

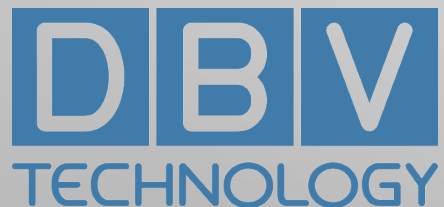


# Geodetic positioning on the deep sea floor using a one-way travel-time continuously operating reference station and an autonomous surface vessel

Harold T. “Bud” Vincent | Frederik J. Simons

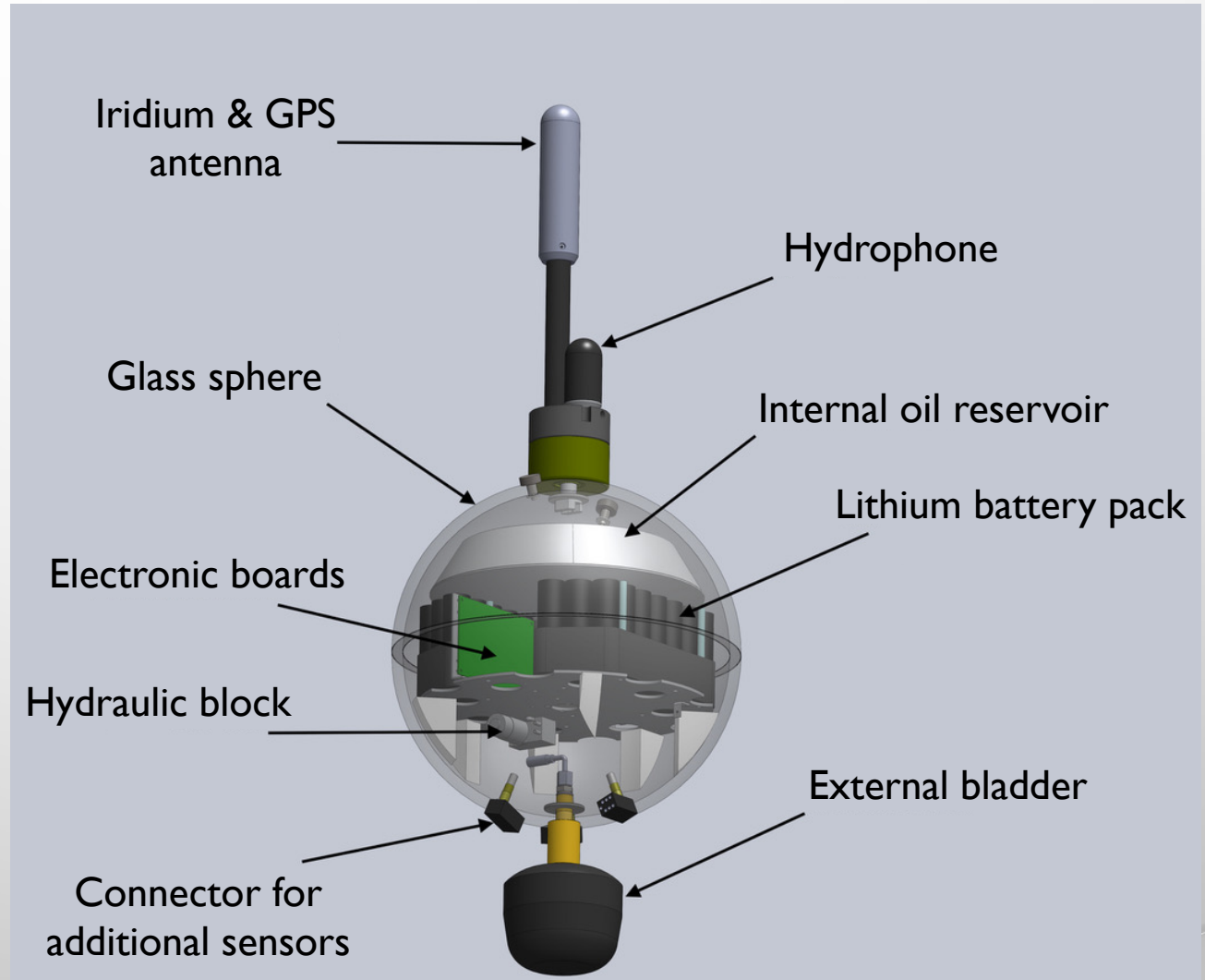
Stefan Kildal-Brandt | Terance Schuh | Thalia Gueroult

Princeton University | DBV Technology | Ensta Bretagne



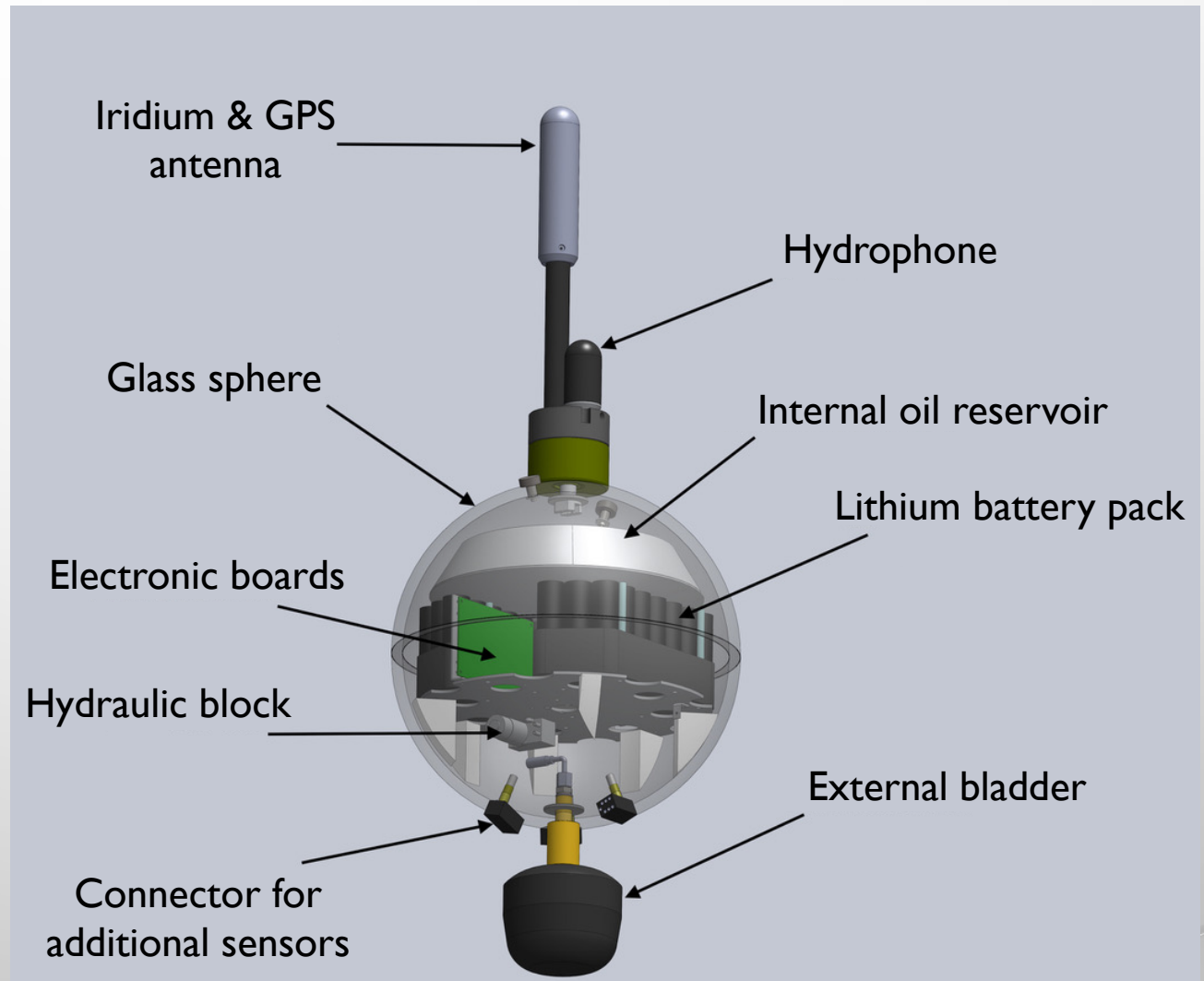
# BEFORE WE BEGIN...

- THIS IS *NOT* A **MERMAID** TALK...



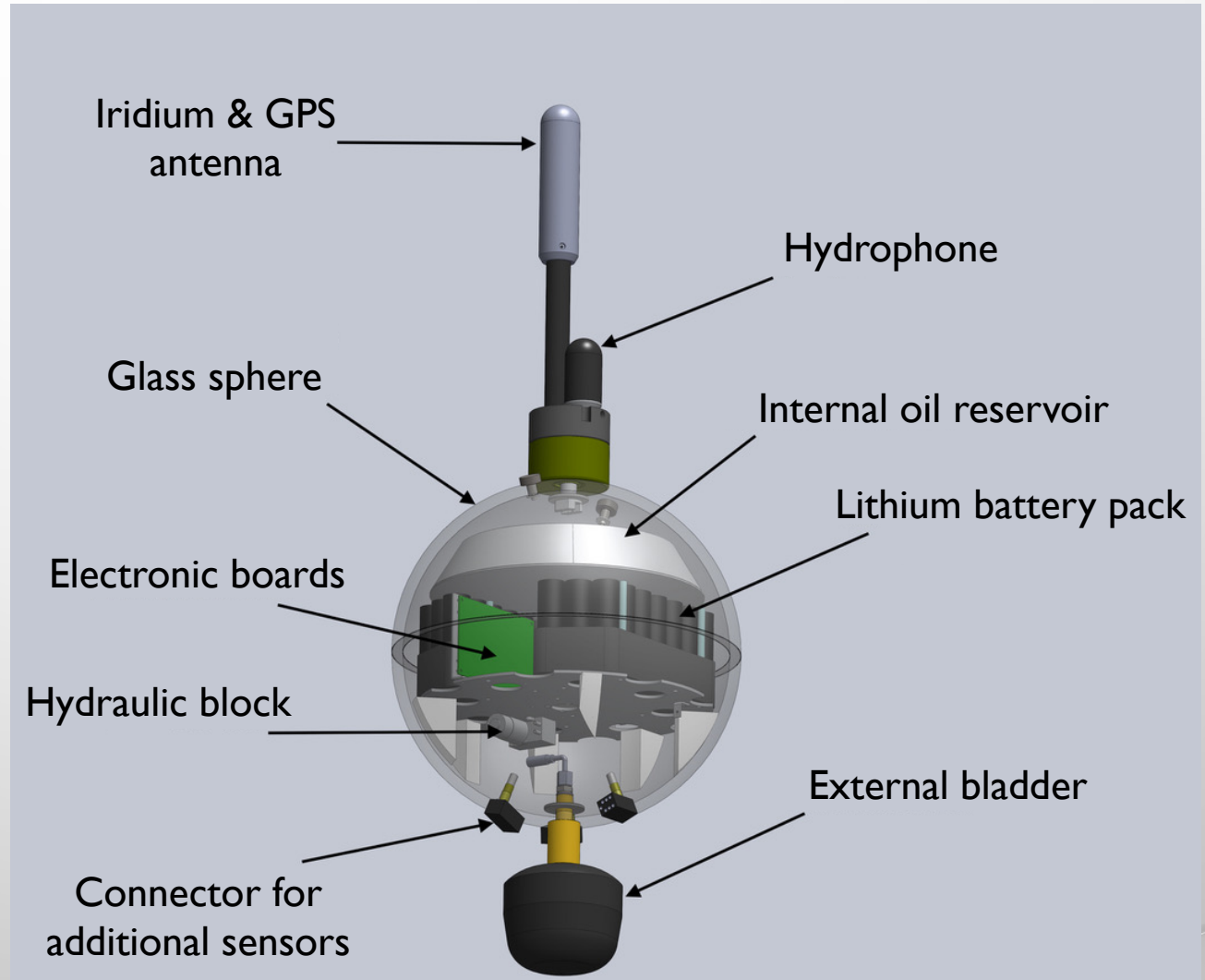
# BEFORE WE BEGIN...

- THIS IS *NOT* A **MERMAID** TALK...
- BUT YOU SHOULD KNOW THAT:



# BEFORE WE BEGIN...

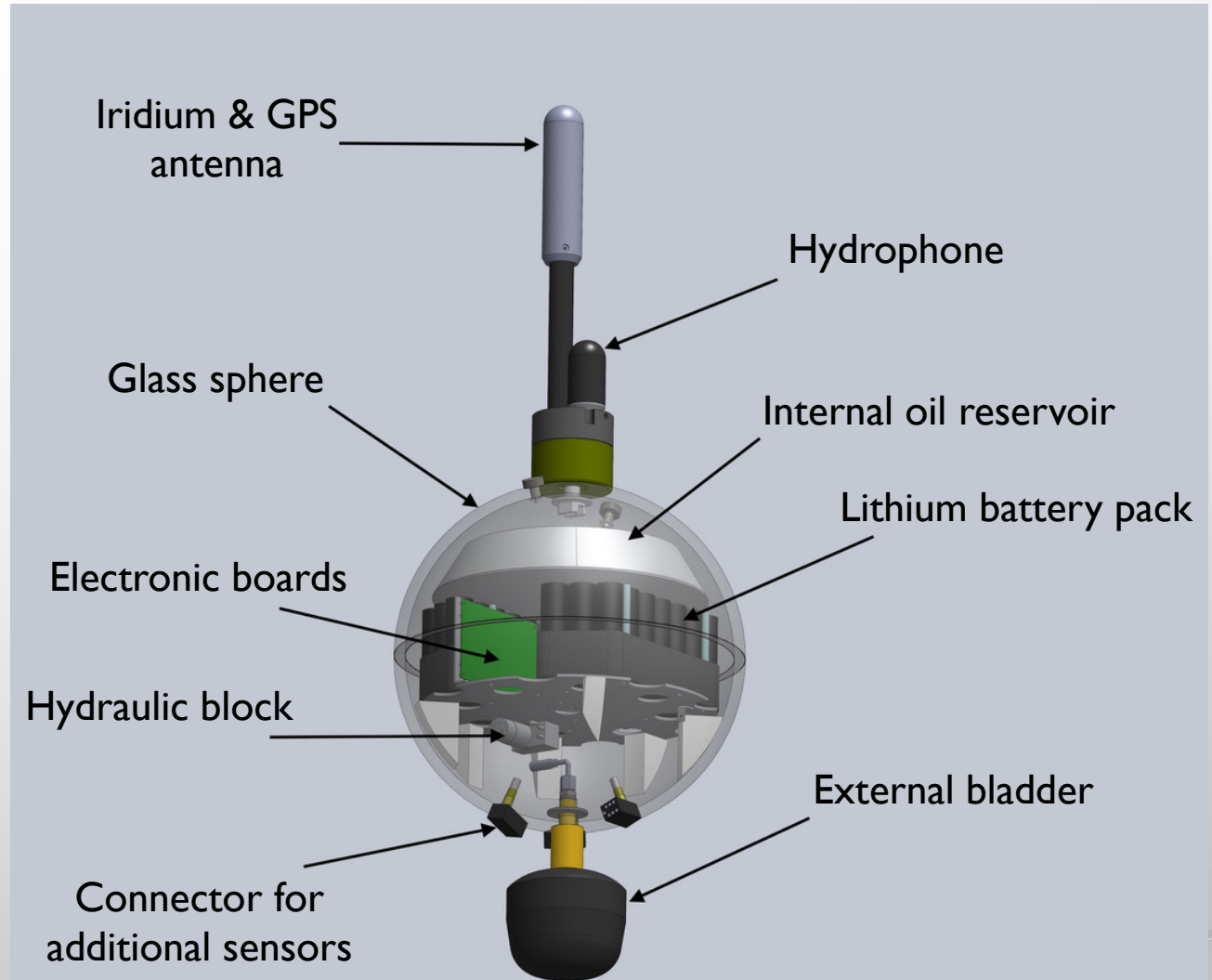
- THIS IS *NOT* A **MERMAID** TALK...
- BUT YOU SHOULD KNOW THAT:
  - MERMAID IS A FLOATING HYDROPHONE FOR QUAKES





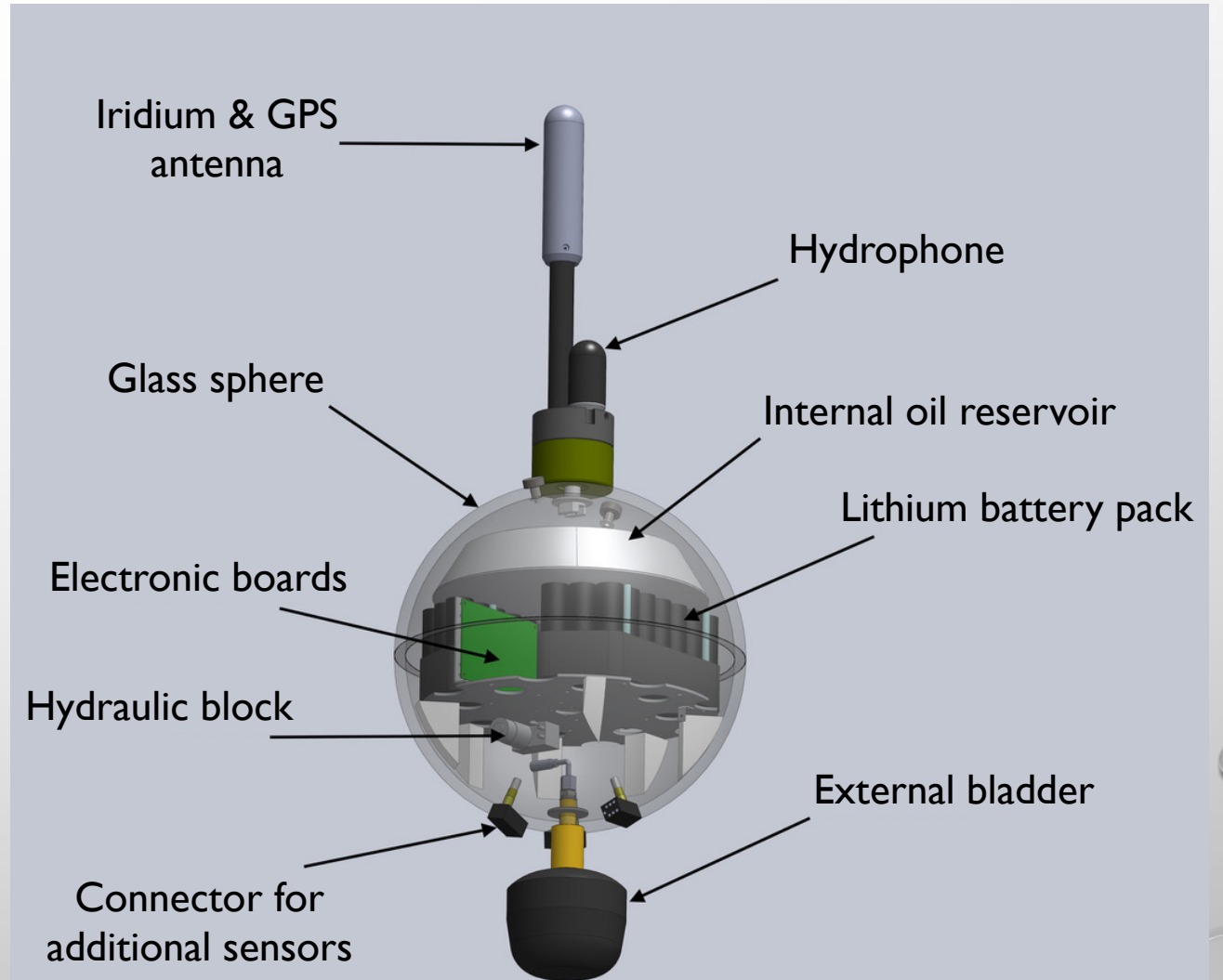
# BEFORE WE BEGIN...

- THIS IS *NOT* A **MERMAID** TALK...
- BUT YOU SHOULD KNOW THAT:
  - MERMAID IS A FLOATING HYDROPHONE FOR QUAKES
  - 75 MERMAIDS HAVE BEEN LAUNCHED WORLDWIDE



# BEFORE WE BEGIN...

- THIS IS *NOT* A **MERMAID** TALK...
- BUT YOU SHOULD KNOW THAT:
  - MERMAID IS A FLOATING HYDROPHONE FOR QUAKES
  - 75 MERMAIDS HAVE BEEN LAUNCHED WORLDWIDE
  - MERMAID-III FLOATS AT 2,000 M DEPTH



# BEFORE WE BEGIN...

- THIS IS *NOT* A **MERMAID** TALK...
- BUT YOU SHOULD KNOW THAT:
  - MERMAID IS A FLOATING HYDROPHONE FOR QUAKES
  - 75 MERMAIDS HAVE BEEN LAUNCHED WORLDWIDE
  - MERMAID-III FLOATS AT 2,000 M DEPTH



# BEFORE WE BEGIN...

- THIS IS *NOT* A **MERMAID** TALK...
- BUT YOU SHOULD KNOW THAT:
  - MERMAID IS A FLOATING HYDROPHONE FOR QUAKES
  - 75 MERMAIDS HAVE BEEN LAUNCHED WORLDWIDE
  - MERMAID-III FLOATS AT 2,000 M DEPTH
  - MERMAID-IV PROFILES CTD AT 4,000 M DEPTH



# BEFORE WE BEGIN...

- THIS IS *NOT* A **MERMAID** TALK...
- BUT YOU SHOULD KNOW THAT:
  - MERMAID IS A FLOATING HYDROPHONE FOR QUAKES
  - 75 MERMAIDS HAVE BEEN LAUNCHED WORLDWIDE
  - MERMAID-III FLOATS AT 2,000 M DEPTH
  - MERMAID-IV PROFILES CTD AT 4,000 M DEPTH





# BEFORE WE BEGIN...

- THIS IS *NOT* A **MERMAID** TALK...
- BUT YOU SHOULD KNOW THAT:
  - MERMAID IS A FLOATING HYDROPHONE FOR QUAKES
  - 75 MERMAIDS HAVE BEEN LAUNCHED WORLDWIDE
  - MERMAID-III FLOATS AT 2,000 M DEPTH
  - MERMAID-IV PROFILES CTD AT 4,000 M DEPTH
  - MERMAID-V WILL DIVE AND LAND AT 6,000 M DEPTH



# END OF MERMAID PRELUDE





# One-Way Underwater Geodetic Positioning



# One-Way Underwater Geodetic Positioning

- Autonomous Surface Vessel (ASV)

# One-Way Underwater Geodetic Positioning

- Autonomous Surface Vessel (ASV)





# One-Way Underwater Geodetic Positioning

- Autonomous Surface Vessel (ASV)
- 4 GPS receivers with  $\sim 2$  cm precise point positioning uncertainty





# One-Way Underwater Geodetic Positioning

- Autonomous Surface Vessel (ASV)
- 4 GPS receivers with  $\sim 2$  cm precise point positioning uncertainty





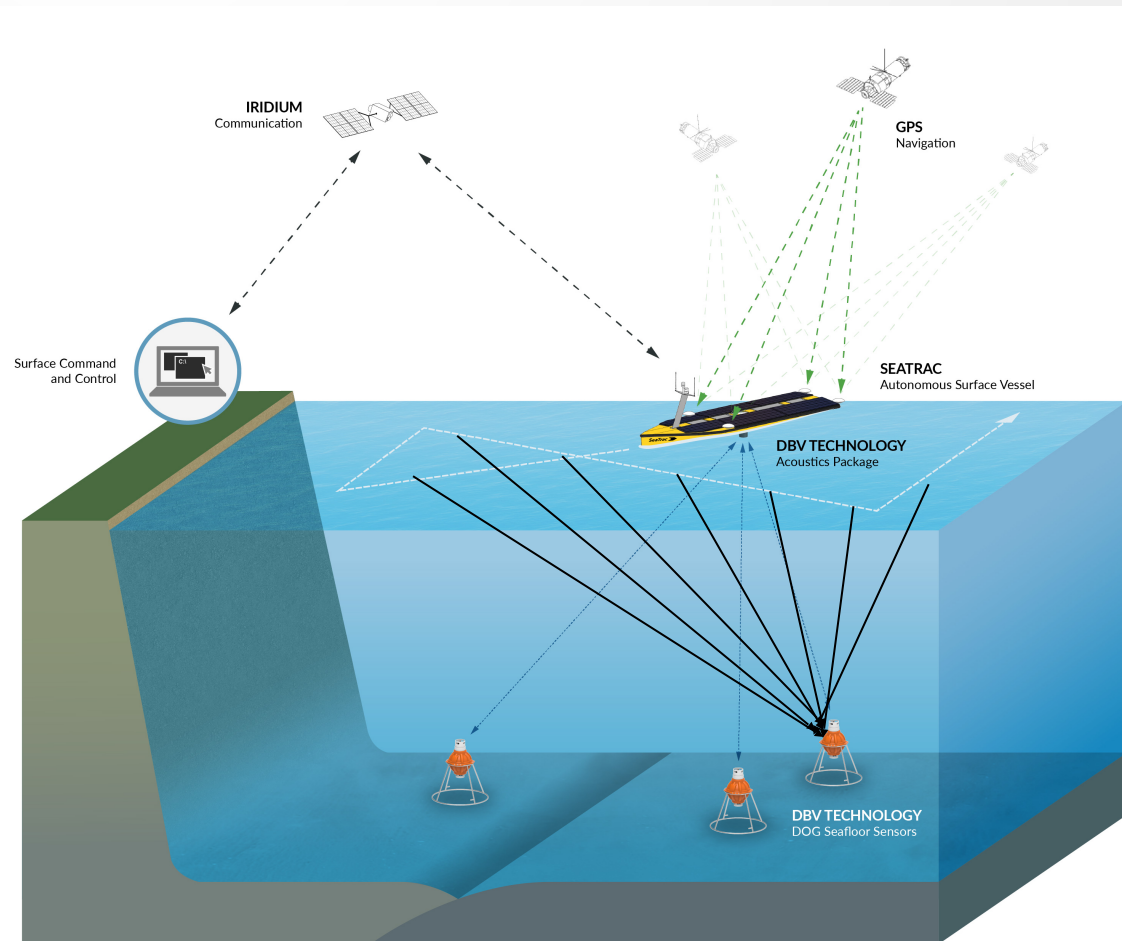
# One-Way Underwater Geodetic Positioning

- Autonomous Surface Vessel (ASV)
- 4 GPS receivers with **~2 cm** precise point positioning uncertainty
- Trajectory covered by ASV with acoustic pulses emitted at 1 Hz



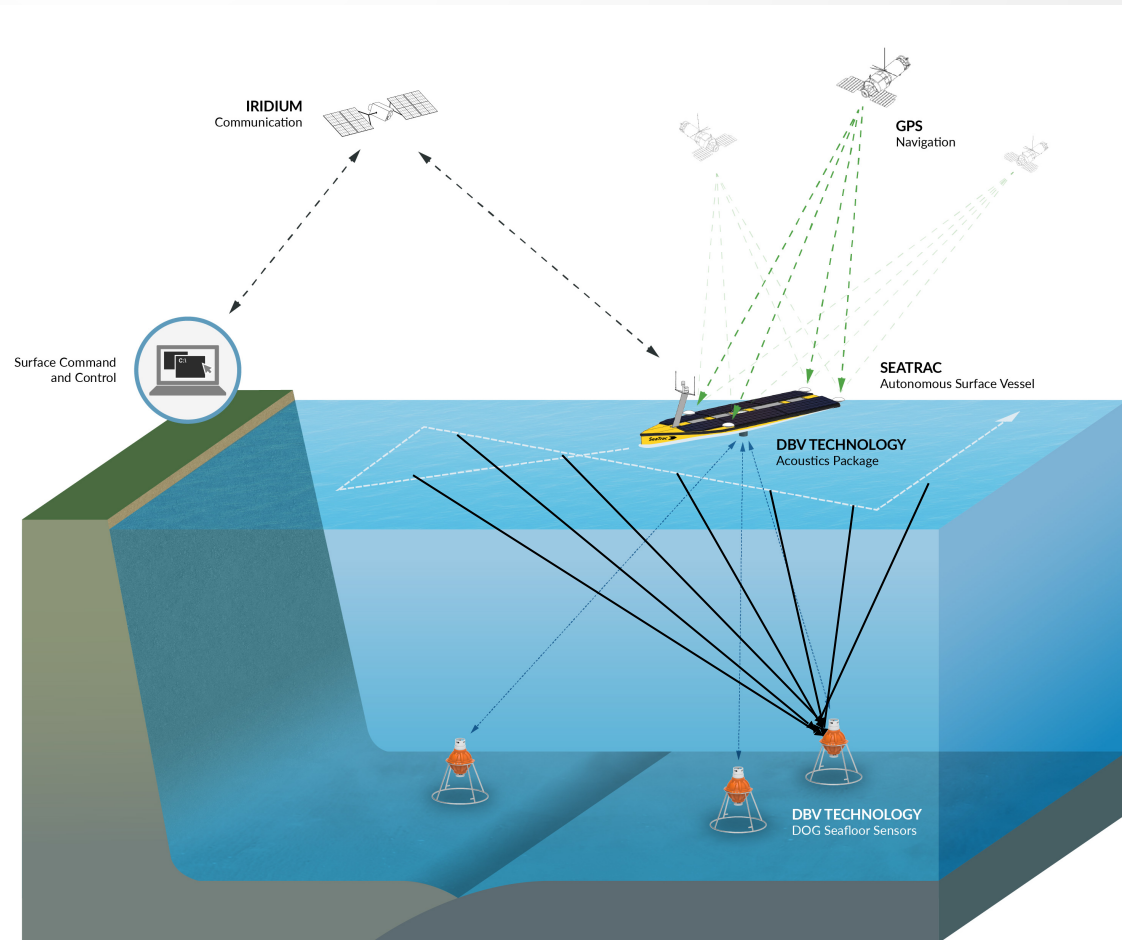
# One-Way Underwater Geodetic Positioning

- Autonomous Surface Vessel (ASV)
- 4 GPS receivers with **~2 cm** precise point positioning uncertainty
- Trajectory covered by ASV with acoustic pulses emitted at 1 Hz



# One-Way Underwater Geodetic Positioning

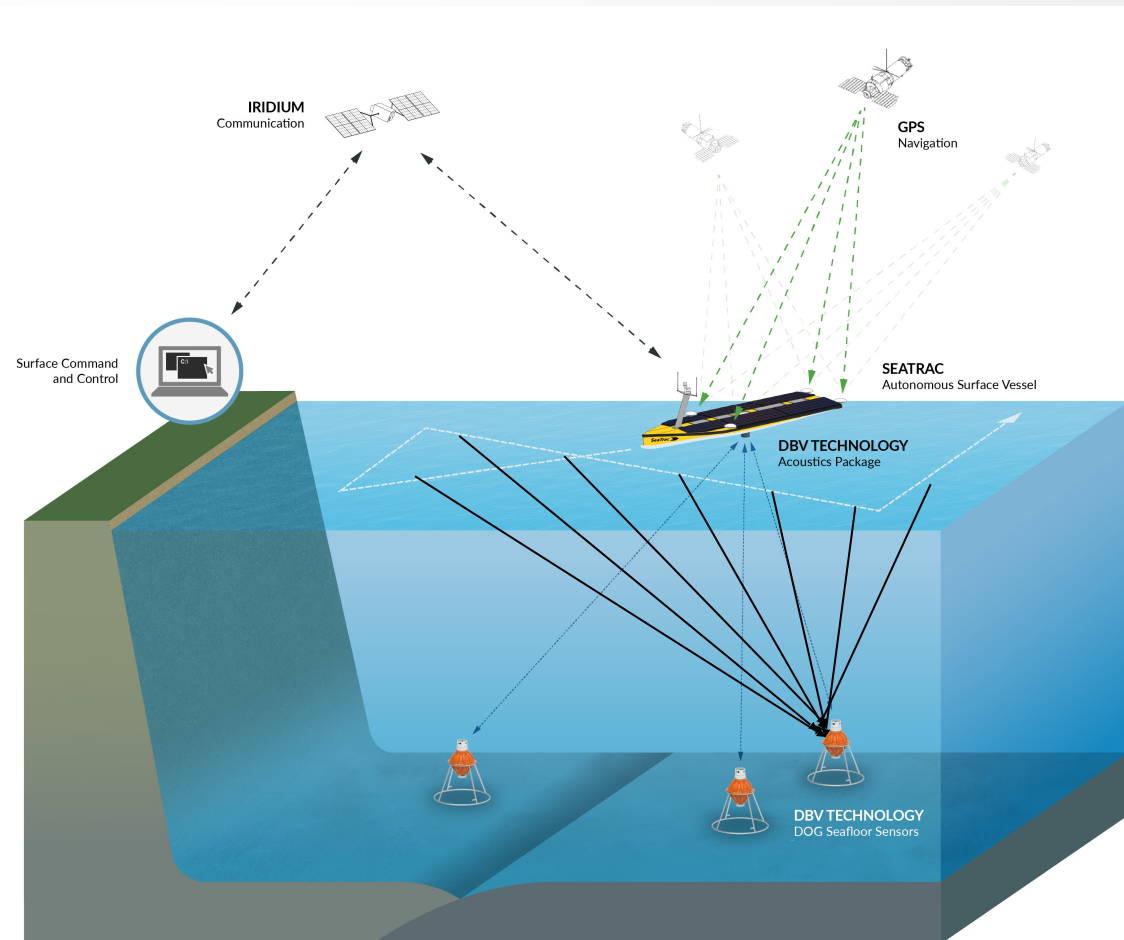
- Autonomous Surface Vessel (ASV)
- 4 GPS receivers with **~2 cm** precise point positioning uncertainty
- Trajectory covered by ASV with acoustic pulses emitted at 1 Hz
- Continuously operating deep ocean geodetic sensor (C-DOG)





# One-Way Underwater Geodetic Positioning

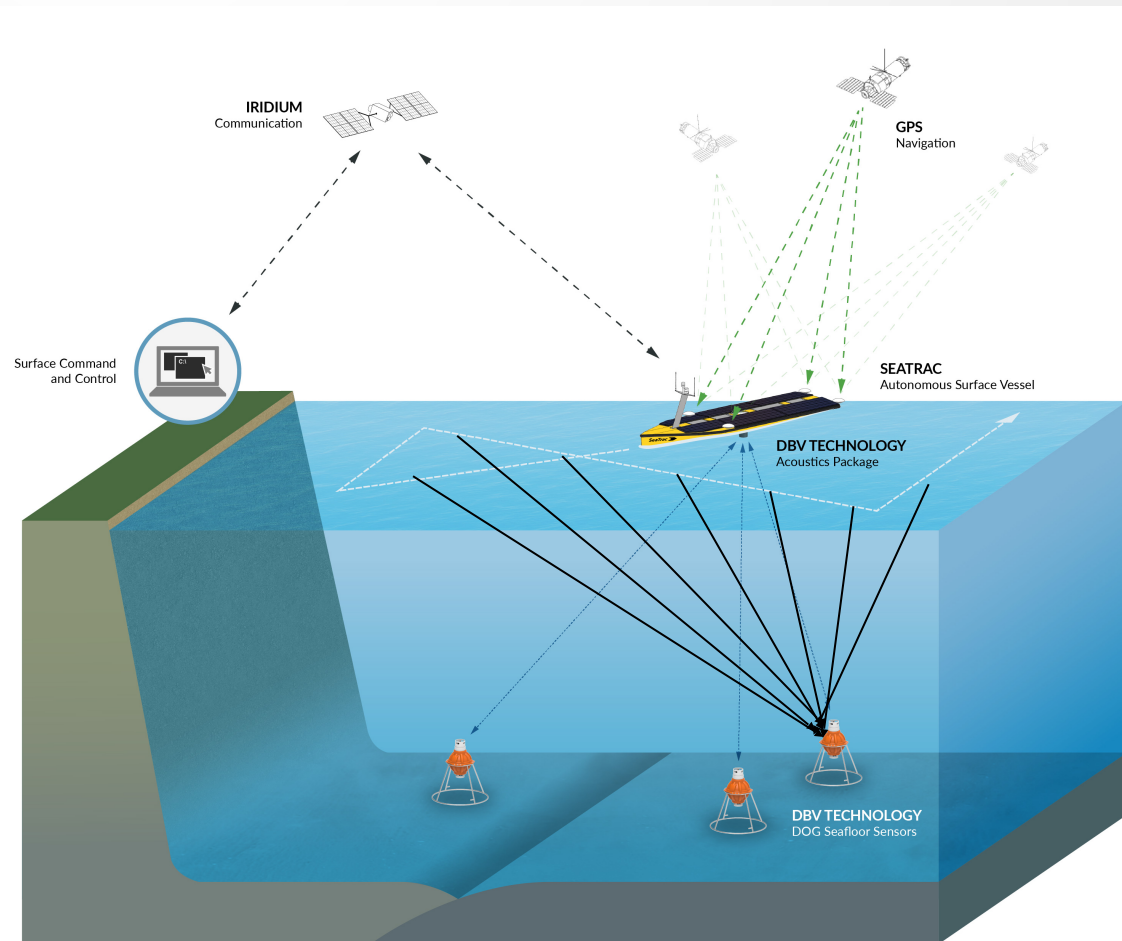
- Autonomous Surface Vessel (ASV)
- 4 GPS receivers with **~2 cm** precise point positioning uncertainty
- Trajectory covered by ASV with acoustic pulses emitted at 1 Hz
- Continuously operating deep ocean geodetic sensor (C-DOG)
- Modem to transport arrival time data from seafloor to surface





# One-Way Underwater Geodetic Positioning

- Autonomous Surface Vessel (ASV)
- 4 GPS receivers with **~2 cm** precise point positioning uncertainty
- Trajectory covered by ASV with acoustic pulses emitted at 1 Hz
- Continuously operating deep ocean geodetic sensor (C-DOG)
- Modem to transport arrival time data from seafloor to surface



# One-Way Underwater Geodetic Positioning

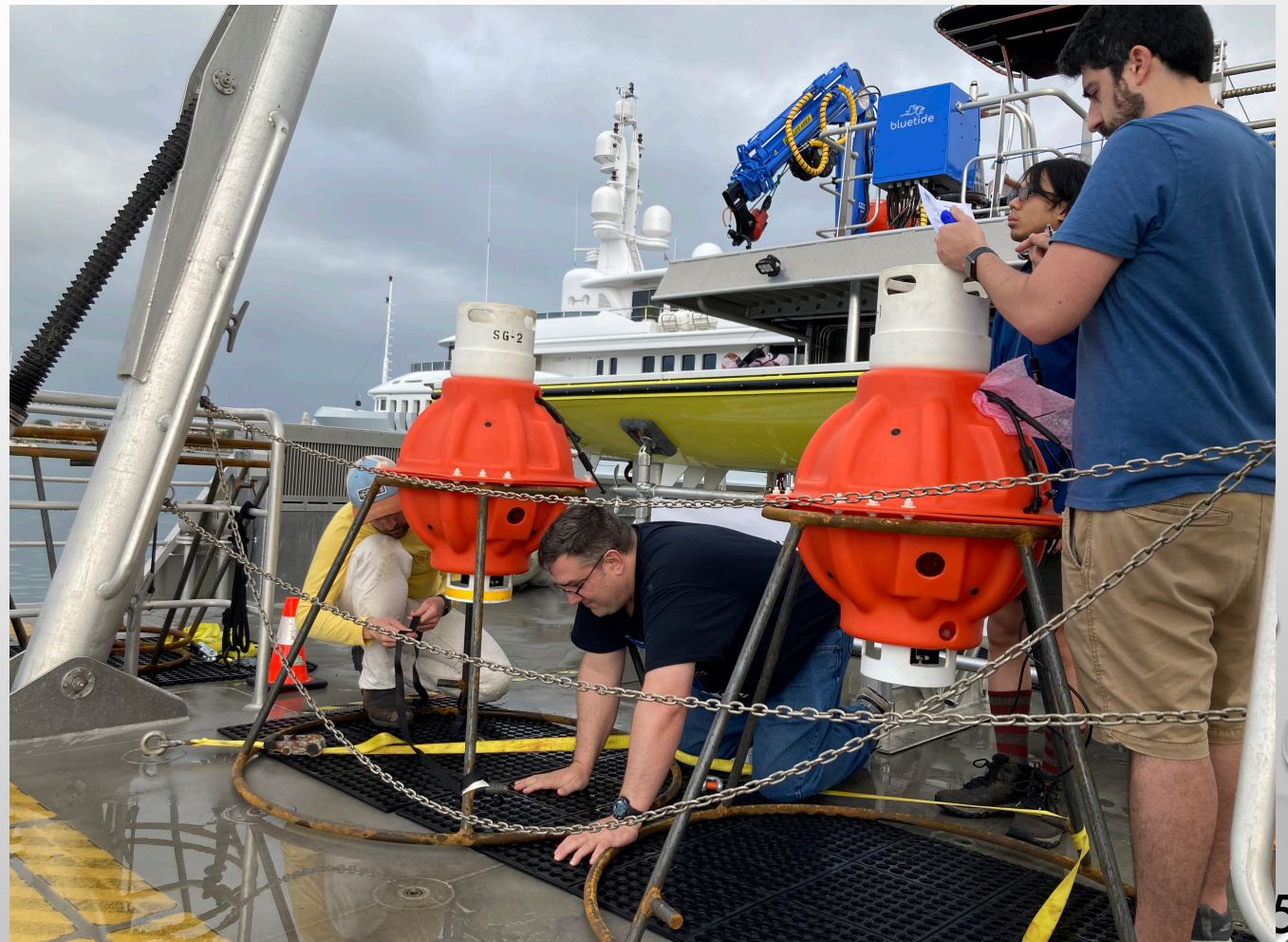
- Autonomous Surface Vessel (ASV)
- 4 GPS receivers with **~2 cm** precise point positioning uncertainty
- Trajectory covered by ASV with acoustic pulses emitted at 1 Hz
- Continuously operating deep ocean geodetic sensor (C-DOG)
- Modem to transport arrival time data from seafloor to surface





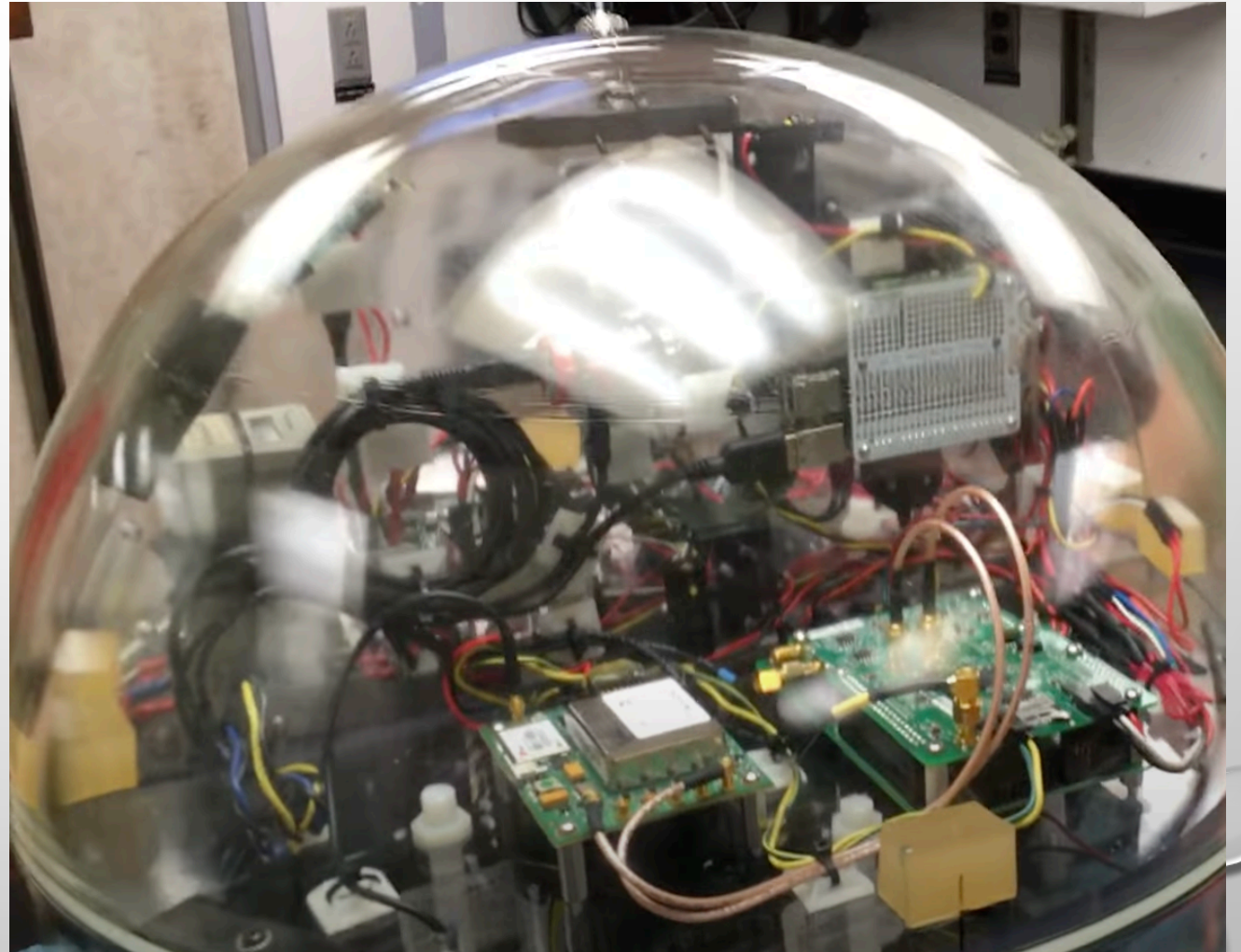
# One-Way Underwater Geodetic Positioning

- Autonomous Surface Vessel (ASV)
- 4 GPS receivers with **~2 cm** precise point positioning uncertainty
- Trajectory covered by ASV with acoustic pulses emitted at 1 Hz
- Continuously operating deep ocean geodetic sensor (C-DOG)
- Modem to transport arrival time data from seafloor to surface
- **Locating the C-DOG is the objective**



# C-DOG Components

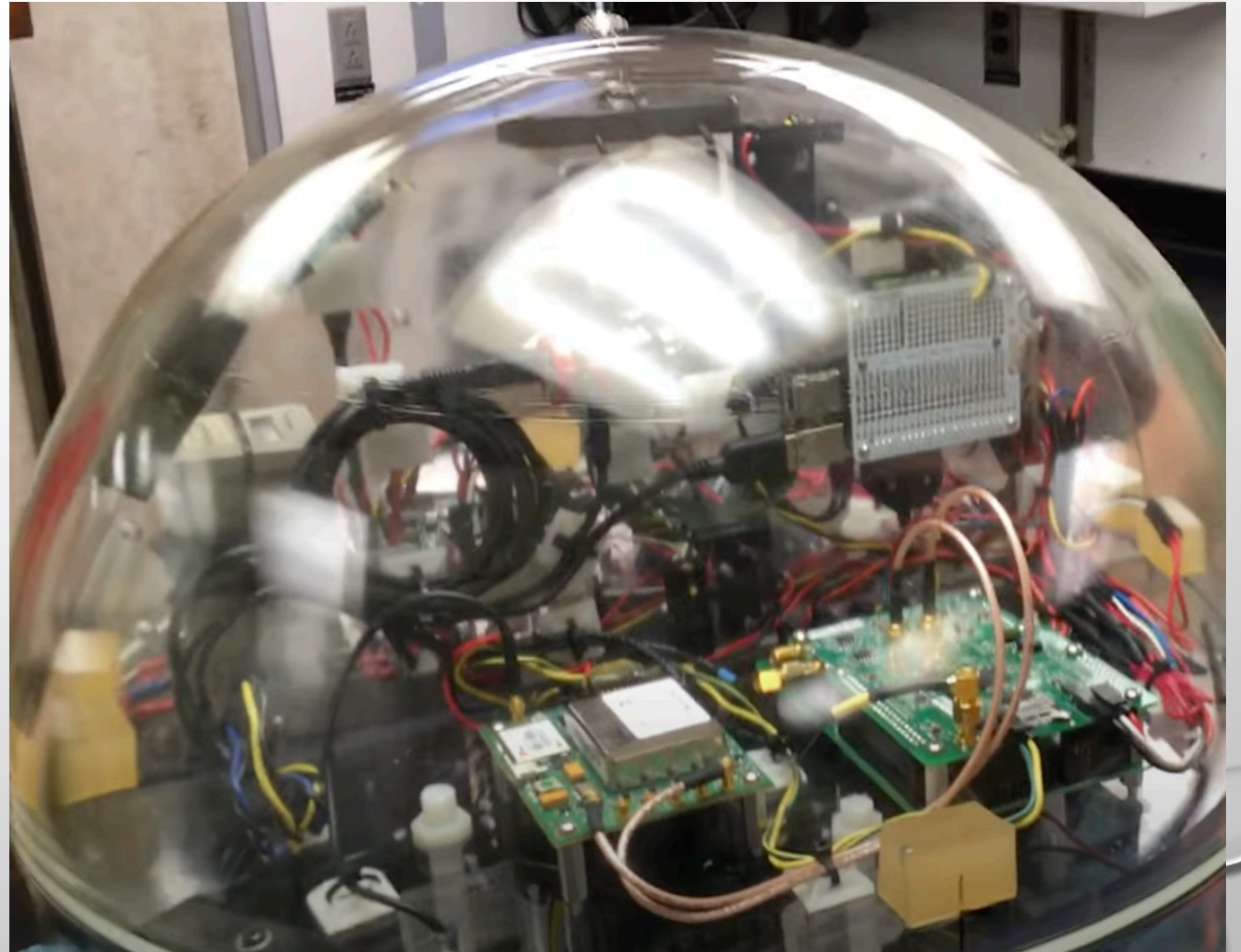
- Sphere rated for depths of **6000 m**





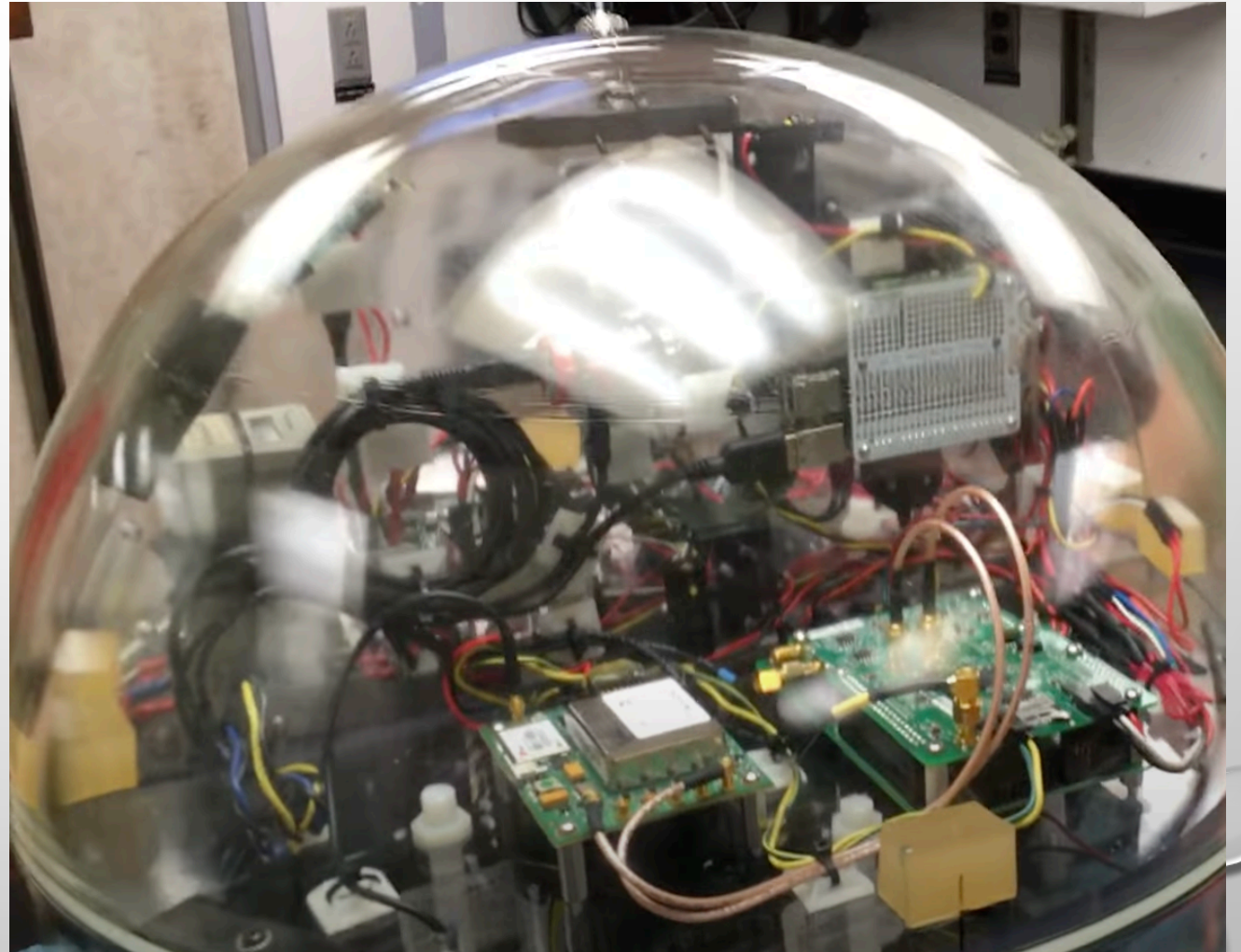
# C-DOG Components

- Sphere rated for depths of **6000 m**
- Extremely low power nanosecond chip-scale atomic clock (CSAC)



# C-DOG Components

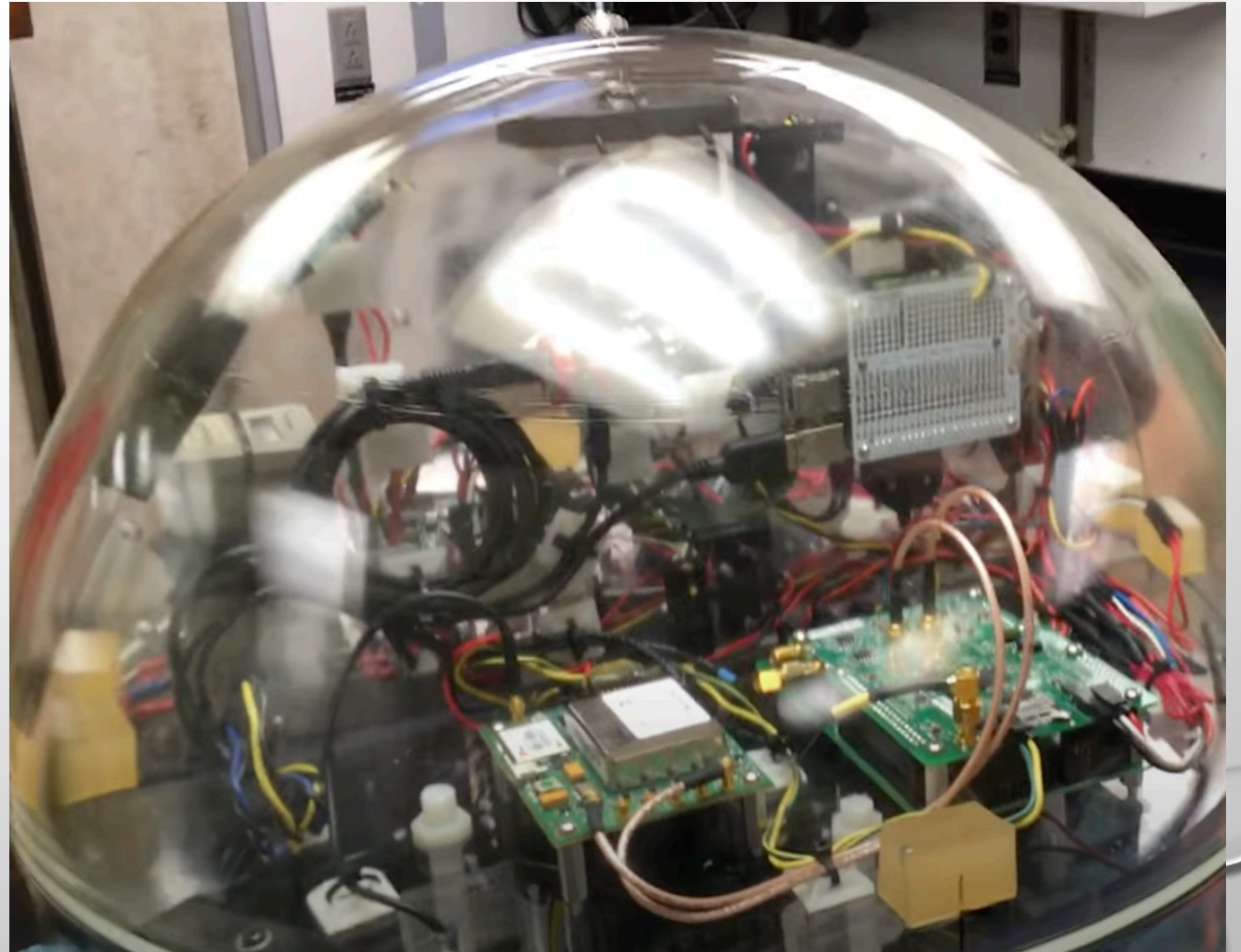
- Sphere rated for depths of **6000 m**
- Extremely low power nanosecond chip-scale atomic clock (CSAC)
- Hydrophone and correlator unit to detect encoded pulses and time-tag them to an uncertainty of **20  $\mu$ s**





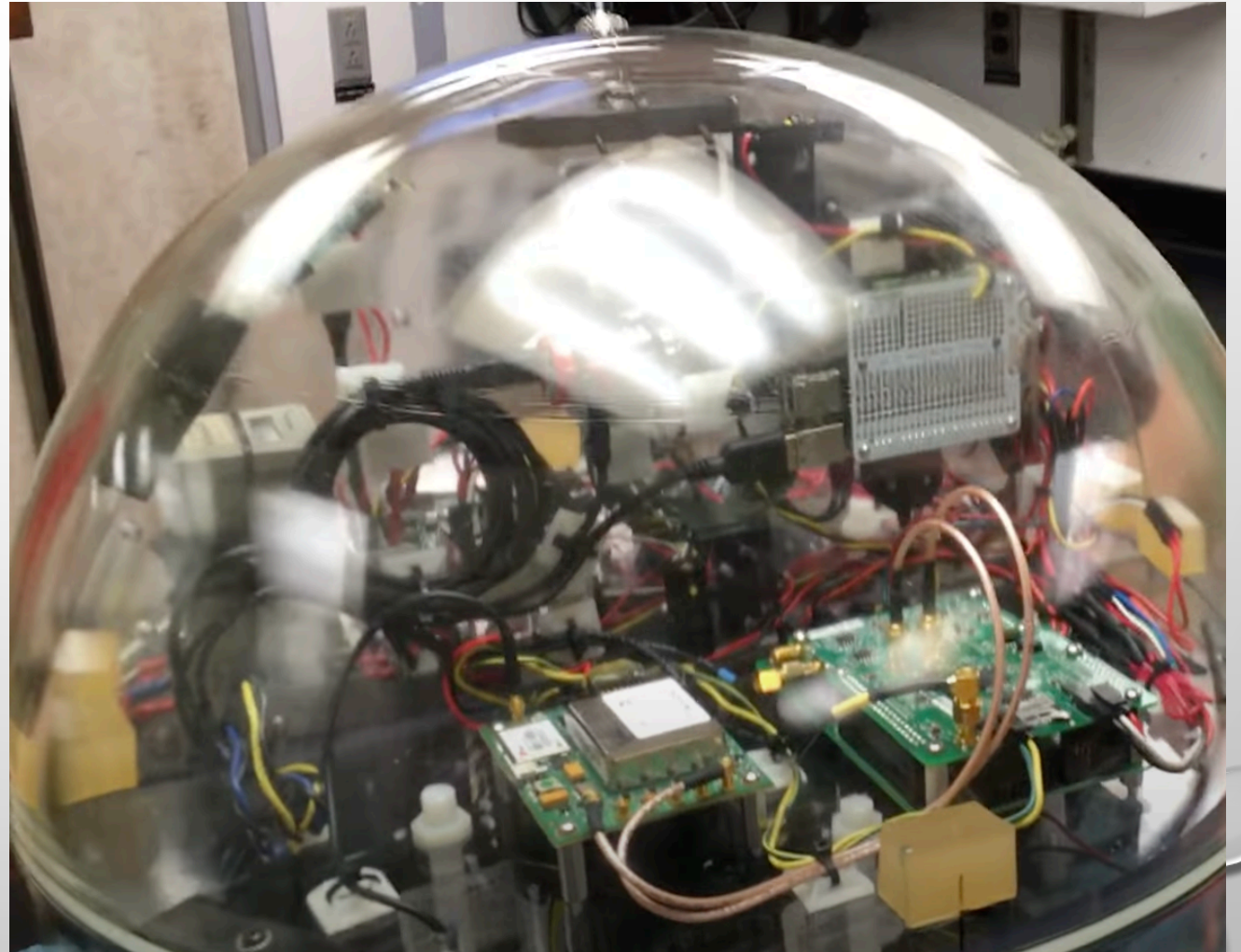
# C-DOG Components

- Sphere rated for depths of **6000 m**
- Extremely low power nanosecond chip-scale atomic clock (CSAC)
- Hydrophone and correlator unit to detect encoded pulses and time-tag them to an uncertainty of **20  $\mu$ s**
- Modem to transport arrival time data from seafloor to surface



# C-DOG Components

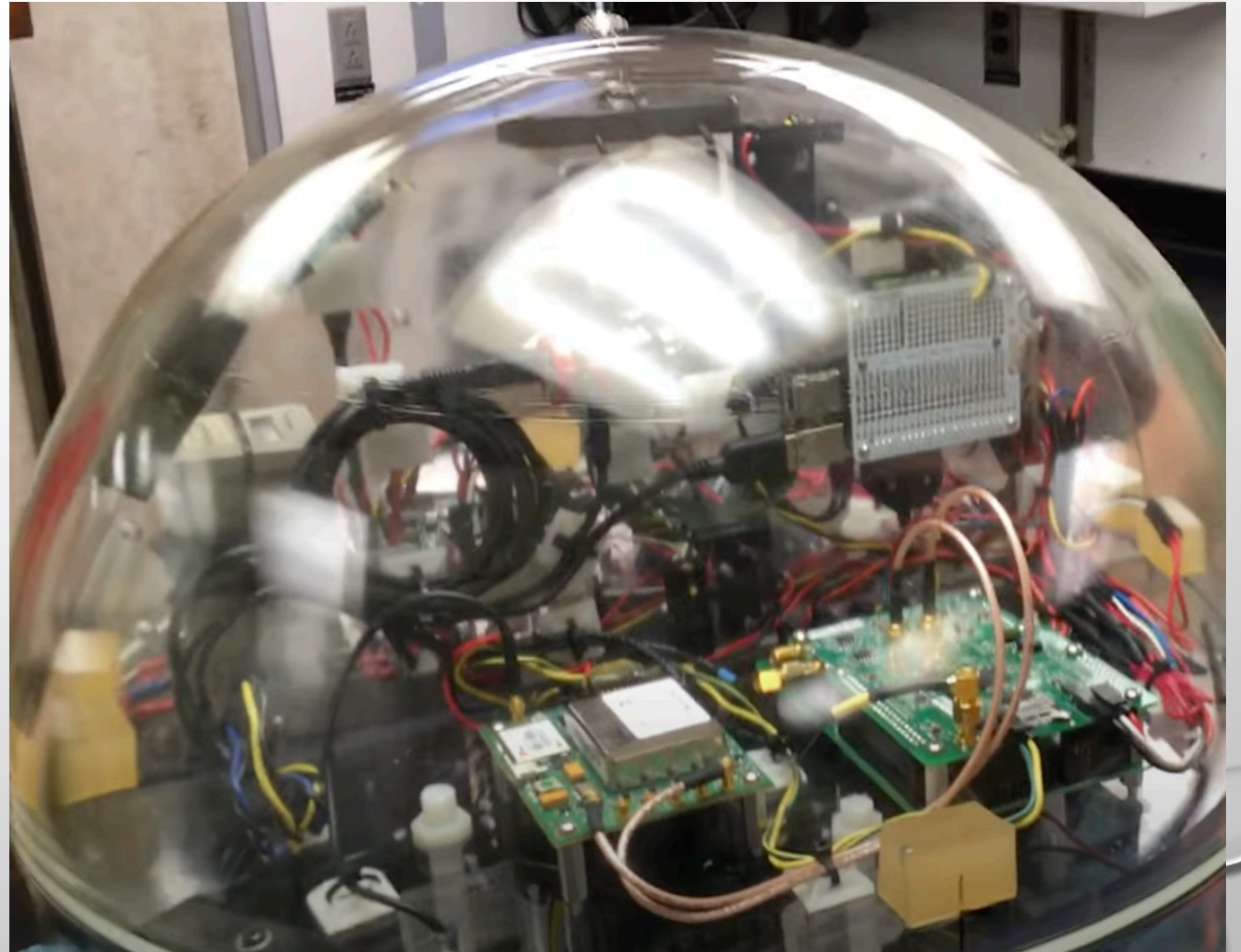
- Sphere rated for depths of **6000 m**
- Extremely low power nanosecond chip-scale atomic clock (CSAC)
- Hydrophone and correlator unit to detect encoded pulses and time-tag them to an uncertainty of **20  $\mu$ s**
- Modem to transport arrival time data from seafloor to surface
- Battery capable of powering long-term deployments





# C-DOG Components

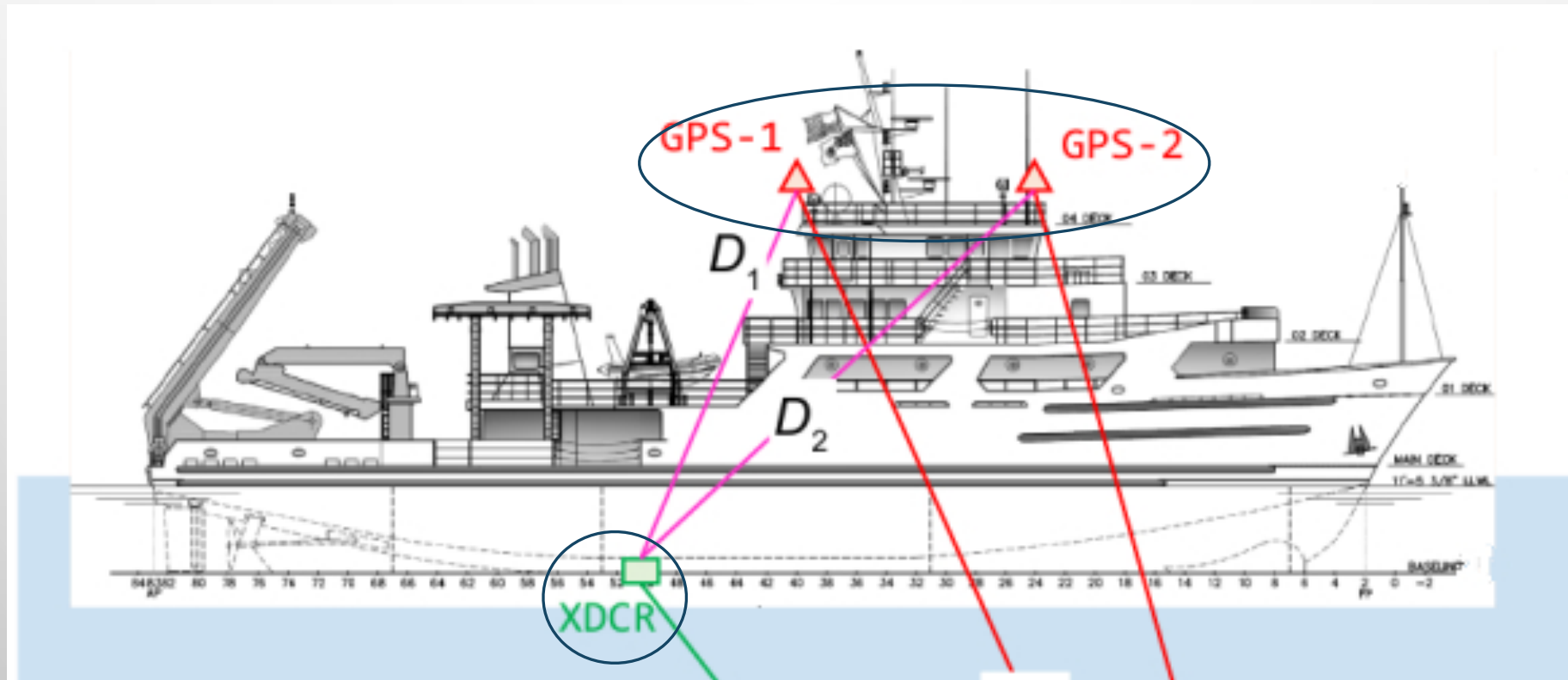
- Sphere rated for depths of **6000 m**
- Extremely low power nanosecond chip-scale atomic clock (CSAC)
- Hydrophone and correlator unit to detect encoded pulses and time-tag them to an uncertainty of **20  $\mu$ s**
- Modem to transport arrival time data from seafloor to surface
- Battery capable of powering long-term deployments
- C-DOG can be put to sleep to lengthen lifespan – decades



Even without an ASV...

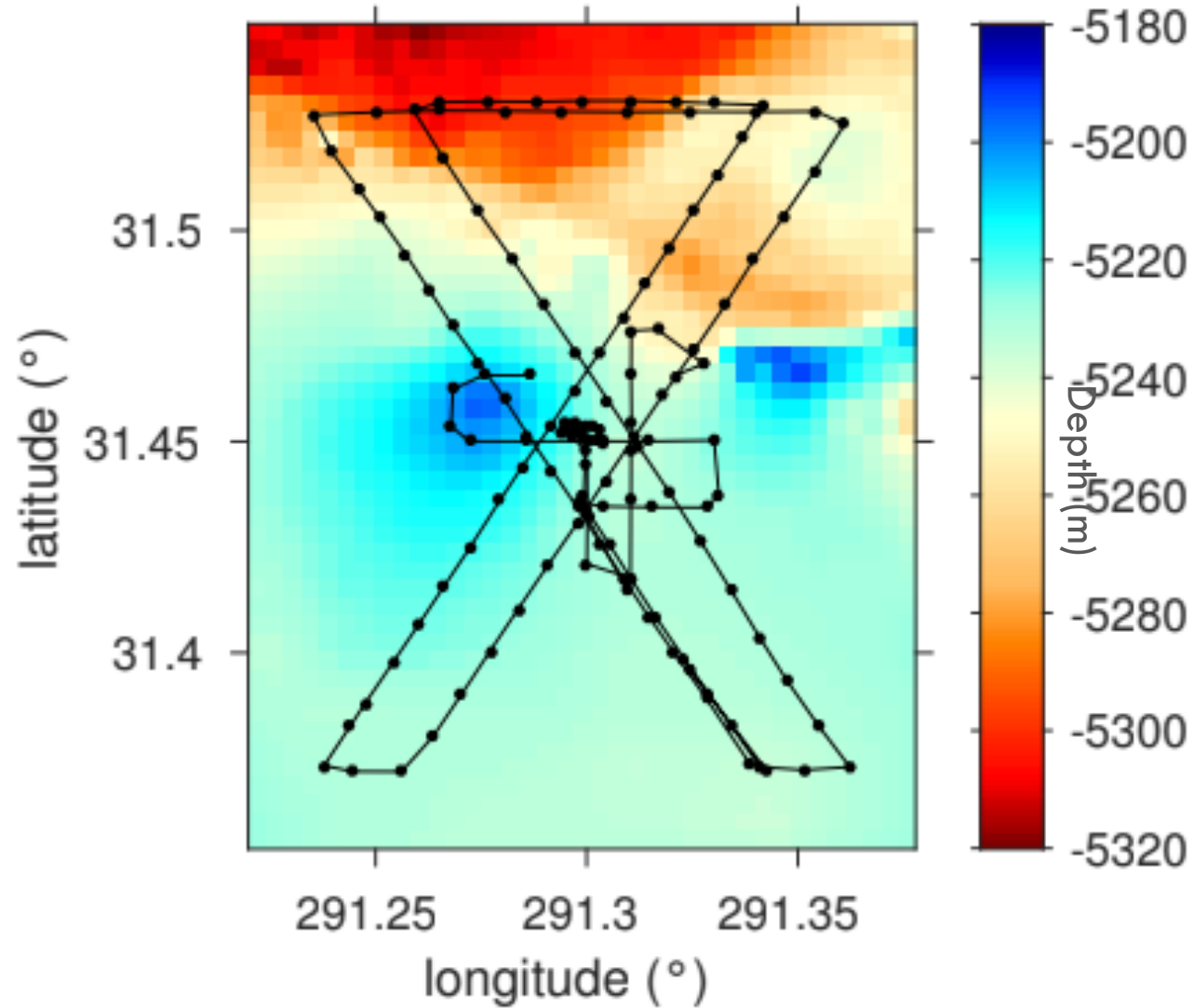


# Even without an ASV...

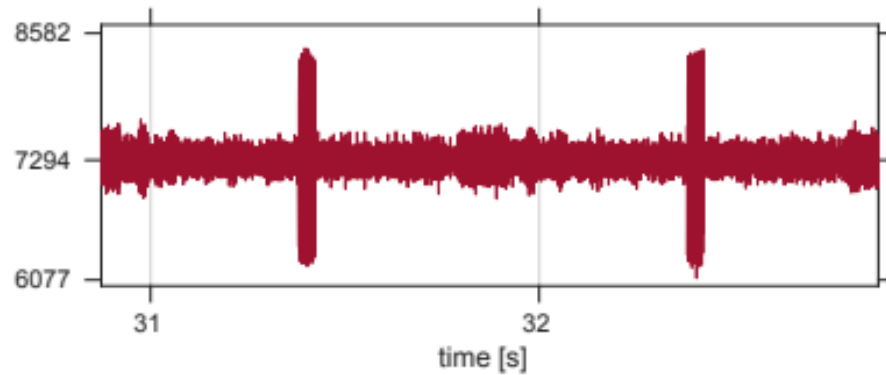
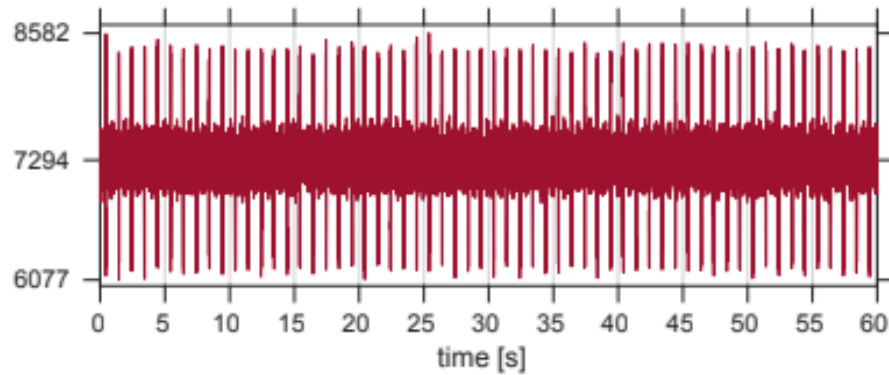




# An experiment in 5000 m water

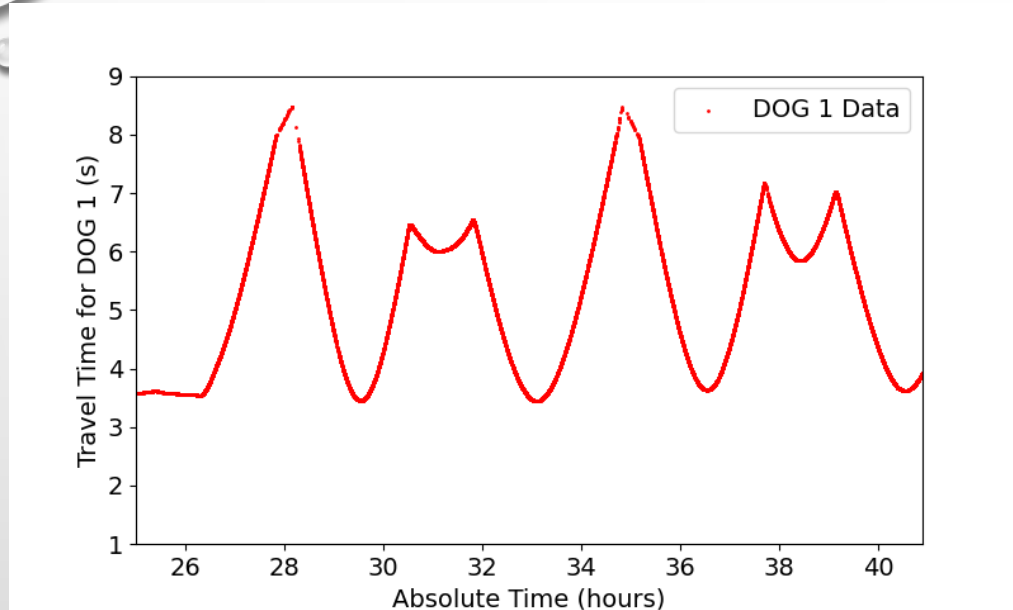


# C-DOG Data Collected in Situ

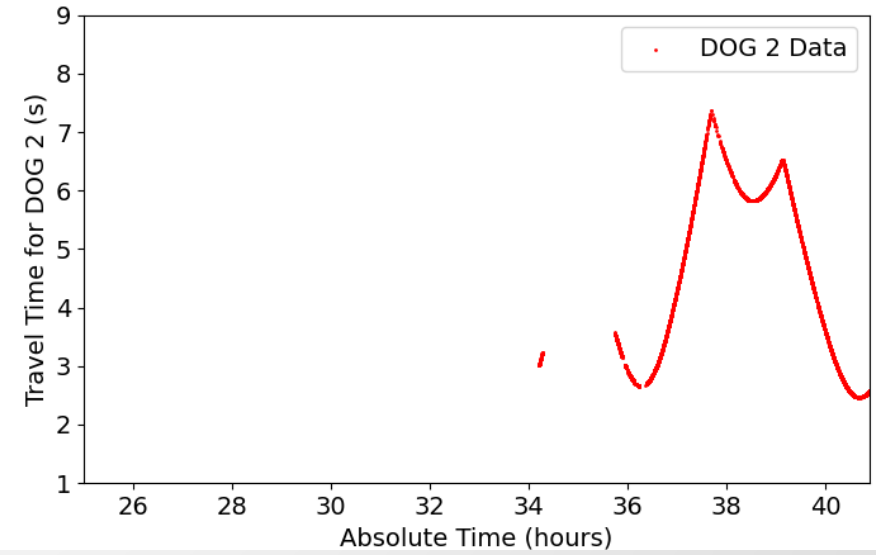
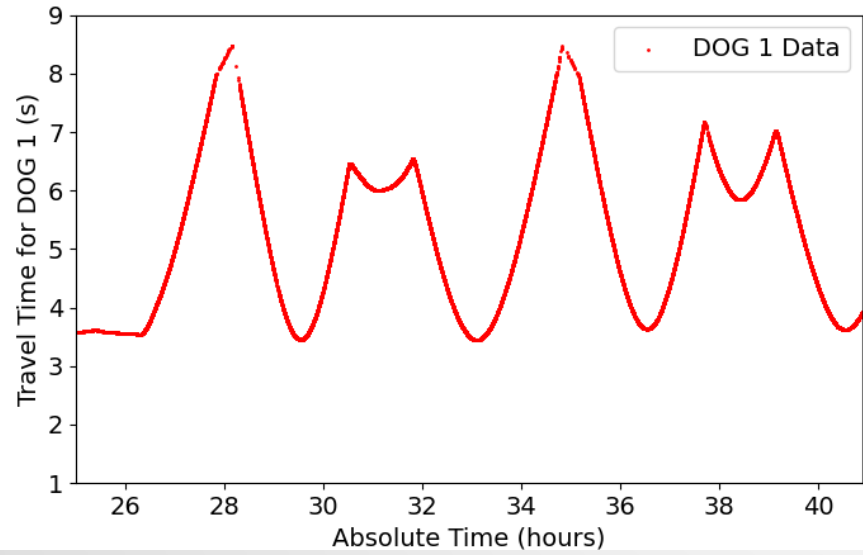


- Experiment performed in **5000 m** water
- Time series of acoustic data observed by hydrophone on C-DOG
- On-board correlator time-stamps arrivals against the CSAC atomic clock
- Timing uncertainty of  $\sim 20 \mu\text{s}$

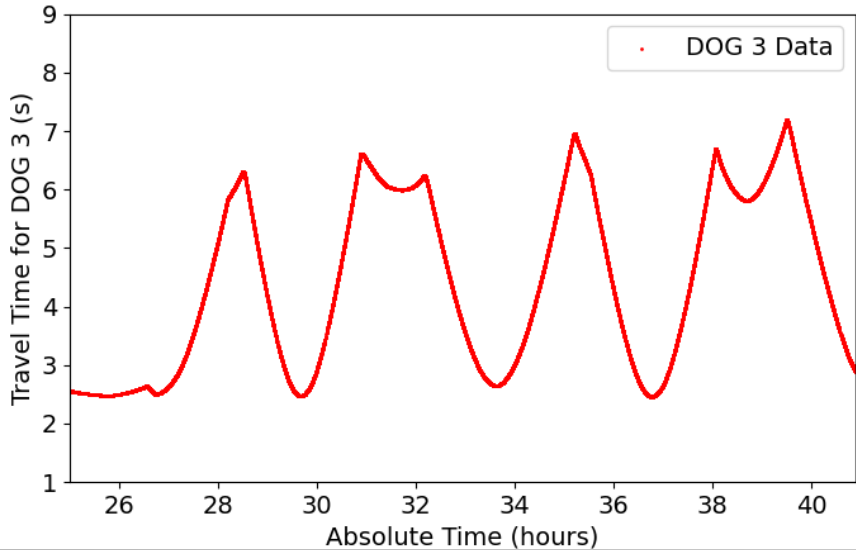
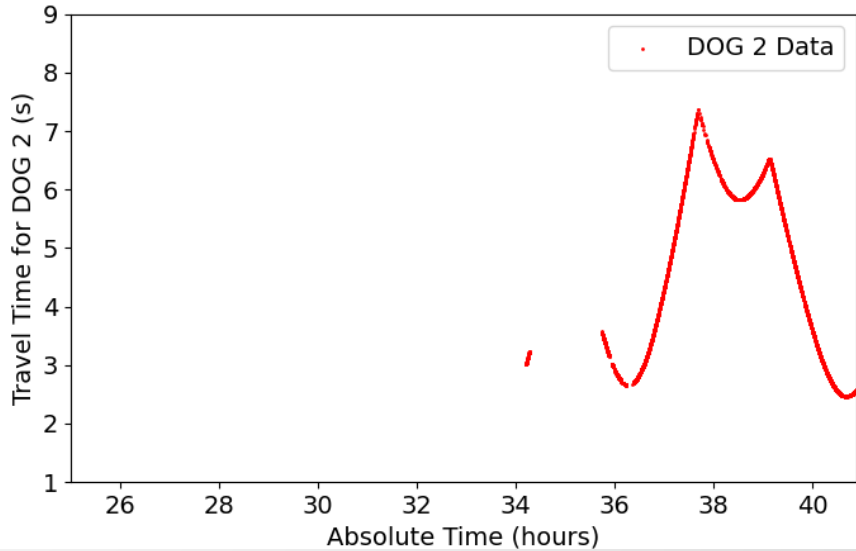
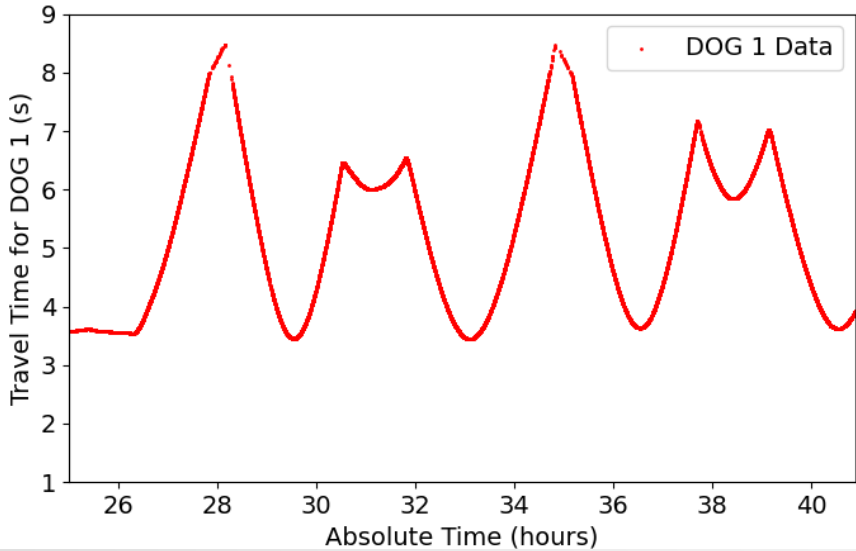
# C-DOG Data Collected in Situ



# C-DOG Data Collected in Situ

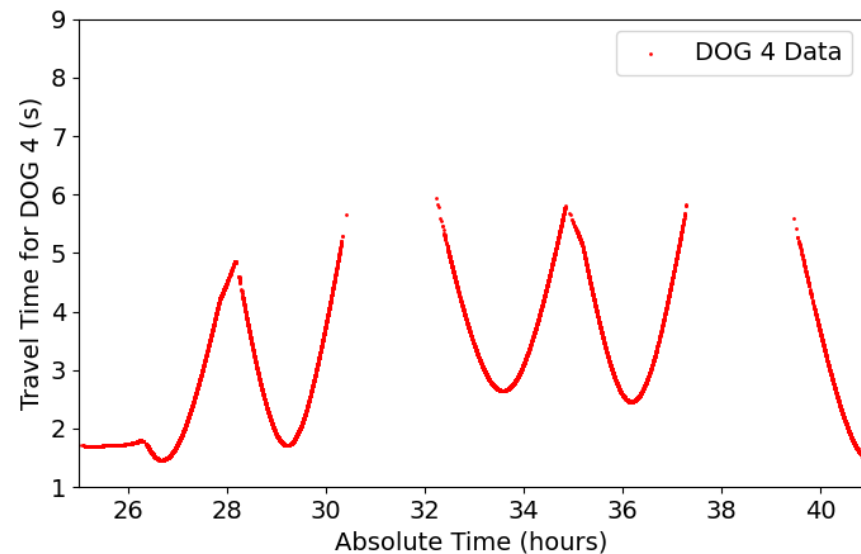
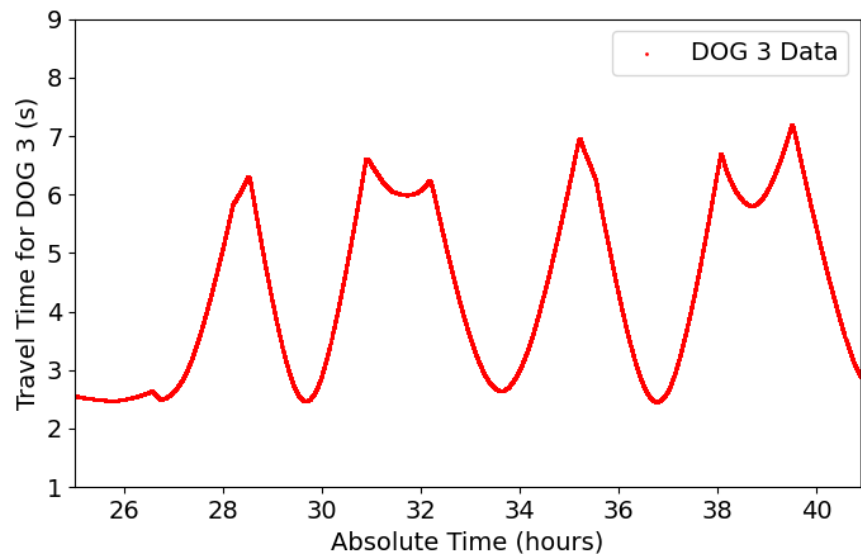
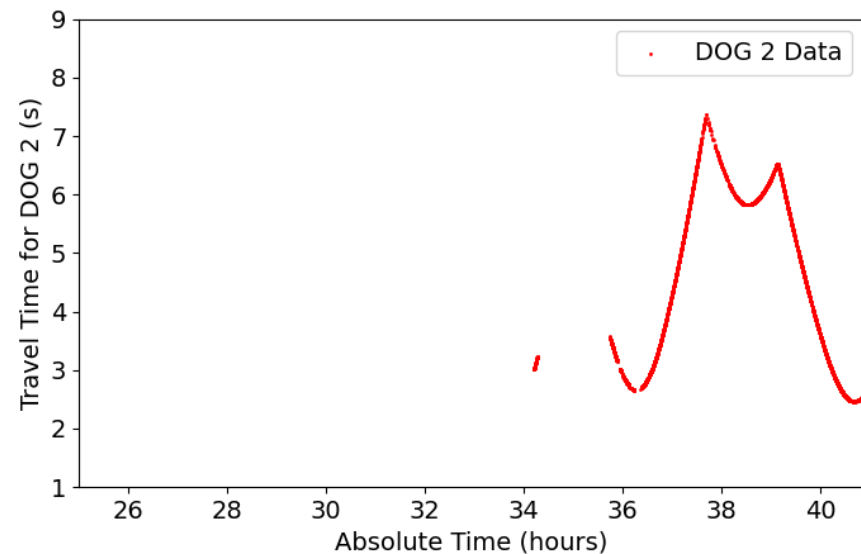
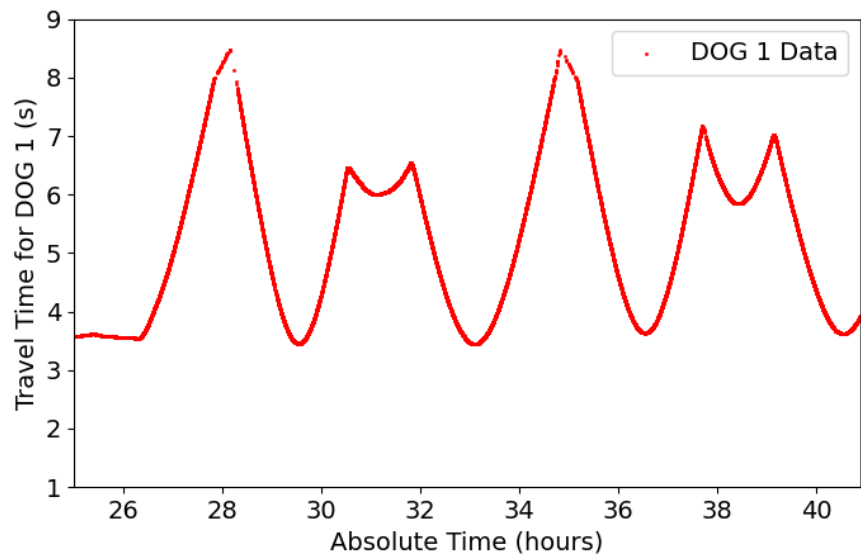


# C-DOG Data Collected in Situ





# C-DOG Data Collected in Situ



# Problems

# Problems

- The C-DOG position is unknown and the parameter of interest.



# Problems

- The C-DOG position is unknown and the parameter of interest.
- C-DOG data may contain **dropped observations**, can be **offset in time** from the GPS clock, and the arrival timings have around **20  $\mu$ s timing** uncertainty.

# Problems

- The C-DOG position is unknown and the parameter of interest.
- C-DOG data may contain **dropped observations**, can be **offset in time** from the GPS clock, and the arrival timings have around **20  $\mu$ s timing** uncertainty.
- GPS positions are not co-located with the transducer (**need to solve for spatial offset**) and have around **2 cm position** uncertainty.

# Problems

- The C-DOG position is unknown and the parameter of interest.
- C-DOG data may contain **dropped observations**, can be **offset in time** from the GPS clock, and the arrival timings have around **20  $\mu$ s timing** uncertainty.
- GPS positions are not co-located with the transducer (**need to solve for spatial offset**) and have around **2 cm position** uncertainty.
- Spatial and temporal variability in the **sound speed profile** of the ocean (**raytracing!**)



# Problems

- The C-DOG position is unknown and the parameter of interest.
- C-DOG data may contain **dropped observations**, can be **offset in time** from the GPS clock, and the arrival timings have around **20  $\mu$ s timing** uncertainty.
- GPS positions are not co-located with the transducer (**need to solve for spatial offset**) and have around **2 cm position** uncertainty.
- Spatial and temporal variability in the **sound speed profile** of the ocean (**raytracing!**)

# Solutions

# Problems

- The **C-DOG** position is unknown and the parameter of interest.
- C-DOG data may contain **dropped observations**, can be **offset in time** from the GPS clock, and the arrival timings have around **20  $\mu$ s timing** uncertainty.
- GPS positions are not co-located with the transducer (**need to solve for spatial offset**) and have around **2 cm position** uncertainty.
- Spatial and temporal variability in the **sound speed profile** of the ocean (**raytracing!**)

# Solutions

- An iterative alignment algorithm (I) accounts for timing offset and missing data points.

# Problems

- The **C-DOG** position is unknown and the parameter of interest.
- C-DOG data may contain **dropped observations**, can be **offset in time** from the GPS clock, and the arrival timings have around **20  $\mu$ s timing** uncertainty.
- GPS positions are not co-located with the transducer (**need to solve for spatial offset**) and have around **2 cm position** uncertainty.
- Spatial and temporal variability in the **sound speed profile** of the ocean (**raytracing!**)

# Solutions

- An iterative alignment algorithm (I) accounts for timing offset and missing data points.
- Plane fitting and simulated annealing algorithm (II) determine the offset between GPS and transducer.



# Problems

- The **C-DOG position is unknown and the parameter of interest.**
- C-DOG data may contain **dropped observations**, can be **offset in time** from the GPS clock, and the arrival timings have around **20  $\mu$ s timing** uncertainty.
- GPS positions are not co-located with the transducer (**need to solve for spatial offset**) and have around **2 cm position** uncertainty.
- Spatial and temporal variability in the **sound speed profile** of the ocean (**raytracing!**)

# Solutions

- An iterative alignment algorithm (I) accounts for timing offset and missing data points.
- Plane fitting and simulated annealing algorithm (II) determine the offset between GPS and transducer.
- A Gauss-Newton inversion algorithm (III) locates the C-DOG on the seafloor.

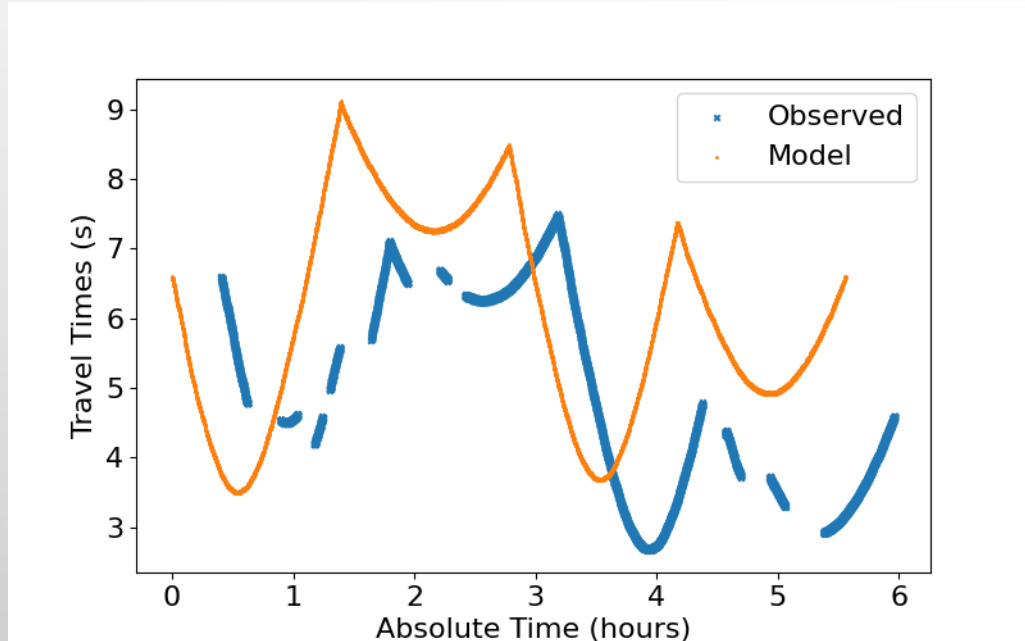
# Problems

- The C-DOG position is unknown and the parameter of interest.
- C-DOG data may contain **dropped observations**, can be **offset in time** from the GPS clock, and the arrival timings have around **20  $\mu$ s timing** uncertainty.
- GPS positions are not co-located with the transducer (**need to solve for spatial offset**) and have around **2 cm position** uncertainty.
- Spatial and temporal variability in the **sound speed profile** of the ocean (**raytracing!**)

# Solutions

- An iterative alignment algorithm (I) accounts for timing offset and missing data points.
- Plane fitting and simulated annealing algorithm (II) determine the offset between GPS and transducer.
- A Gauss-Newton inversion algorithm (III) locates the C-DOG on the seafloor.
- Current workflow solves for three parameters: **spatial offset, timing offset, and C-DOG position**

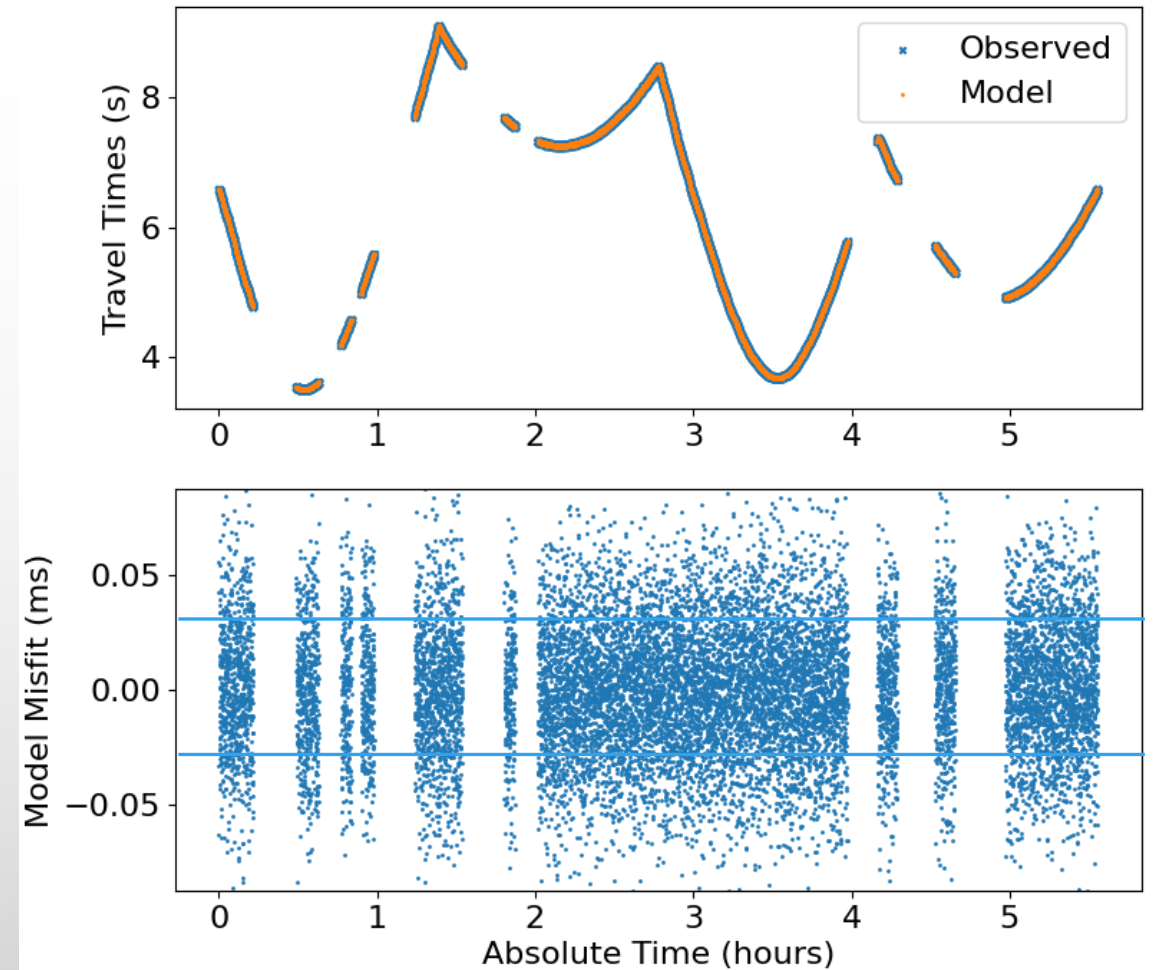
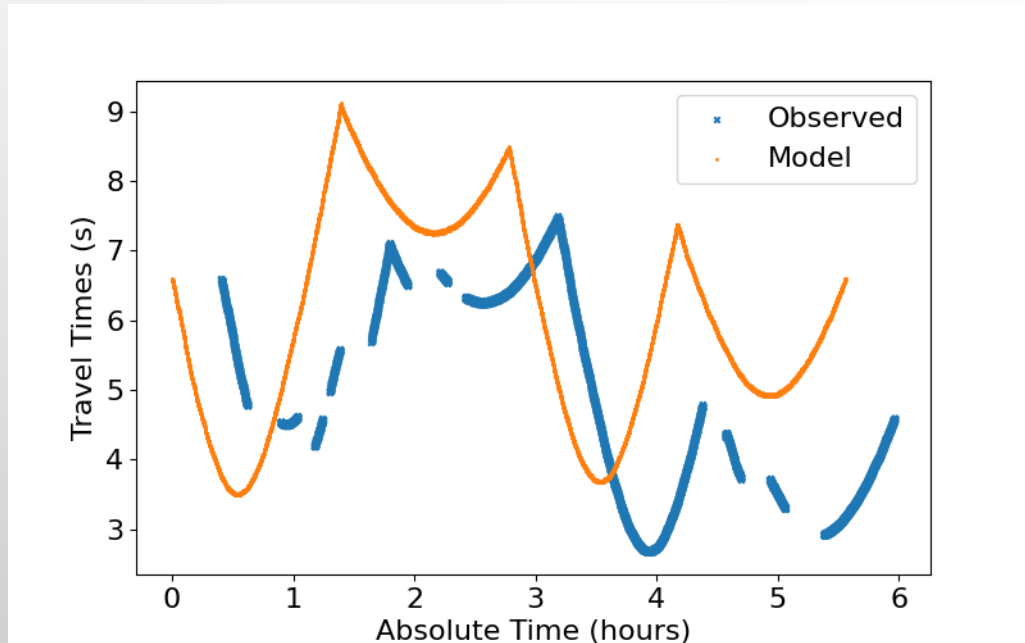
# (I) Alignment Algorithm



- Travel times come from unwrapping the time-tagged data
- Utilizes two-pointer approach to index data by absolute time and correct for missing segments
- Iteratively approach correct offset with cross-correlation
- Travel time corrected within alignment algorithm

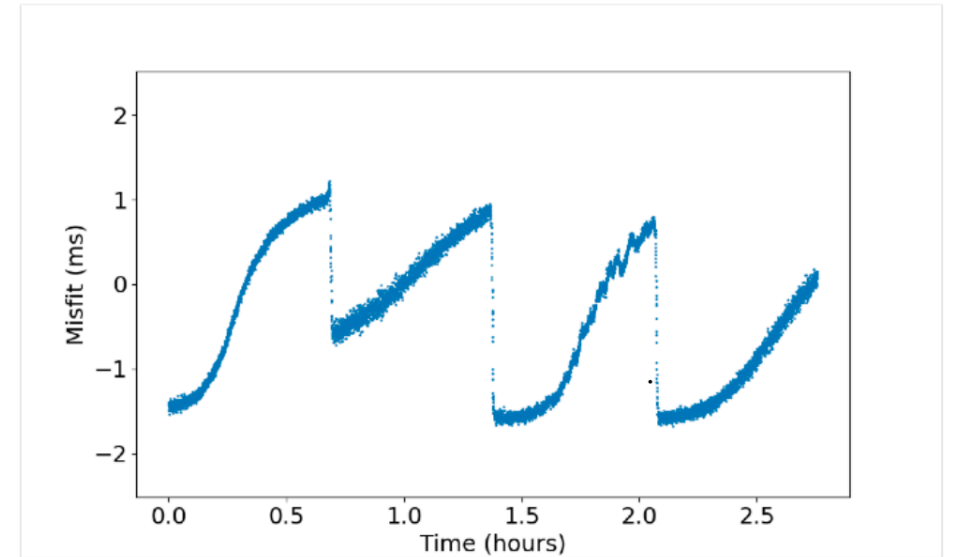
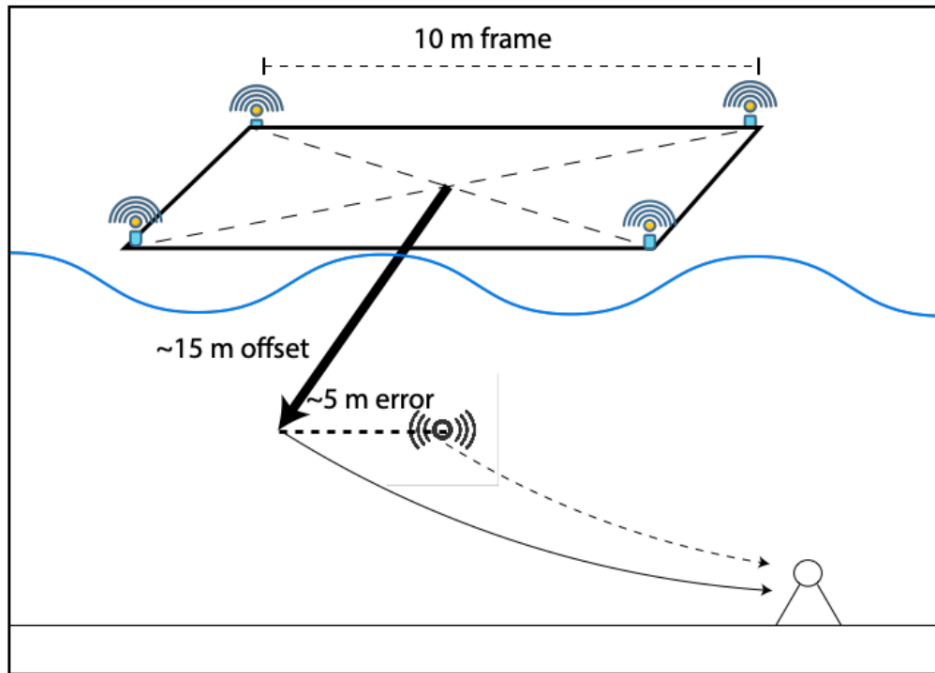


# (I) Alignment Algorithm

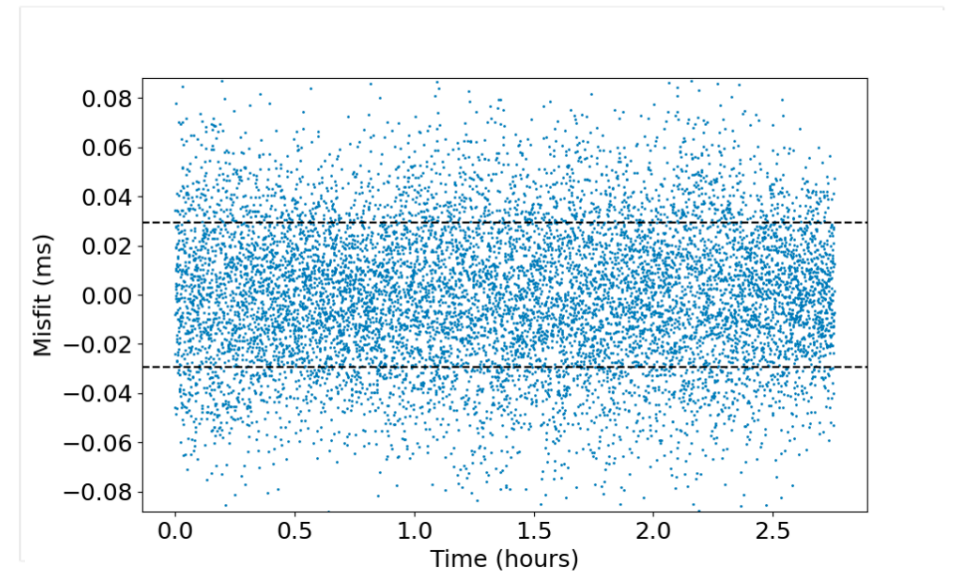
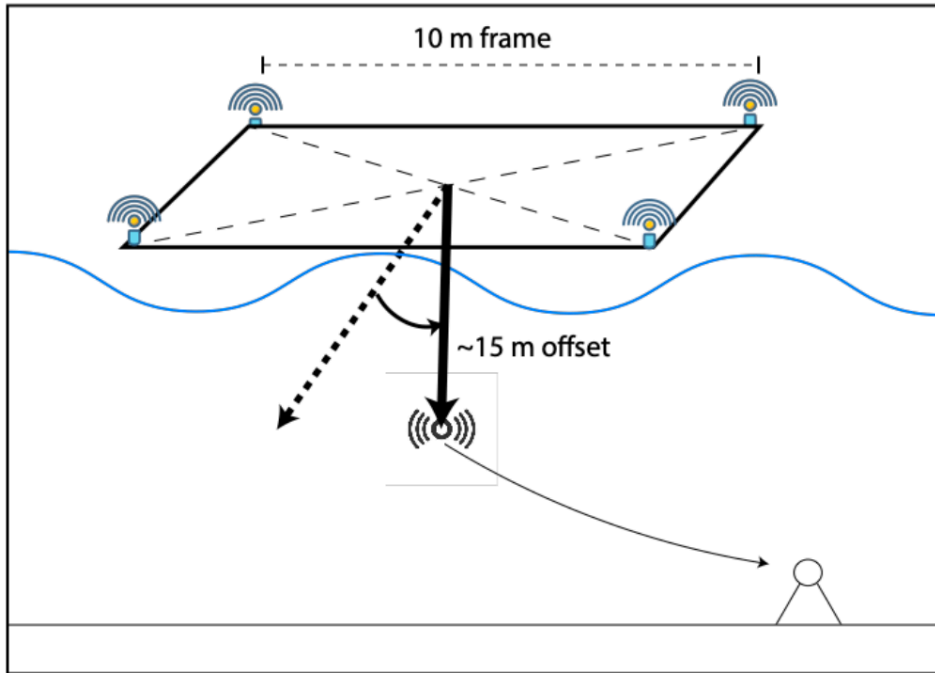


- Travel times come from unwrapping the time-tagged data
- Utilizes two-pointer approach to index data by absolute time and correct for missing segments
- Iteratively approach correct offset with cross-correlation
- Travel time corrected within alignment algorithm

## (II) Plane Fitting and Offset Determination by SA

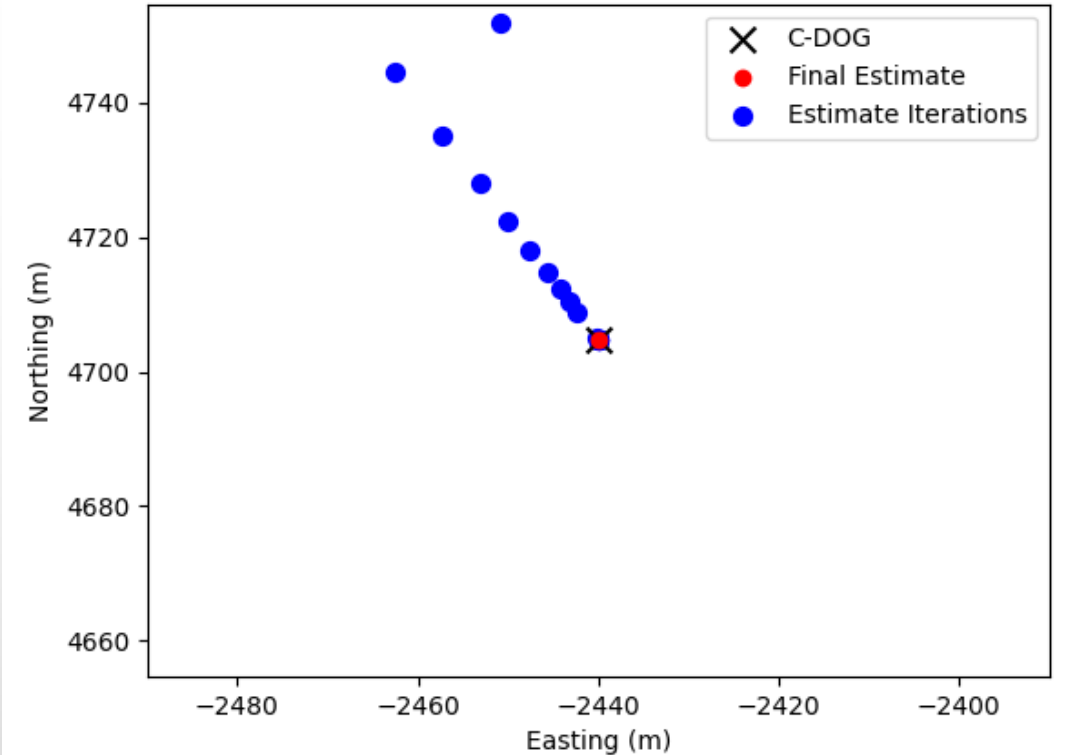


## (II) Plane Fitting and Offset Determination by SA



# (III) Gauss-Newton Inversion

- An iterative Gauss-Newton method hones in on the seafloor C-DOG
  - Works in conjunction with the alignment and simulated annealing algorithms
  - Requires reasonable initial guesses for transponder offset, alignment timing offset, and C-DOG position (otherwise it diverges)







# Full Synthetic

- With synthetic inputs:

# Full Synthetic

- With synthetic inputs:
  - 20,000 surface emissions along a 10 km trajectory in the shape of an X

# Full Synthetic

- With synthetic inputs:
  - 20,000 surface emissions along a 10 km trajectory in the shape of an X
  - 2 cm surface GPS position error

# Full Synthetic

- With synthetic inputs:
  - 20,000 surface emissions along a 10 km trajectory in the shape of an X
  - 2 cm surface GPS position error
  - 20  $\mu$ s time-tagging error

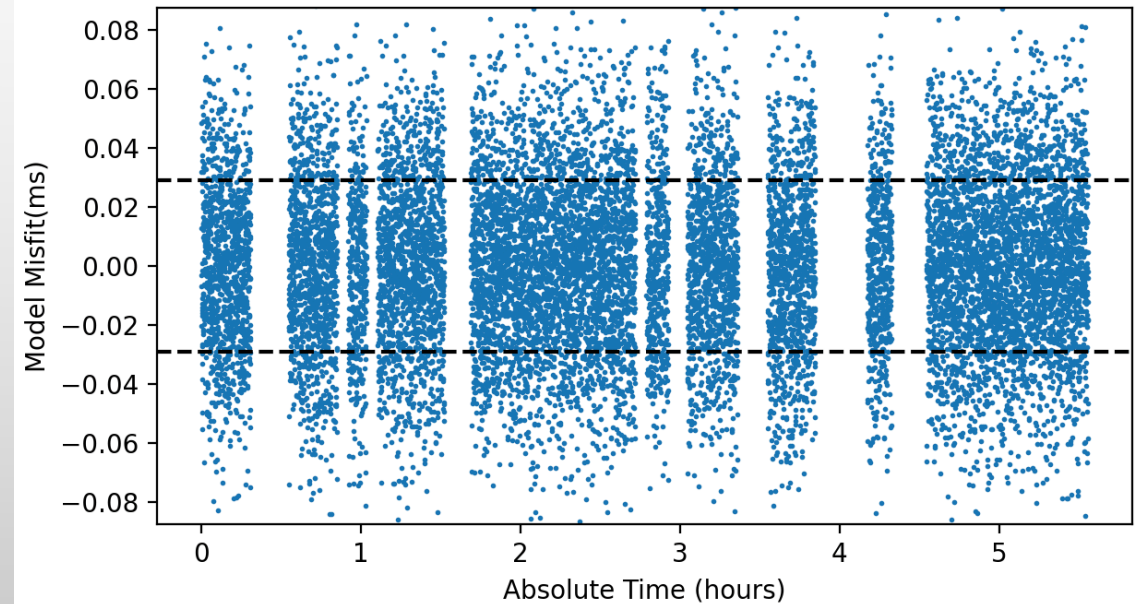
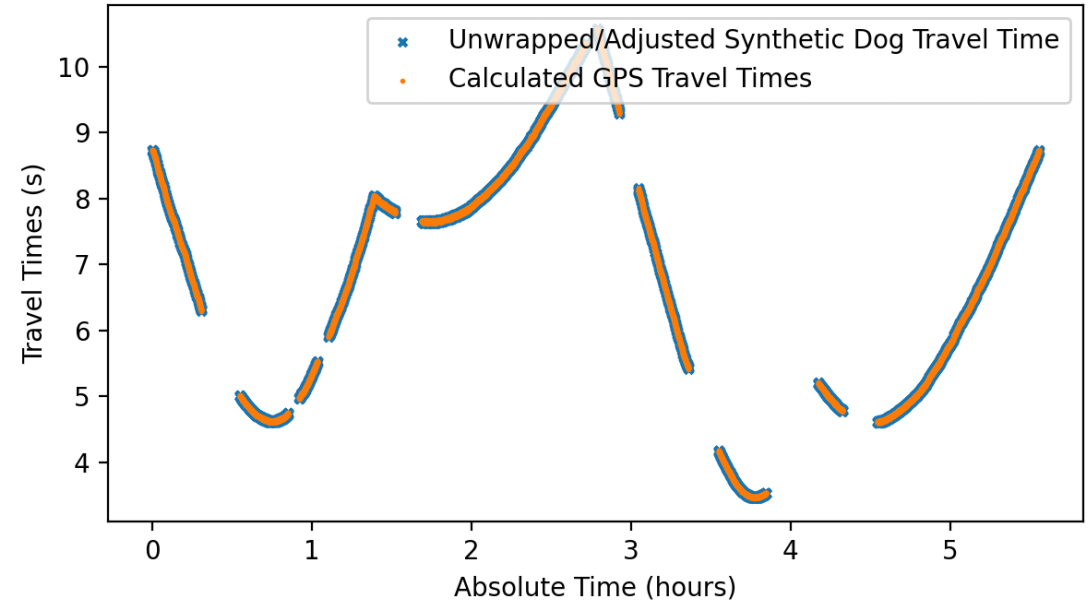


# Full Synthetic

- With synthetic inputs:
  - 20,000 surface emissions along a 10 km trajectory in the shape of an X
  - 2 cm surface GPS position error
  - 20  $\mu$ s time-tagging error
  - Random timing offset and data drops

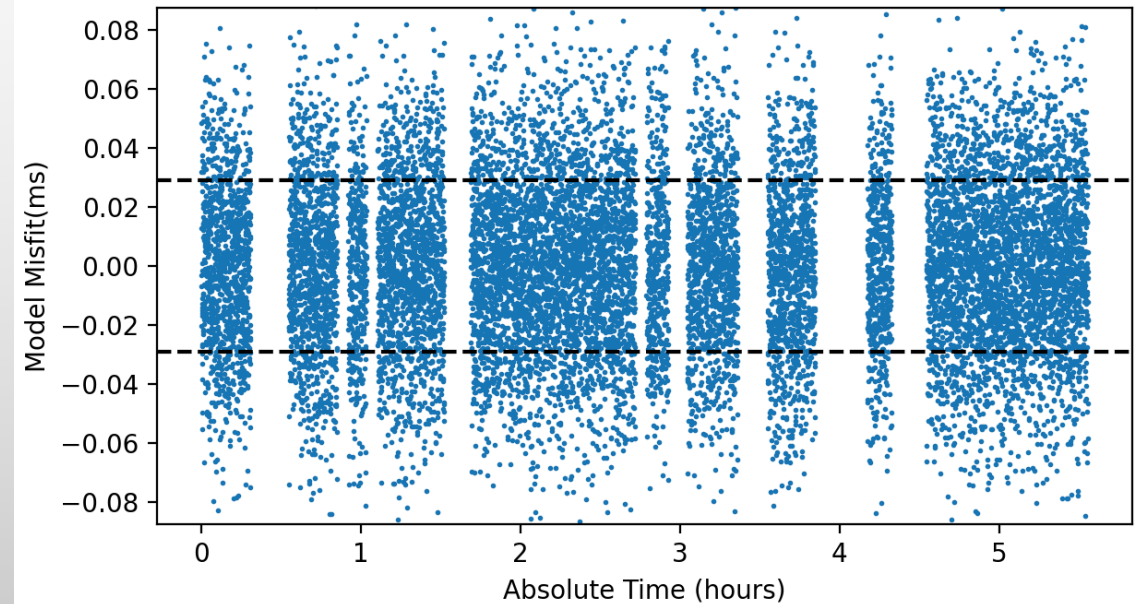
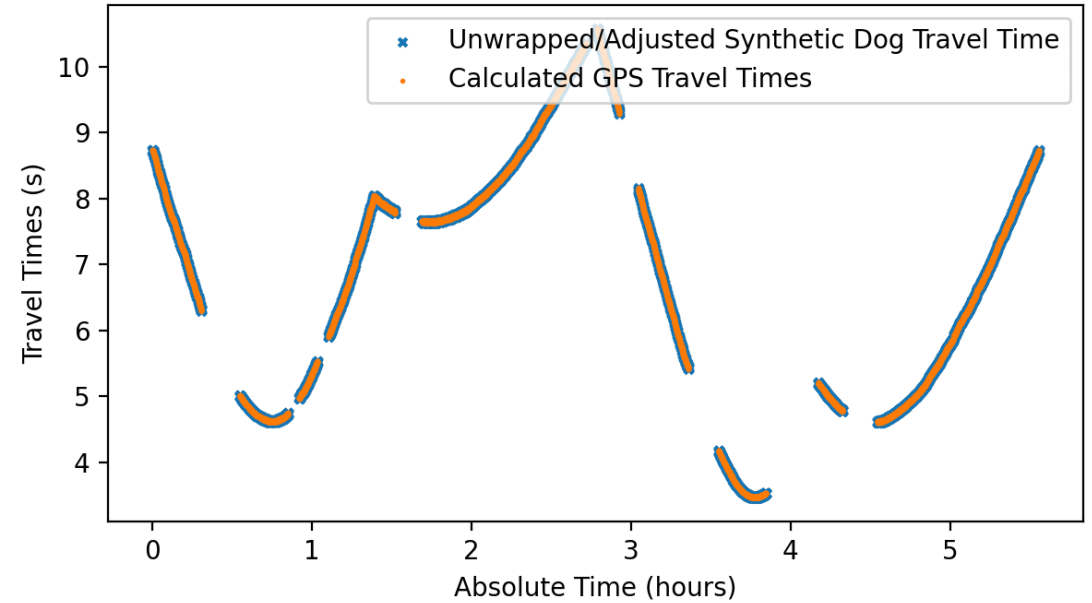
# Full Synthetic

- With synthetic inputs:
  - 20,000 surface emissions along a 10 km trajectory in the shape of an X
  - 2 cm surface GPS position error
  - 20  $\mu$ s time-tagging error
  - Random timing offset and data drops



# Full Synthetic

- With synthetic inputs:
  - 20,000 surface emissions along a 10 km trajectory in the shape of an X
  - 2 cm surface GPS position error
  - 20  $\mu$ s time-tagging error
  - Random timing offset and data drops
- The model estimates the C-DOG to a position  **$\sim 0.2$  cm** from the actual location



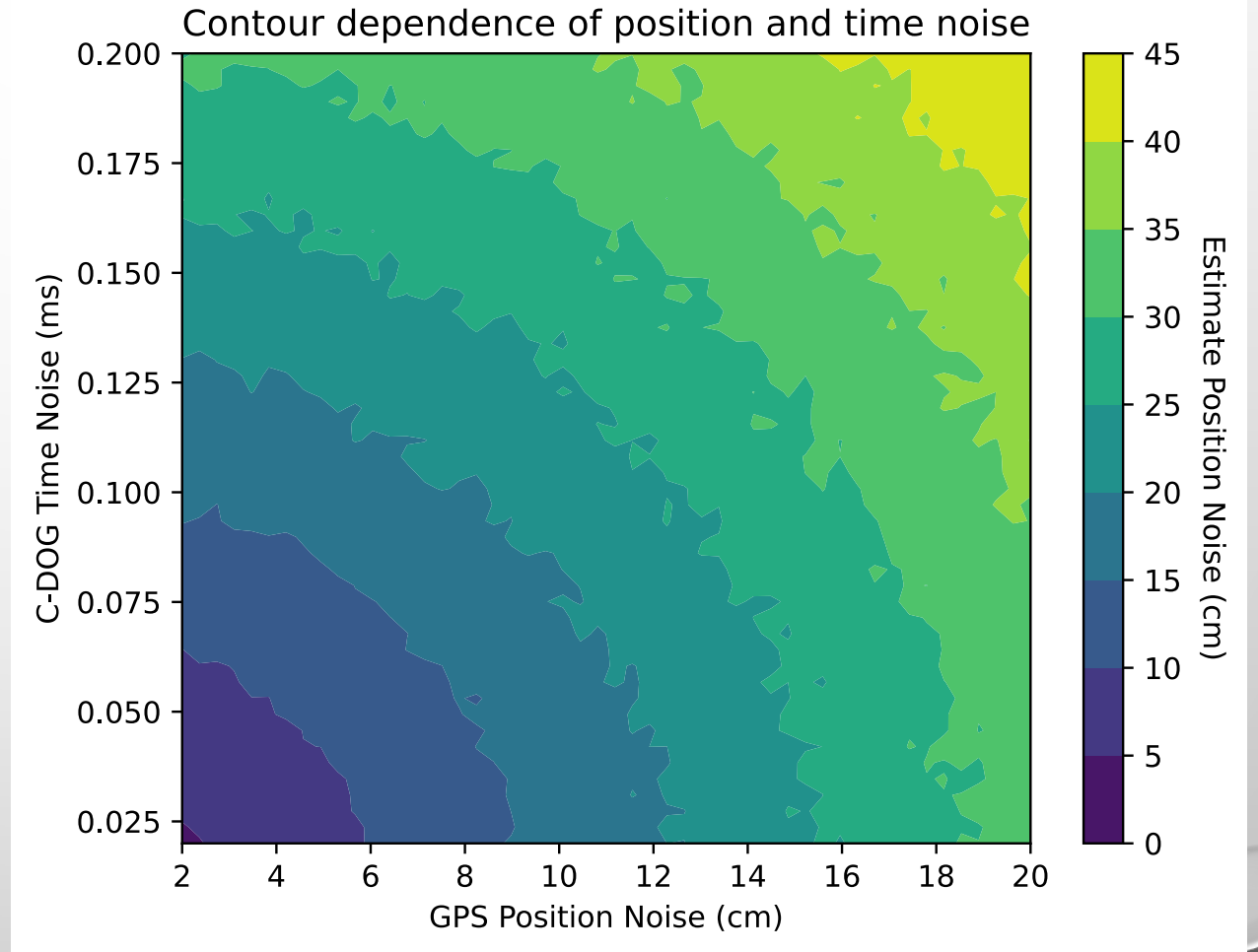
# Full Synthetic

- With synthetic inputs:
  - 20,000 surface emissions along a 10 km trajectory in the shape of an X
  - 2 cm surface GPS position error
  - 20  $\mu$ s time-tagging error
  - Random timing offset and data drops
- The model estimates the C-DOG to a position **~0.2 cm** from the actual location



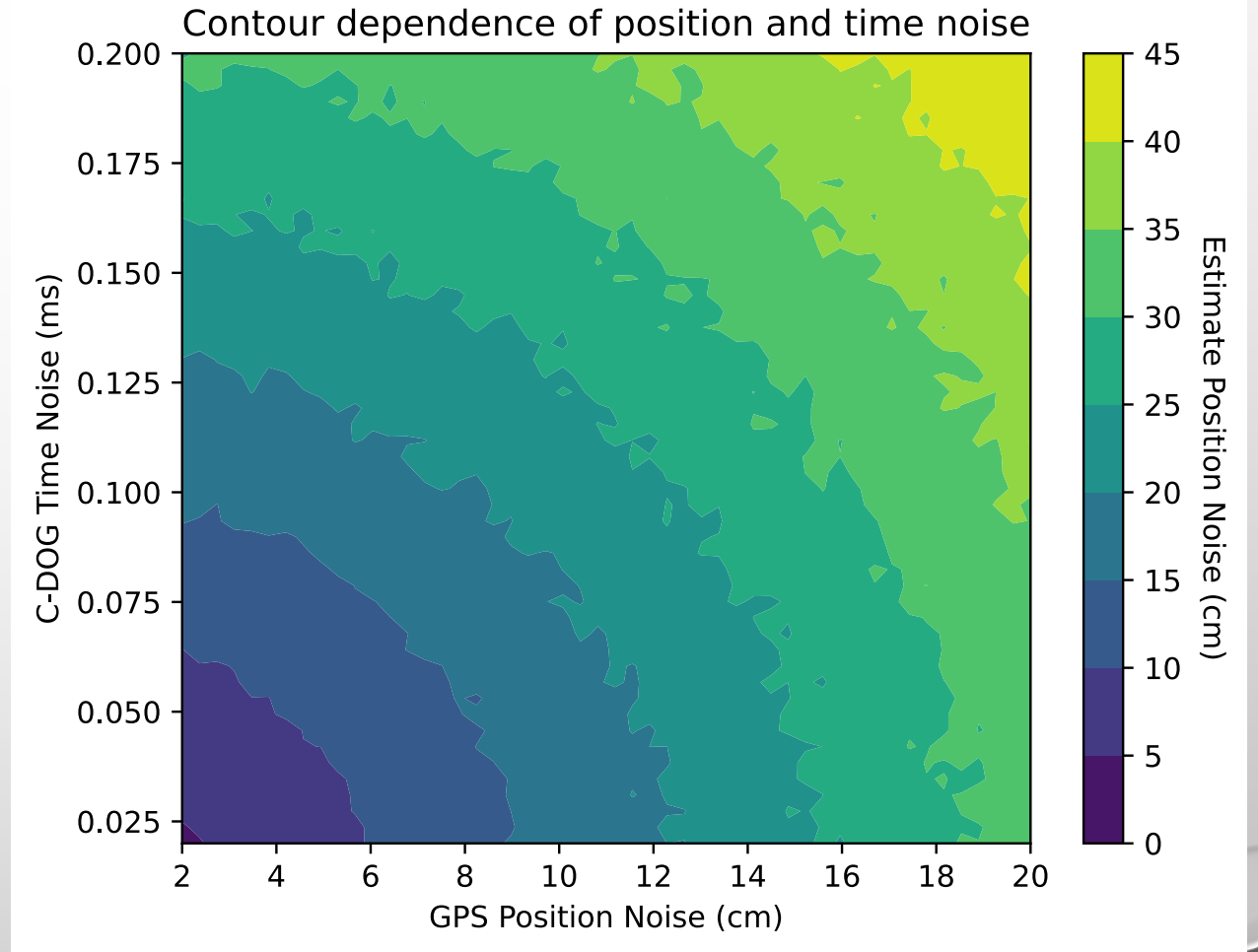
# Full Synthetic

- With synthetic inputs:
  - 20,000 surface emissions along a 10 km trajectory in the shape of an X
  - 2 cm surface GPS position error
  - 20  $\mu$ s time-tagging error
  - Random timing offset and data drops
- The model estimates the C-DOG to a position  **$\sim 0.2$  cm** from the actual location



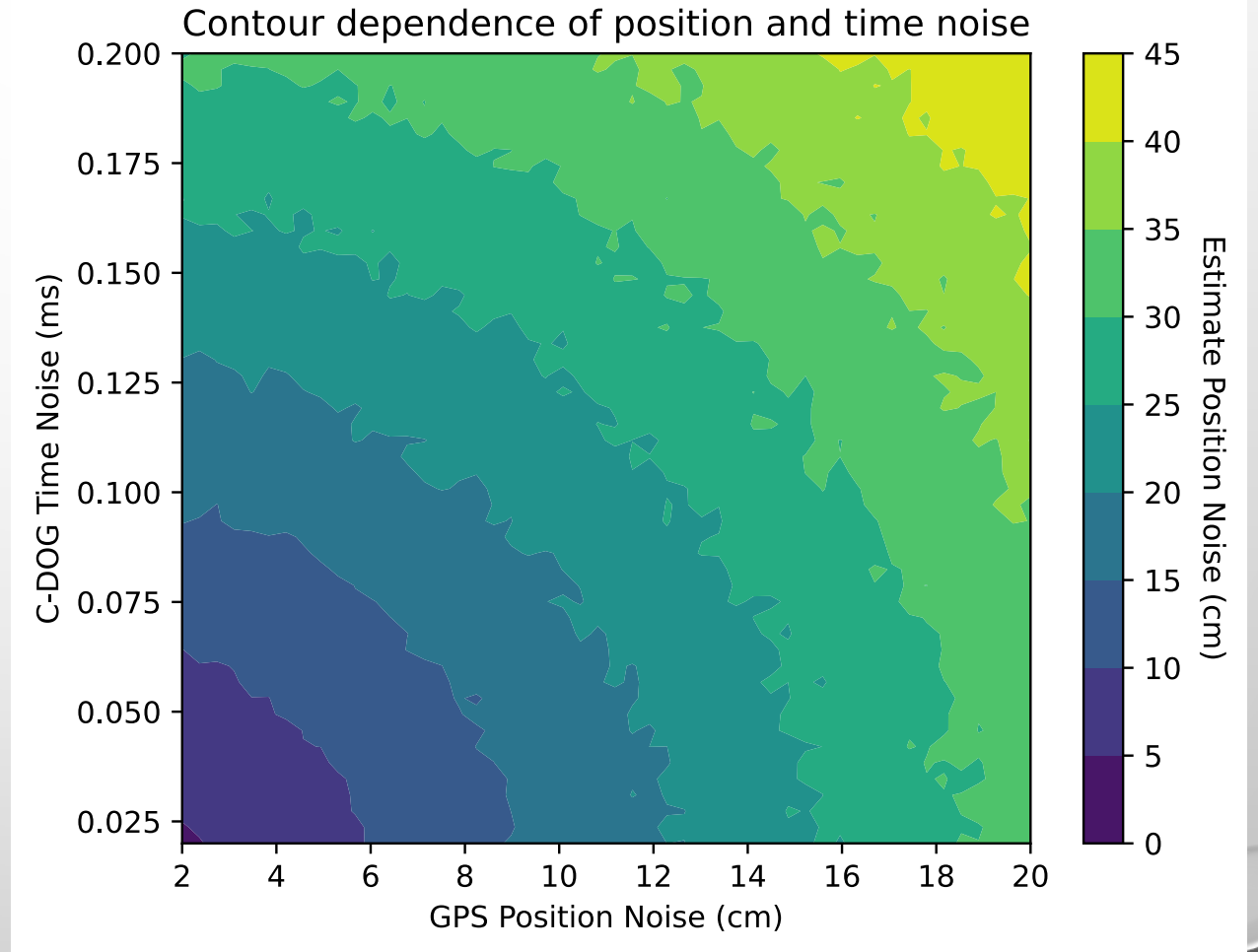
# Full Synthetic

- With synthetic inputs:
  - 20,000 surface emissions along a 10 km trajectory in the shape of an X
  - 2 cm surface GPS position error
  - 20  $\mu$ s time-tagging error
  - Random timing offset and data drops
- The model estimates the C-DOG to a position **~0.2 cm** from the actual location
- Next: Varying ocean sound speed in the synthetic



# Full Synthetic

- With synthetic inputs:
  - 20,000 surface emissions along a 10 km trajectory in the shape of an X
  - 2 cm surface GPS position error
  - 20  $\mu$ s time-tagging error
  - Random timing offset and data drops
- The model estimates the C-DOG to a position **~0.2 cm** from the actual location
- Next: Varying ocean sound speed in the synthetic
- Next: Real data analysis





# THE END

