

<b>WinFrog Device Group:</b>	<b>PLOW</b>
<b>Device Name/Model:</b>	<b>SeaPlow VIII</b>
<b>Device Manufacturer:</b>	<b>Perry Slingsby Systems</b> 821 Jupiter Park Drive Jupiter, Florida 33458-8946 Tel: 1 561 743 7000 Fax: 1 561 743 1313 Email: pssi@us.perrymail.com
<b>Device Data String(s) Output to WinFrog:</b>	See Telegram Specification section below.
<b>WinFrog Data String(s) Output to Device:</b>	See Telegram Specification section below.
<b>WinFrog Data Item(s) and their RAW record:</b>	HEADING            409 PLOWDATA           490 ROV REF VEH        NONE

**DEVICE DESCRIPTION:**

This driver is used for positioning the Plow and reading plow related data from the SeaPlow VIII plow device.

***DEVICE CONFIGURATION INSTRUCTIONS***

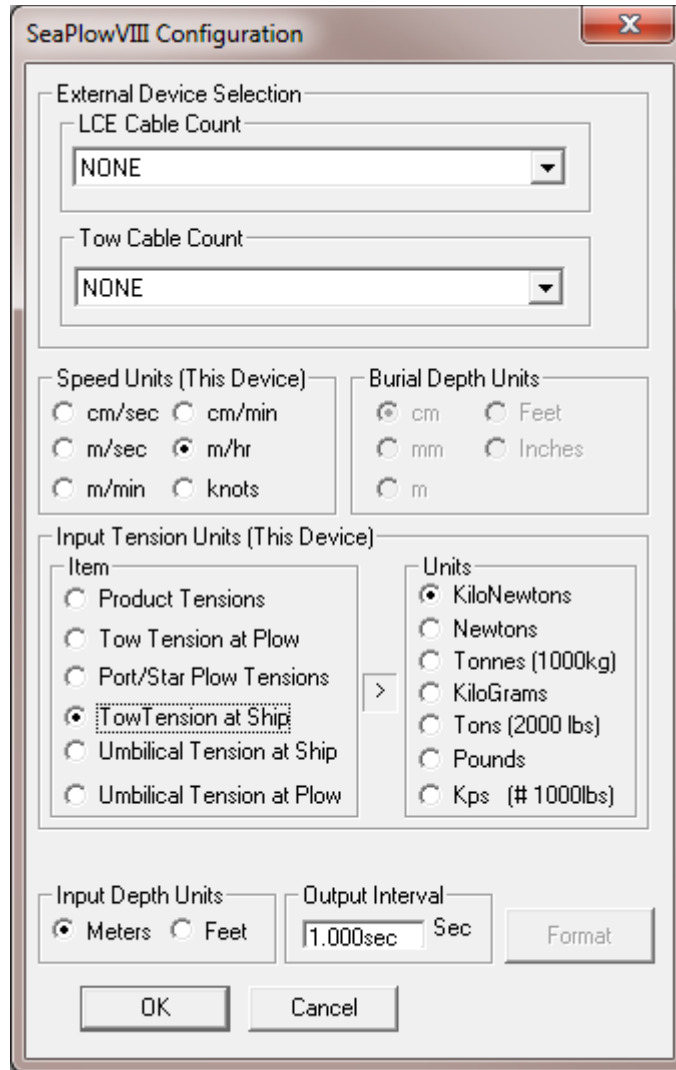
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**WINFROG I/O DEVICES > EDIT I/O:**

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 SeaPlowVIII 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 lists. Also select the appropriate Input Speed Units and Burial Depth Units as well as each Input Tension Item and its associated Units. Specify whether the Input Depth Units are to be meters or feet and enter an Output Interval.

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

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

## Data item: ROV, SeaPlowVIII, 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.

The screenshot shows the 'Configure Gyro' dialog box with the following settings:

- Heading Data Item Options:**
  - Application Mode:** Primary (selected), Secondary
  - Heading Offset:** 0.00
- Status Control:**
  - Apply heading status, use heading if status is good.
- Heading Filter:**
  - Off 4.00
- Heading Gate:**
  - Off 1.00
- Multiple Heading Sources Options:**
  - Disable Auto Switching Operation
  - Enable Auto Switching Operation
  - Age of data in seconds when switch occurs: 20.0s

### 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.

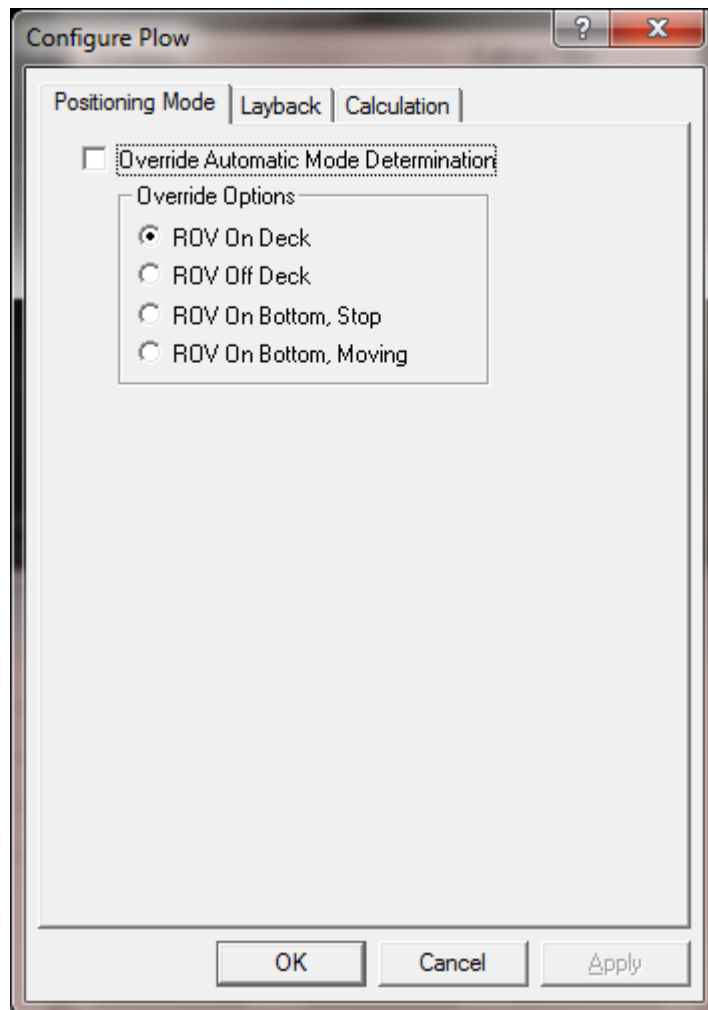
**Age of data in seconds when switch occurs:**

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

**Data item: ROV, SeaPlowVIII, PLOWDATA**

This data item is used to read plow related data and 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.

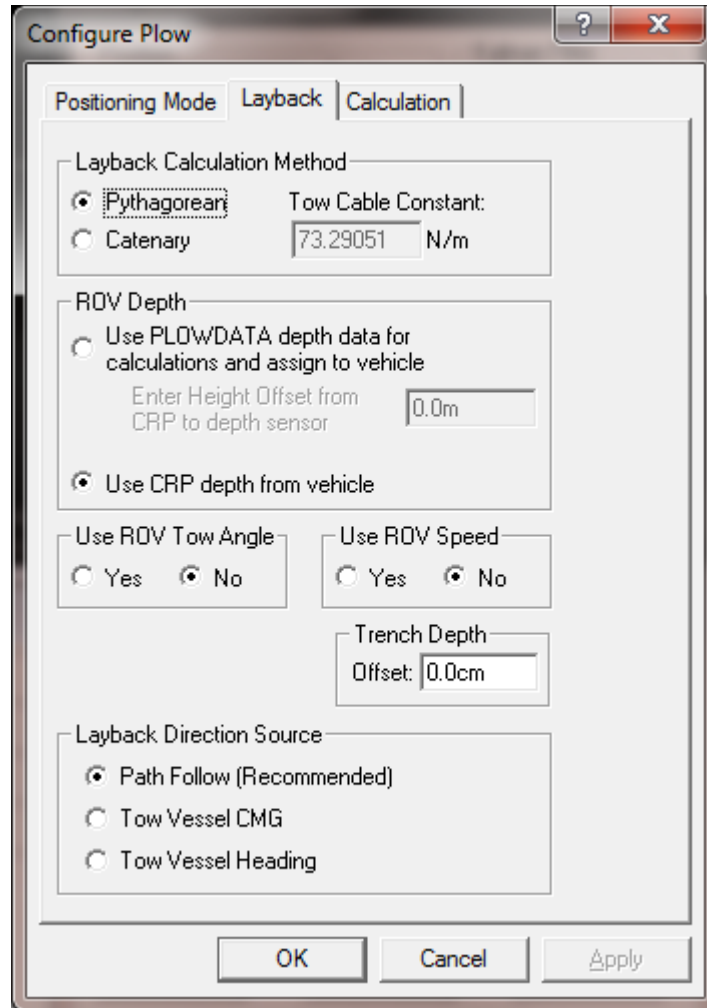
### **Override Options:**

**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**

#### **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 as follows: 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.

## 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 Tow Angle

If Yes is selected then the tow angle used to derive the plow position is received in the plow telegram.

## 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.

## 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.

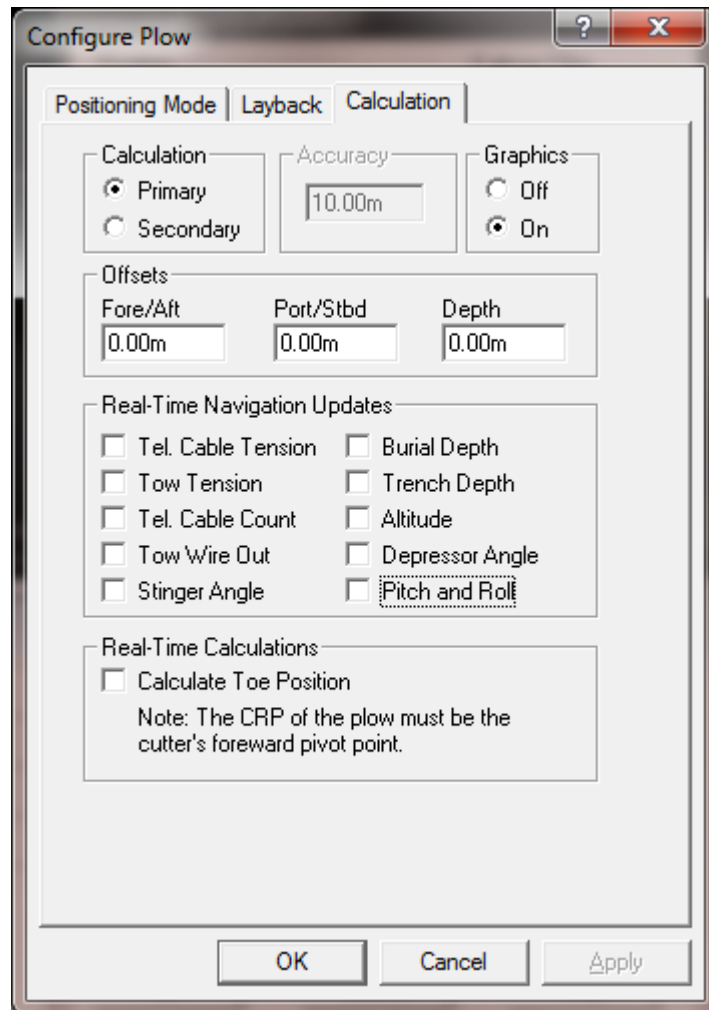
## Layback Direction Source

**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, SeaPlowVIII, 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.

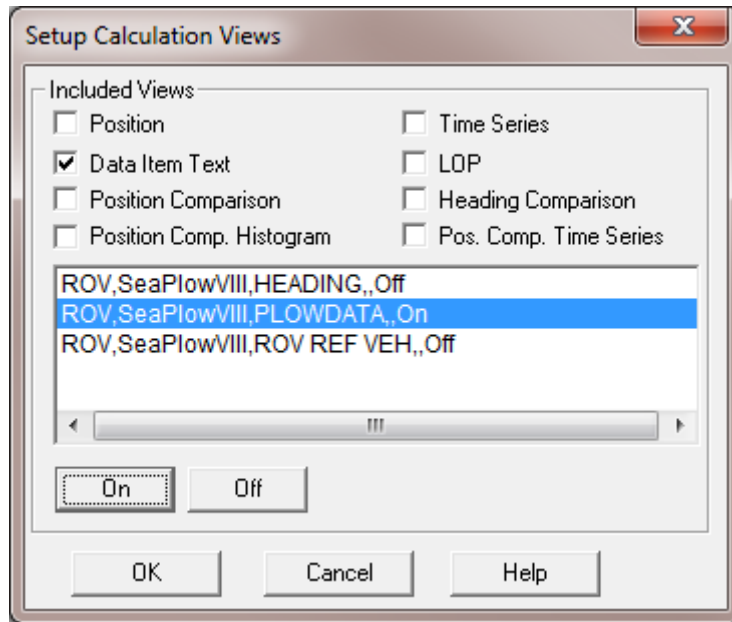
### **Real-Time Navigation Updates**

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.

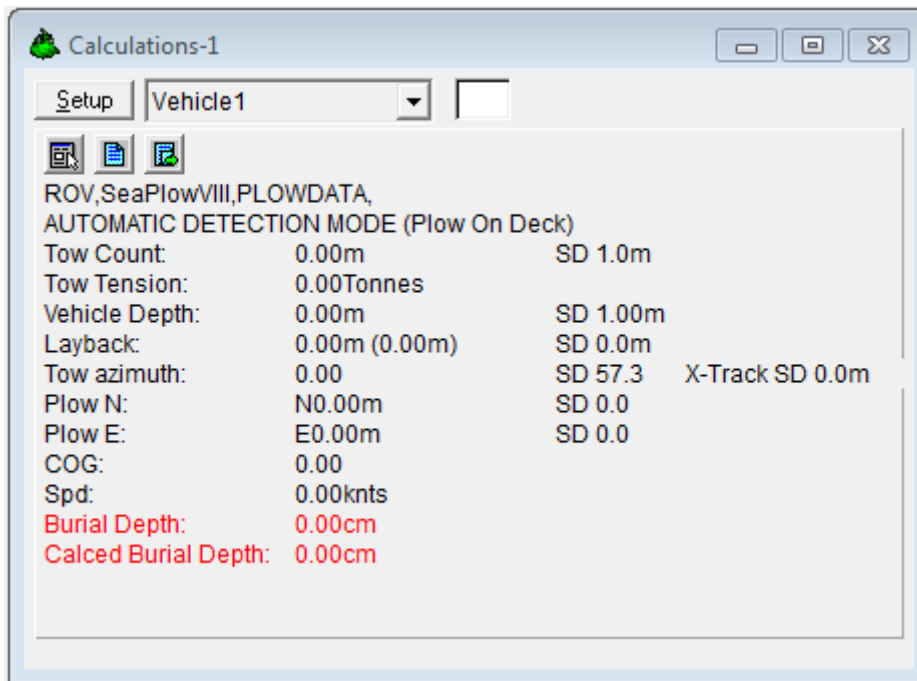
### **Real-Time Calculations**


**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, SeaPlowVIII, PLOWDATA on by highlighting it and clicking the ON button as seen below.



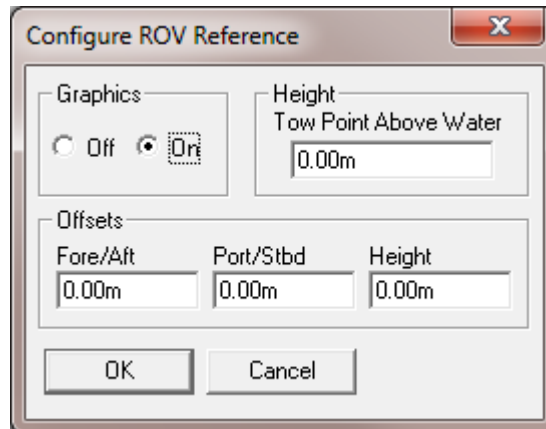
Exit with OK to display the Calculations window as seen below.



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, SeaPlowVIII, 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 as 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 plow vehicles.

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

## TELGRAM SPECIFICATION:

### INPUT STRING

Field	Data
1	\$SPVIII
2	portPull
3	stbdPull
4	asLaidTension
5	depHeight
6	trenchDepth
7	pitch
8	roll
9	subDepth
10	fwdPortSkidHeight
11	fwdStbdSkidHeight
12	aftPortSkidHeight
13	aftStbdSkidHeight
14	heading
15	altitude
16	speed
17	travel
18	shipTowTen
19	shipTowOut
20	burialDepth
21	teleToPlow
22	towCableAngle
23	plowSteerAngle
24	plow comment

### OUTPUT STRING

Field	Data
1	"\$WFSP"
2	rovRefVehHeading
3	rovRefVehSpeed
4	IceTension
5	IceCount