at the top of the page.

Direction

When the *Up/Down* button is not depressed the reference count will increase if the input cable count increases and decrease if the input cable count decreases. When the *Up/Down* button is depressed the reference count will decrease if the input cable count increases and increase if the input cable count decreases.

Set Specific Cable Count

To set the reference counter to a specific cable count, enter the desired value in the edit field then click the *Set* button. When you exit the Configure Counter dialog by clicking the OK button, the desired reference counter value will be set to the entered value. This value will then continue to increment or decrement based on the input cable count and the current settings for the reference count.

Set Counter Scale

To change the scale at which the reference count will increment or decrement relative to the input cable count, enter the desired scale factor into the scale field. Leave the *New Counter Scale from Cable Count* value at its present value to apply the scale from the current point onward. Enter in a count value into the *New Counter Scale from Cable Count* field to apply the scale from a previous count value onward. Once the desired scale factor and count value is entered, click the *Set* button and then click the *OK* button.

Set Counter Offset

To set an offset from the input cable count to the reference count, enter the desired value into the Set Counter Offset field, click the *Set* button and then click the *OK* button. This value will be added to the input cable count.

Counter Name

To change the reference counter name, enter the desired name into the *Counter Name* field. Click the *Set* and then the *OK* button to enter the change.

Real-Time Navigation Updates tab

The screenshot shows the 'Configure Counter' dialog box with the 'Real-Time Navigation Updates' tab selected. The dialog has a title bar with a question mark and a close button. Inside, there are two tabs: 'Reference Counters' and 'Real-Time Navigation Updates'. The 'Real-Time Navigation Updates' tab contains several sections:

- Interval:** A text box containing '1.0 s' and a label 'Enter Raw Data File Logging Interval in Seconds, 0=All Data'.
- Channel 1 (Telephone / Power Cable):** A group box containing three checked checkboxes: 'Cable Count', 'Payout Speed', and 'Tension'.
- Channel 2 (Tow Cable):** A group box containing three checked checkboxes: 'Cable Count', 'Payout Speed', and 'Tension'.
- Channels 3,4,5 Tension:** A group box containing three unchecked checkboxes: 'LCE Tension (Channel 3)', 'CDE 1 Tension (Channel 4)', and 'CDE 2 Tension (Channel 5)'.
- General:** A group box containing two unchecked checkboxes: 'Distance to Event' and 'Cable Angle'.

At the bottom of the dialog are 'OK' and 'Cancel' buttons.

This tab enables/disables data from this device to be passed to the vehicle. Unlike the Reference Counters tab, data from the Real-Time Navigation Updates tab can be logged to the raw files if this data item is associated with a vehicle. This allows the vehicle to have more than one COUNT data item added to it, which is required if it is necessary to log data from more than one counter (raw device data is only logged if the data item is associated with a vehicle). If a checkbox is selected the data value will be passed to the vehicle. For example, if the *Cable Count* checkbox is selected in the *Channel 1* section, then the cable count from the input device will be passed to the vehicles channel 1 count.

The *Interval* section sets the data logging interval used when the “With Events” Logging Control option is selected (refer to chapter 10 of the WinFrog User’s Guide for more information).

Data item: **GENERIC, GENERIC, BOTTOMDEPTH**

Once the BOTTOMDEPTH data item has been added to a vehicle's device list, it must be edited to suit the application. In the vehicle's device list, highlight the BOTTOMDEPTH data item and click the Edit button. The Configure Sounder dialog box appears as seen below.

Configure Sounder

Calculation
☒ Primary
☐ Secondary

Graphics
☒ Off
☐ On

Apply Tides
☐ Yes
☒ No

Soundings for Profile
☐ Collect Data
Distance Interval: 25.00m
☐ Purge RAM
Interval Type:
☒ Along Line
☐ Actual Distance

Database Filename: no file

☒ Abort Saving Data Browse

☒ Display Soundings Data in Profile Window

Offsets
Fore/Aft: 0.00m Port/Stbd: 0.00m Depth: 0.00m

OK Cancel Help

Calculation

Set the type of calculation to Primary or Secondary using the appropriate radio button. WinFrog will only utilize (i.e., display and record) data from a Primary sounder device. If there is more than one Primary sounder attached to a vehicle's device list, WinFrog will not mean the data (as is done with positional devices), but rather alternate between the devices. Data from a Secondary status sounder will simply be monitored.

Graphics

If the On radio button is selected, a labeled square representing the location of the sounder will be displayed in the Graphics and/or Bird's Eye windows.

Apply Tides

If the Yes radio button is selected, WinFrog will apply tidal corrections to the observed water depths. Depths displayed in the Vehicle Text window and recorded in automatic event (i.e., .DAT, .SRC, and .RCV) and type 351 raw files will refer to

the datum corrected depths. Note that type 411 raw data records will remain truly raw and will not reflect the tide correction.

The tide information can be supplied by a real time telemetry system or by predicted tide files. Either way, the tide “device” must also be attached to the same vehicle’s device list. For more information, refer to documentation on Tide devices.

Soundings for Profile

This section of the Configure Sounder dialog permits the collection of sounding data to an .mdb database file for display in WinFrog’s Profile window. This collection is completely separate from automatic event or raw data collection.

Collect Data

Select this checkbox to enable the collection of data to an .mdb database file.

Interval Type

Select to utilize either Along Line or Actual Distance (i.e., between successive position updates) calculations for data collection intervals. Selecting Along Line requires that you also enable survey line tracking.

Distance Interval

Specify the distance interval at which the data will be collected.

Purge RAM

Sounding data is stored in the RAM memory of the computer. Any data collected which will not be required at later time can be deleted by selecting the Purge RAM checkbox, then clicking the **OK** button to exit the dialog box.

Database filename

Click the Browse button to define where and to what filename the .mdb file will be written. The file name and location is displayed.

Abort Saving Data

Select this checkbox to abort saving data to the .mdb file. In other words, to save data to the .mdb file ensure that this box is NOT checked.

Display Soundings Data in Profile Window

Select this checkbox to enable the display of this data in WinFrog’s Profile window.

Offsets

This section of the dialog allows for entry of Offset values as measured from the vessel’s common reference point (CRP). Note that the Fore/Aft and Port/Stbd offsets are used for “cosmetic” visual purposes only: An echo sounder is not a positioning device, and hence its horizontal offsets have no application. If the echo sounder’s position is to be recorded correctly, you must create and enable a vehicle Tracking Offset for that specific location. The offsets entered here can simply be used as a

means of graphically confirming that the Tracking Offset values have been entered correctly.

The Depth Offset is applied: The entered value will be added to the received sounder data. Depths displayed in the Vehicle Text window and recorded in automatic event (i.e., .DAT, .SRC, and .RCV) and type 351 raw files will refer to the corrected depths. Note that type 411 raw data records will remain truly raw and will not reflect the depth offset correction.

Data item: GENERIC, GENERIC, WIND

There are no Edit or configuration options for this data item. However, it must be attached to the vehicle in WinFrog in order to record and display the data.

TELGRAM SPECIFICATION:

The Generic Input device can be configured to accept a variety of input strings. The specific data types accepted by this driver include:

ROVDATA

- depth
- pitch
- roll
- heading
- altitude
- cable burial depth

POSITION

- CRP latitude
- CRP longitude
- CRP Northing
- CRP Easting
- CRP Height

HEADING

- true heading

ELEVATION

- elevation

BOTTOMDEPTH

- water depth directly (e.g. sounder)
- water depth indirectly (ROV altimeter and depth w/ offsets)

ATTITUDE

- pitch
- roll

VELOCITY

- speed

MAGNETOMETER

- magnetic field value
- magnetic signal strength
- magnetometer depth
- magnetometer voltage
- magnetometer tuning value
- magnetometer altitude

COUNT

- cable count channel 1
- cable tension channel 1
- cable velocity channel 1
- cable count channel 2
- cable tension channel 2
- cable velocity channel 2
- ship speed

WIND

- wind speed
- wind direction