

WinFrog Device Group:	PLOW
Device Name/Model:	SeaDragon
Device Manufacturer:	Oceaneering International 11911 FM 529 Houston, Texas U.S.A. 77041 Tel: 1 713 329 4500 Fax: 1 713 329 4951
Device Data String(s) Output to WinFrog:	See Telegram Specification section below
WinFrog Data String(s) Output to Device:	NONE
WinFrog Data Item(s) and their RAW record:	PLOWDATA 490 ROV REF VEH NONE HEADING 409 COUNT 492

DEVICE DESCRIPTION:

This driver is used for positioning the plow and reading plow related data from the SeaDragon device.

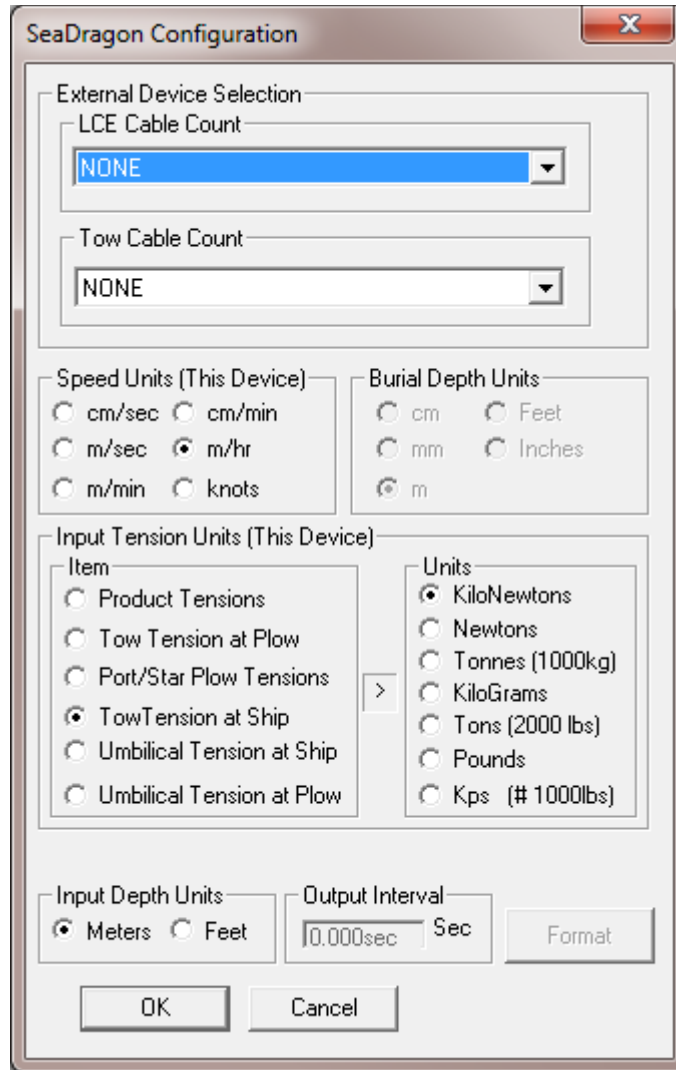
DEVICE CONFIGURATION INSTRUCTIONS

WINFROG I/O DEVICES > EDIT I/O:

Serial
Configurable Parameters

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 SeaDragon Configuration dialog box appears, as seen below.



Select the data source for the LCE telephone cable count data and the Tow cable count data from the dropdown list boxes. If the appropriate cable count data is contained in the data string from the SeaDragon, select SeaDragon from the dropdown lists. If the cable count data is coming from another device, select the appropriate device from the dropdown lists.

Also select the appropriate Input Speed Units as well as the Input Tension Items and their associated Units. Specify whether the Input Depth Units are to be meters or feet.

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

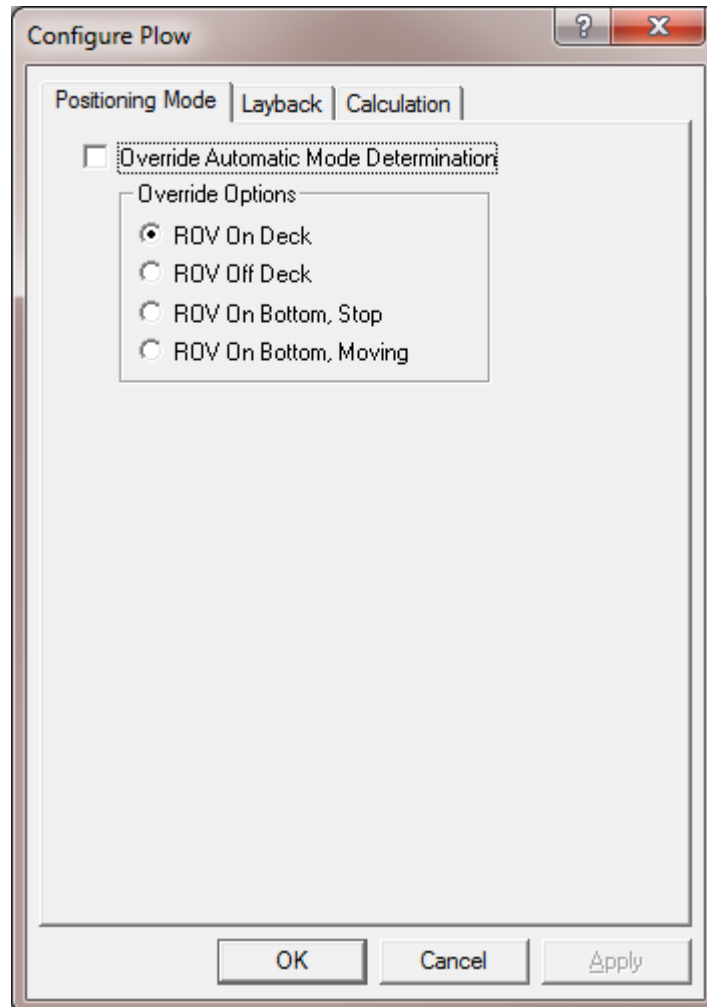
Adding the SeaDragon device creates four data items: PLOWDATA, HEADING, ROV REF VEH and COUNT. Once the data items have been added to the vehicle, they must be edited to suit the application.

Data item: ROV, SeaDragon, PLOWDATA

This data item is used to read plow related data as well as to provide a reference point on the plow for positioning the plow relative to the ship. It is typically added to the plow vehicle in WinFrog.

Highlight this data item in the vehicle's device list and click the Edit button to open the Configure Plow dialog box as seen below.

Positioning Mode tab



Override Automatic Mode Determination:

This checkbox determines whether WinFrog automatically determines the towed vehicle location and mode or whether the operator determines it.

When in automatic mode, WinFrog uses the following criteria to determine the mode of the towed vehicle:

ROV On Bottom, Moving is assumed if the speed is greater than .2 knots or the Use ROV Speed setting is off and the layback is calculated at more than 1 meter.

ROV Off deck is assumed if the speed is greater than .2 and the layback is calculated at less than 1 meter and the altitude is greater than 4 meters.

ROV On deck is assumed if the speed is 0 and the layback calculated is less than the sum of the depth offset entered on the Calculations tab and the Tow point above water entered on the ROV REF VEH dialog.

ROV On Bottom, Stopped is assumed if none of the others are true.

Override Options:

ROV On deck places the towed vehicle on the tow vessel 5 meters forward of the offset point entered in the ROV REF VEH dialog.

ROV Off deck places the towed vehicle on the tow vessel at the tow point, which is the offset point entered in the ROV REF VEH dialog.

ROV On Bottom, Stop leaves the vehicle where it was when this option was selected and makes no further calculations as to its position.

ROV On Bottom, Moving calculates the towed vehicle's position using the data available and updates all displays with this data.

Layback tab

The screenshot shows the 'Configure Plow' dialog box with the 'Layback' tab selected. The dialog has three tabs: 'Positioning Mode', 'Layback', and 'Calculation'. The 'Layback' tab contains the following settings:

- Layback Calculation Method:** Radio buttons for 'Pythagorean' (selected) and 'Catenary'. A text box for 'Tow Cable Constant' contains '73.29051' with units 'N/m'.
- ROV Depth:** Radio buttons for 'Use PLOWDATA depth data for calculations and assign to vehicle' (unselected) and 'Use CRP depth from vehicle' (selected). A text box for 'Enter Height Offset from CRP to depth sensor' contains '0.0m'.
- Use ROV Tow Angle:** Radio buttons for 'Yes' (unselected) and 'No' (selected).
- Use ROV Speed:** Radio buttons for 'Yes' (unselected) and 'No' (selected).
- Trench Depth:** A text box for 'Offset:' contains '0.0cm'.
- Layback Direction Source:** Radio buttons for 'Path Follow (Recommended)' (selected), 'Tow Vessel CMG' (unselected), and 'Tow Vessel Heading' (unselected).

At the bottom of the dialog are three buttons: 'OK', 'Cancel', and 'Apply'.

Layback Calculation Method

Pythagorean uses the depth and cable count to form a right triangle. The layback is then calculated and applied to the tow vehicle's offset position along with an azimuth based upon the previous towed vehicle's raw position. WinFrog will use this position to calculate an azimuth but use the calculated layback for the distance between the towed vehicle and the tow vehicle.

The right triangle is formed thus: the hypotenuse is the cable count and the vertical value is the sum of the depth, Tow Point Above Water and the z offset found on the Calculations tab.

Catenary requires the weight of the cable in newtons/meter, (1lbs/ft = 14.63nt/m). This calculation uses the cable count, depth of the towed vehicle and the tow tension to calculate the layback using a static catenary model. The azimuth used is the same as described above.

Use ROV Depth

Use PLOWDATA depth for calculations and assign to vehicle causes two actions:

- 1) The depth obtained from this device will be added to the depth offset and assigned to this vehicle. The depth offset is entered in the Calculation tab.
- 2) The value used to calculate the layback is the above value plus the depth offset entered on the Calculations tab plus the value *Tow Point above the Water*, entered in the ROV REF VEH configuration dialog (attached to the tow vehicle).

Use CRP depth from Vehicle causes the depth for the layback calculation to be obtained from the vehicle. Essentially, this means the depth must be obtained by another device and assigned to the vehicle by that device.

Use ROV Speed

Yes causes the speed of the device to be obtained from this device. This requires that the towed vehicle in use must have the ability to output a speed in its data string. If it does not, then select No. **No** causes the speed to be calculated from the positional information and time. It will be assigned to the vehicle.

Use ROV Tow Angle

This option only applies to the SeaplowVIII Device.

Trench Depth

Offset – If the Trench depth checkbox is selected on the Calculation tab (see below) then this value, 0.0 or otherwise, will be assigned as this vehicle's trench depth.

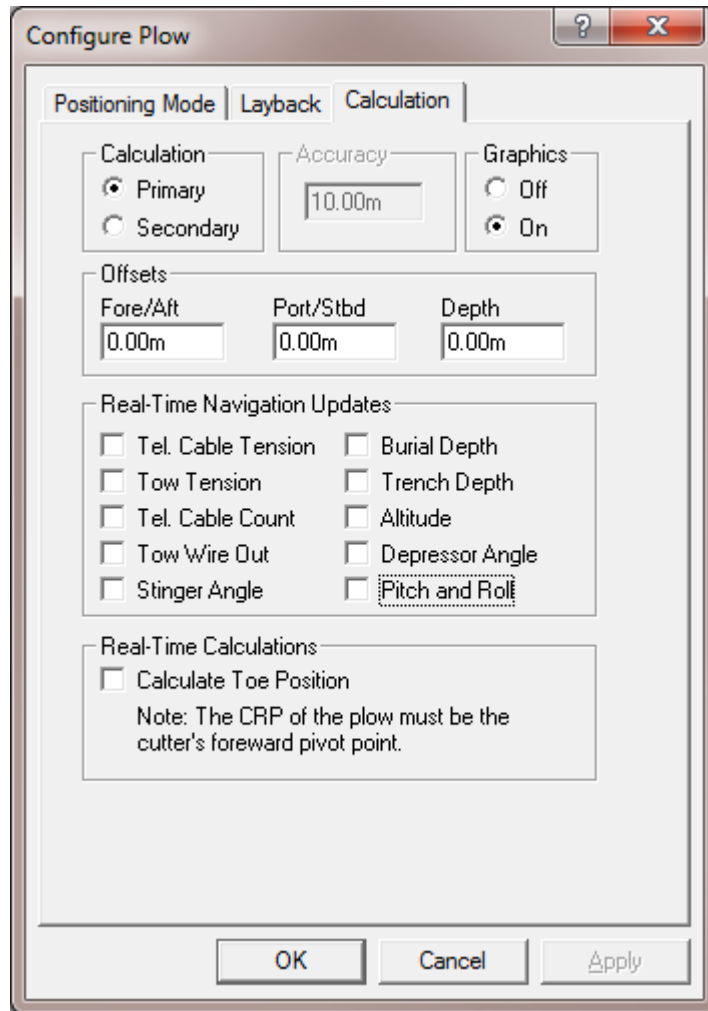
Layback Direction Source

Path Follow (Recommended) This is the recommended selection. It uses its own previous position and the tow vehicle location to determine the direction to the new position.

Tow Vessel CMG This selection uses the tow vehicle's course made good (plus 180 degrees) to determine the direction to the new position. As the course made good changes the towed vehicle will swing back and forth.

Tow Vessel Heading This selection uses the tow vehicle's heading (plus 180 degrees) to determine the direction to the new position. As the vessel's heading changes the towed vehicle will swing back and forth. This is usually more pronounced than the Tow Vessel CMG selection.

Calculation tab



Calculation

Primary – when selected, the layback described above will be used to calculate this vehicle's position, which will be assigned to it.

Secondary – when selected, this device will not determine this vehicle's position.

Accuracy

The Kalman filter uses this value as a weight factor. It should be set to a reasonable value.

Graphics

Select the On radio button to display a square in the Graphics and Bird's Eye windows at the offset position below.

Offsets

The **Fore/Aft** and **Port/Stbd** offset point is the reference point for the layback distance. Essentially, the lay back distance is the distance between this point and the offset point of the tow vehicle described in the **ROV, SeaDragon, ROV REF VEH** section. This can also be viewed as the beginning or 0 point of the tow cable. This offset point is from the towed vehicle's CRP to the tow point.

Depth is an offset from the CRP. It is applied in several different ways:

- 1) If **Use ROV Depth** is set to **Yes** (on the Layback tab) this value is added to the depth from this towed vehicle device and assigned to the vehicle's depth. See Use ROV Depth on the Layback tab above.
- 2) If the Pythagorean solution is selected, this value is added to the vehicle depth and the Tow Point Above Water value to get the vertical portion of the right triangle when computing the layback.
- 3) If the catenary solution is selected, this value is not used in the model.

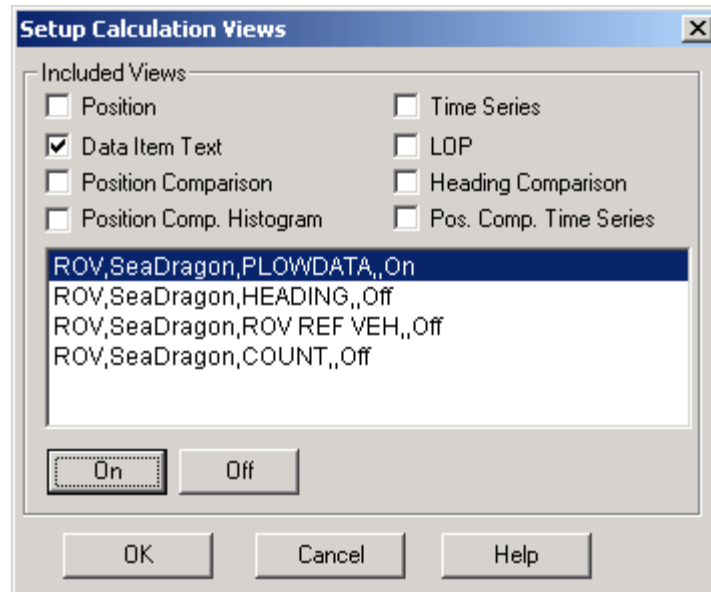
Real-Time Navigation Updates

Most Plow devices have the ability to provide real-time data updates via an umbilical. The Decoded data tab in the I/O Devices window will indicate what data is updated in real-time for each device. You should only select the checkboxes for data output by the device, as leaving these checkboxes selected causes data to be assigned to the vehicle. If the device does not output a particular type of data, 0 will be assigned for each item left selected and this will cause values from other devices to be overwritten.

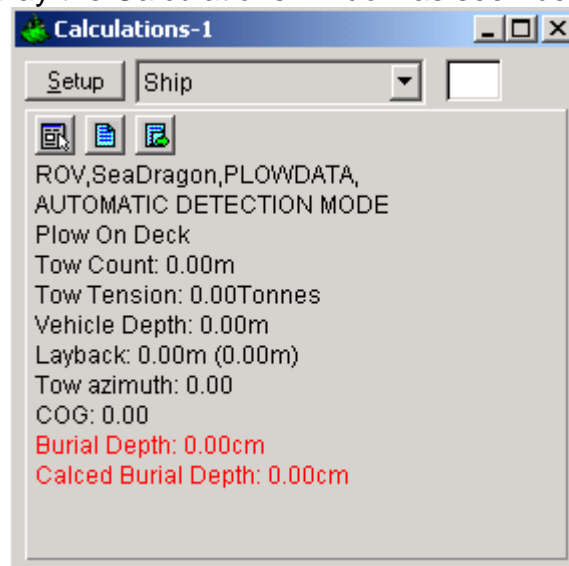
Real-Time Calculations


Calculate Toe Position – this option only applies to the Smart Cutter plow device.

The results of the above configurations are typically viewed in a Calculations window. To display the Calculations window, select View > Calculations from the main menu. Select the appropriate vehicle from the dropdown list and click the Setup button. Select **Data Item Text** and turn the data item **ROV, SeaDragon, PLOWDATA** on by highlighting it and clicking the **ON** button as seen below.



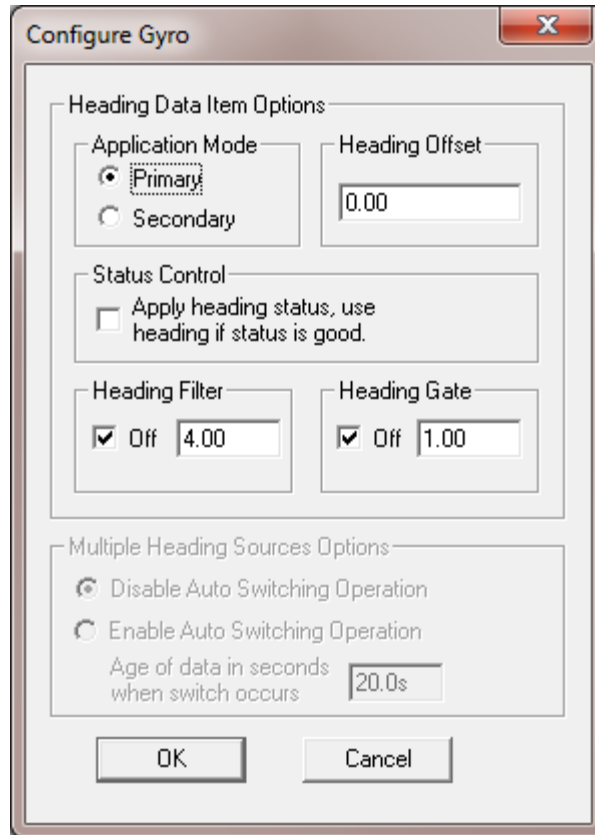
Exiting with OK will display the Calculations window as seen below.



From this window, you can monitor some of the input data as well as the layback calculation. This Calculation window also provides a shortcut to the Configure Plow dialog box by clicking the  button.

Data item: ROV, SeaDragon, HEADING

If the Heading data from the sensor on the Plow is deemed reliable enough to orient the vehicle then this data item is added to the Plow vehicle in WinFrog. Highlight this data item in the vehicle's device list and click the Edit button to open the Configure Gyro dialog box as seen below.



Heading Data Item Options

Application Mode(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 heading information. Devices set to Secondary are simply monitored, and are not used in the vehicle's calculations.

Note that WinFrog supports automatic switching from a designated Primary to a Secondary in the event that data from the Primary fails (see Multiple Heading Sources Options).

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.

Status Control

If the respective device is providing data status (valid or not valid) for the HEADING data, selecting this option will result in WinFrog monitoring the data status and if it is set to not valid, the data will not be used.

If this option is not selected, the data is used regardless of the data status.

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.

Multiple Heading Sources Options:

WinFrog supports automatic switching from a designated Primary source to an alternate Secondary source in the event that the Primary fails. The first Secondary source to receive data after the Primary has failed becomes the alternate Primary providing the heading for the vehicle. When the designated Primary is detected as active again, the alternate Primary source reverts to Secondary and the designated Primary provides the heading data to the vehicle.

If an alternate Secondary fails and there are additional Secondary sources, it in turn is detected by the first of the remaining operational Secondary sources to receive data after the failure, at which time this Secondary becomes the alternate Primary.

Note that this option is only available if more than one HEADING source is associated with the respective vehicle. Changes made to the Auto Switching options for any one of the HEADING data items are automatically assigned to the others upon exiting this dialog with OK. If the Auto Switching option is enabled and the respective HEADING source has been set to Primary, all others are automatically set to Secondary. The exception to this is when configuring a WinFrog Controlled Remote (WinFrog with a Remote module) from a Controller. In this case, changes made to one HEADING source are not automatically made to other HEADING sources. The operator must explicitly make them for each HEADING source.

This option is not available in the WinFrog Remote package.

Disable/Enable Auto Switching Operation:

Select the mode you wish to operate WinFrog.

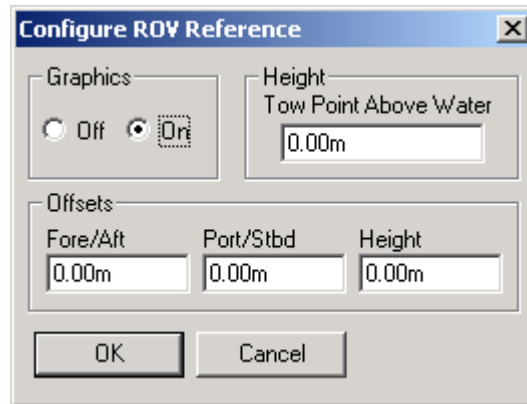
Age of data in seconds when switch occurs:

Enter the age of data that is permitted before the source is considered to have failed.

Data item: ROV, SeaDragon, ROV REF VEH

This data item is attached to the vehicle in WinFrog that has a real-time positioning source (DGPS, etc.), typically the ship. This vehicle with its known position serves as

the reference point for determining the Plow's position. Highlight this data item and click the Edit button to open the Configure ROV Reference dialog box seen below.



Graphics:

Select the On radio button to display the device name and a square at the location of the ROV, within the Graphics and Bird's Eye windows.

Tow Point Height:

The height of the tow point above water is added for layback calculations only if a towed vehicle model is used.

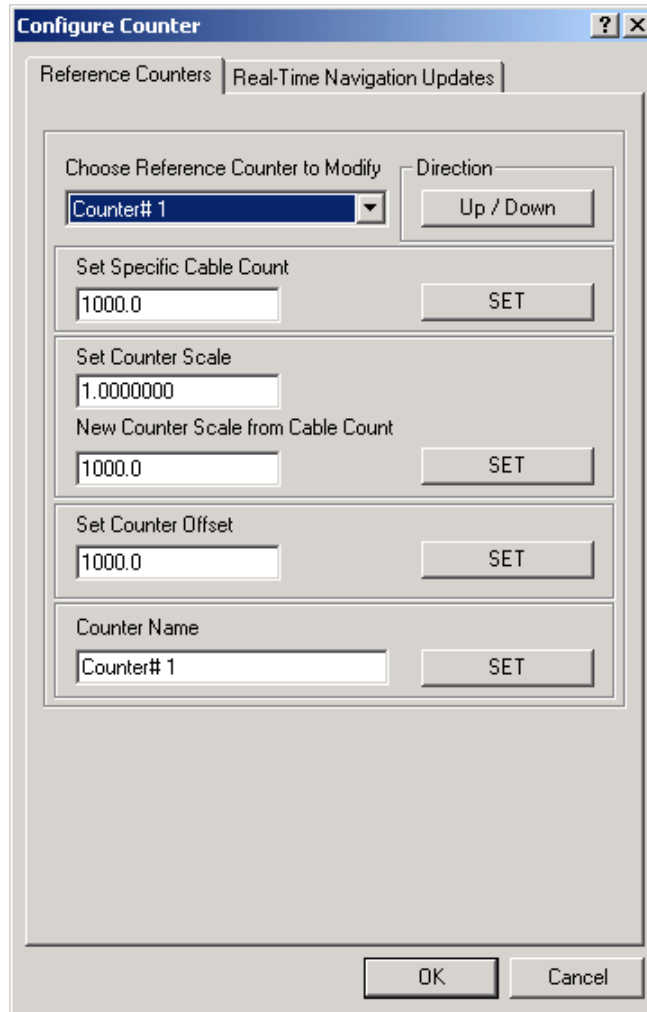
Offsets:

The X,Y,Z Offsets are applied from the CRP to the tow point (usually the winch) on the ship. These values are set similar to values that would be applied to any device offset within WinFrog. Note that the Height Offset is not used for operations involving plough vehicles.

Note: It is advised to use the waterline as the vertical CRP reference when sub-sea positioning devices are employed.

Data item: ROV, SeaDragon, COUNT

Highlight this data item and click the Edit button to open the Configure Counter dialog box seen below.



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.

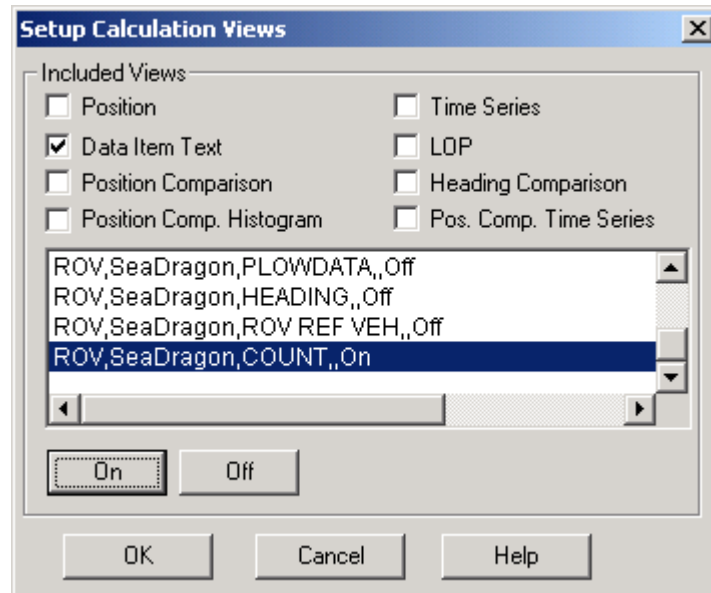
One common use for the Reference Counters tab is to have a 'count down' between cable body deployment. This is accomplished by entering the cable spans between cable bodies in the 'Set Specific Cable Count' field(s), selecting the 'Direction' as 'Down' and exiting with OK when the first cable body is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

View and configure the Calculations window (shown below) by completing the following steps.

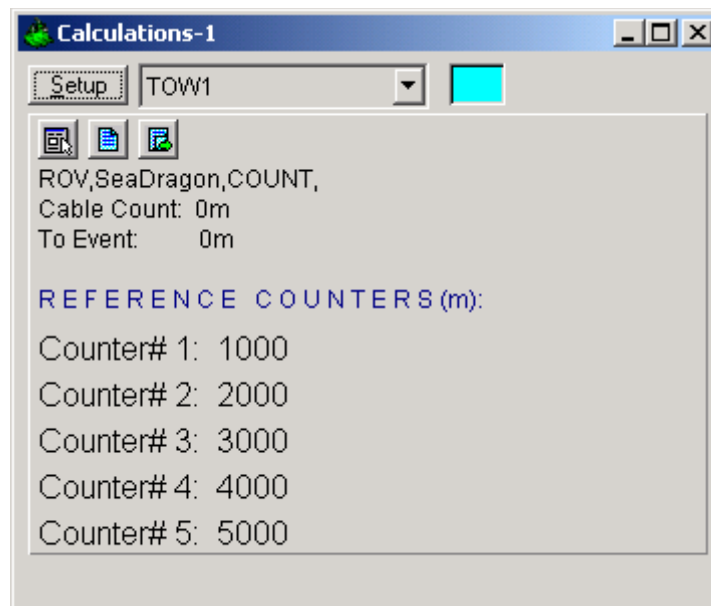
Note: To view the reference counts, the COUNT data item must be attached to the vehicle.

1. Select View > Calculations from the main menu to open the Calculations window.


2. In the Calculations window, click the Setup button to open the Setup Calculation Views dialog shown below.



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 a Calculations window, with the reference counter information displays as seen below.



Once the Calculations window has been opened and configured, the five reference counters can be modified using the Reference Counters page 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 and click the *Set* button. When the Configure Counter dialog OK button is clicked, 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 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.

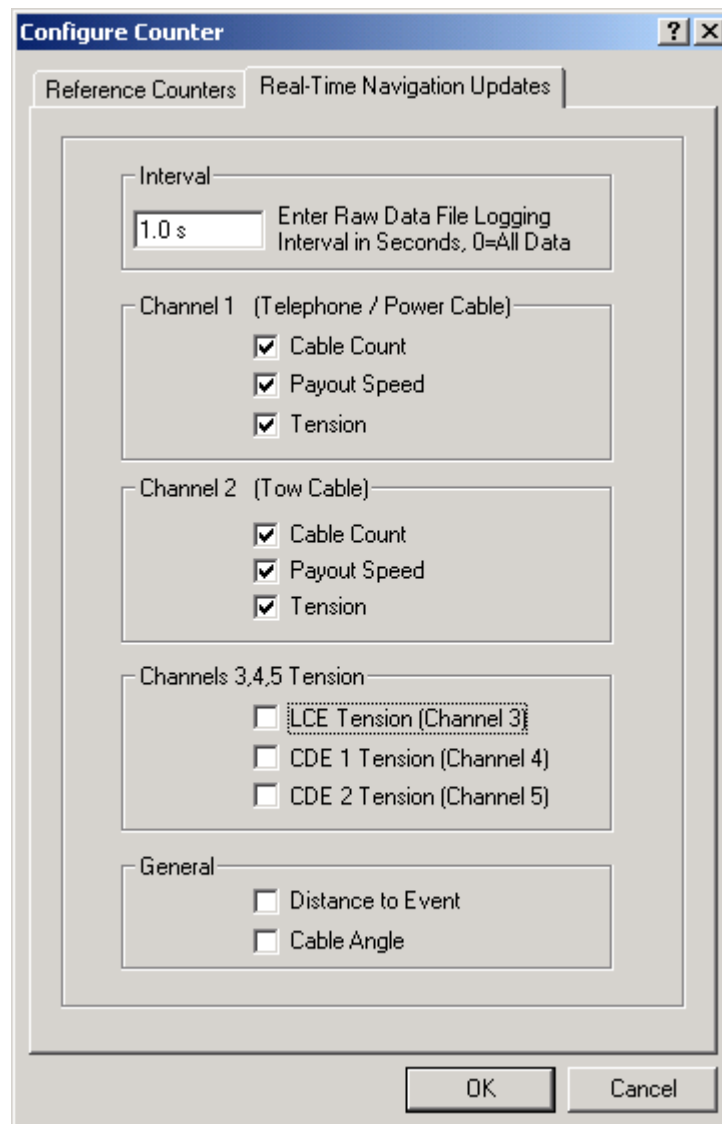
Set Counter Offset

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* button and then the *OK* button to enter the change.

Real-Time Navigation Updates tab



This tab enables/disables certain 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 without one conflicting with the other. One COUNTER device may provide the telephone cable count while the other provides the tow count. 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).

TELGRAM SPECIFICATION:

Field Data

1	"#"
2	plow burial converted to cm
3	M_Water_Depth
4	plowTowTension
5	Plow_Tow_Angle
6	Plow_Head
7	M_Speed
8	Plow_Pitch
9	plow_Roll
10	Port_Skid_Pos
11	Stbd_Skid_Pos
12	M_Altitude converted to cm
13	Plow_Off_Angle
14	Date_Text
15	Plow_Tension
16	shipTowOut
17	telTension
18	telCount