

# **GSFlib, The Generic Sensor Format Library**

**12 April 2024**

Prepared For:  
Naval Oceanographic Office  
Stennis Space Center, MS 39522

Prepared By:  
Leidos Corporation  
221 Third Street  
Newport, RI 02840

## GSFLib, the Generic Sensor Format Library

REVISIONS			
Rev	Date	Pages Affected	Remarks
0	04 SEP 1998	All	Baseline Version
1	12 NOV 1998	All	Updated specification to reflect changes due to implementations through GSF-v1.07.
2	07 OCT 1999	All	Updated specification to reflect changes due to implementations through GSF-v1.08.
3	12 OCT 1999	All	Updated specification to reflect changes due to implementations through GSF-v1.09.
4	20 OCT 2000	All	Updated specification to reflect changes due to implementations through GSF-v1.10
5	16 JAN 2001	All	Updated specification to reflect changes due to implementations through GSF-v1.11
6	29 MAR 2002	Various	Updated Library Documentation to reflect changes made for GSF version 2.0. Including: (c++ support, and support for Simrad EM120)
7	08 JUL 2002	Various	Updated Library Documentation to reflect changes made for GSF version 2.01.
8	20 JUN 2003	Various	Updated Library Documentation to reflect changes made for GSF version 2.02, including support for bathymetric receive beam time series intensities.
9	29 DEC 2004	Various	Updated Library Documentation to reflect changes made for GSF version 2.03.
10	30 JUN 2006	Various	Updated Library Documentation to reflect changes made for GSF version 2.04.
11	09 MAR 2007	Various	Updated Library Documentation to reflect changes made for GSF version 2.05.

12	04 Sep 2007	Various	Updated Library Documentation to reflect changes made for GSF version 2.06 and 2.07
13	03 Dec 2007	None	No change to the text for GSF version 2.08
14	30 Jan 2008	Various	Updated Library Documentation to reflect changes made for GSF version 2.09
15	20 Mar 2009	Various	Updated Library Documentation to reflect changes made for GSF version 03.01
16	24 Sep 2010	Various	Updates for GSF version 03.02.
17	24 Sep 2011	Various	Updates for GSF version 03.03. Includes Kongsberg EM12 and R2Sonic support
18	8 June 2012	Various	Updates for GSF version 03.04.
19	02 May 2014	Various	Updates for GSF version 03.05.
20	30 Jun 2014	Various	Updates for GSF version 03.06.
21	31 Oct 2016	Footers	Updates for GSF version 03.07
22	2 Oct 2018	Various	Updates for GSF version 03.08
23	26 April 2019	Various	Updates for GSF version 03.09
24	12 April 2024	Various	Updates for GSF version 03.10

## Table of Contents

1.Introduction .....	1-1
1.1Implementation Concept.....	1-1
1.2Development History.....	1-3
1.3Restrictions and Limitations .....	1-7
1.4References .....	1-8
1.5Distribution .....	1-8
1.6Sensors Supported.....	1-8
1.7Computer Platforms Supported .....	1-10
1.8Documentation Conventions.....	1-11
2.Function Definitions.....	2-1
2.1Access Functions.....	2-1
2.1.1Function: gsfOpen .....	2-1
2.1.2Function: gsfOpenBuffered .....	2-3
2.1.3Function: gsfRead .....	2-6
2.1.4Function: gsfWrite .....	2-8
2.1.5Function: gsfSeek.....	2-9
2.1.6Function: gsfClose.....	2-10
2.2Utility Functions.....	2-12
2.2.1Function: gsfCopyRecords .....	2-12
2.2.2Function: gsfFree .....	2-12
2.2.3Function: gsfPutMBParams .....	2-13
2.2.4Function: gsfGetMBParams.....	2-14
2.2.5Function: gsfStat.....	2-15
2.2.6Function: gsfLoadScaleFactor .....	2-16
2.2.7Function: gsfGetScaleFactor .....	2-19
2.2.8Function: gsfSetDefaultScaleFactor.....	2-20

2.2.9Function: gsfLoadDepthScaleFactorAutoOffset .....	2-21
2.2.10Function: gsfGetPositionDestination.....	2-22
2.2.11Function: gsfGetPositionOffsets.....	2-23
2.2.12Macro: gsfTestPingStatus .....	2-24
2.2.13Macro: gsfSetPingStatus.....	2-25
2.2.14Macro: gsfClearPingStatus .....	2-25
2.3Information Functions .....	2-26
2.3.1Function: gsfIntError .....	2-26
2.3.2Function: gsfPrintError .....	2-27
2.3.3Function: gsfStringError.....	2-27
2.3.4Function: gsfIndexTime .....	2-28
2.3.5Function: gsfPercent.....	2-29
2.3.6Function: gsfGetNumberRecords .....	2-30
2.3.7Function: gsfGetSwathBathyBeamWidths .....	2-31
2.3.8Function: gsfGetSwathBathyArrayMinMax.....	2-31
2.3.9Function: gsfIsStarboardPing.....	2-32
2.3.10Function: gsf_register_progress_callback .....	2-33
2.3.11Function: gsfGetSonarTextName .....	2-34
2.3.12Function: gsfFileSupportsRecalculateXYZ.....	2-35
2.3.13Function: gsfFileSupportsRecalculateTPU .....	2-36
2.3.14Function: gsfFileSupportsRecalculateNominalDepth.....	2-38
2.3.15Function: gsfFileContainsMBAmplitude .....	2-39
2.3.16Function: gsfFileContainsMBImagery.....	2-41
2.3.17Function: gsfIsNewSurveyLine.....	2-42
2.3.18Function: gsfInitializeMBParams .....	2-43
3.ERROR CODE DESCRIPTIONS.....	3-1
4.C-language Definitions of Structures used by GSFLib.....	4-1
4.1Definition of GSF Data Records .....	4-1

4.1.1Header Record.....	4-1
4.1.2Swath Bathymetry Ping Record.....	4-2
4.1.3Single-beam Bathymetry Record.....	4-49
4.1.4Sound Velocity Profile (SVP) Record.....	4-51
4.1.5Processing Parameters Record.....	4-52
4.1.6Sensor Parameters Record .....	4-55
4.1.7Comment Record.....	4-55
4.1.8History Record .....	4-56
4.1.9Navigation Error Record.....	4-56
4.1.10Swath Bathymetry Summary Record .....	4-57
4.1.11Attitude Record .....	4-57
4.2Supporting Data Structures and Definitions.....	4-58
4.2.1Record Identifier.....	4-58
4.2.2Time Structure.....	4-58
4.2.3Null values used to represent missing data .....	4-59
4.2.4Positioning System Type Codes .....	4-60

## List of Figures

Figure 1-1 GSFLib Functions.....	1-3
----------------------------------	-----

## List of Tables

Table 2-1 GSF Beam Array Field Size Definitions .....	2-17
Table 3-1 GSF Error Codes .....	3-1
Table 4-1 Sensor ID allocation to Sensor Specific Subrecord Data Structure .....	4-42

# 1. INTRODUCTION

The Generic Sensor Format (GSF) library contains functions for creating and accessing multibeam and single-beam sonar data that have been stored in a generic byte stream format corresponding to the sequential encapsulation described in the Generic Sensor Format Specification. This specification defines a set of eleven record types that are used to store bathymetric data.

This document is derived from documentation within the GSFLib source code, primarily the header file, `gsf.h`. The intent is to present that information in a more accessible, organized form and to describe the library's design and implementation. Because the information presented herein is derived from the source code, the code itself should be the primary reference for application developers.

## 1.1 Implementation Concept

The GSF library (gsflib) is a “thin” layer of software that transfers data between the data format described in the specification and a standardized set of data structures. This is necessary because the specified data format is a byte stream of data containing records of arbitrary length that have been extensively optimized for compactness and is not easily manipulated. The organization of the data structures populated by GSFLib is for the developer's convenience and presents the data in a uniform manner with a consistent set of physical units. There is a one-to-one correspondence between the record types defined in the specification and the data structures made available through the library.

Figure 1-1 illustrates the GSF library functions. There are three functional categories in the library routines: those that provide access to the data when stored on disk, those that perform utility operations and those that provide information about the data. The access functions, which translate between the memory-based data structures and the byte-stream data format, include operations to open and close, read and write to data files and seek functions to access data by time and record type.

Utility functions include routines that copy data structures, free memory, translate processing parameters into a more accessible form, and provide the programmer with access to the scale factors used to optimize the storage of ping arrays. Processing parameters document the extent to which data have been processed and the values of any correctors or offsets that have been applied to the data. Access to processing parameters is necessary when they are required or need to be updated. Scale factor information defines how the data are packaged into the GSF data files. They are automatically applied to read operations and need to be manipulated only when the application is writing data to disk.

Informational functions provide a variety of facts about the data. These functions provide capabilities such as:

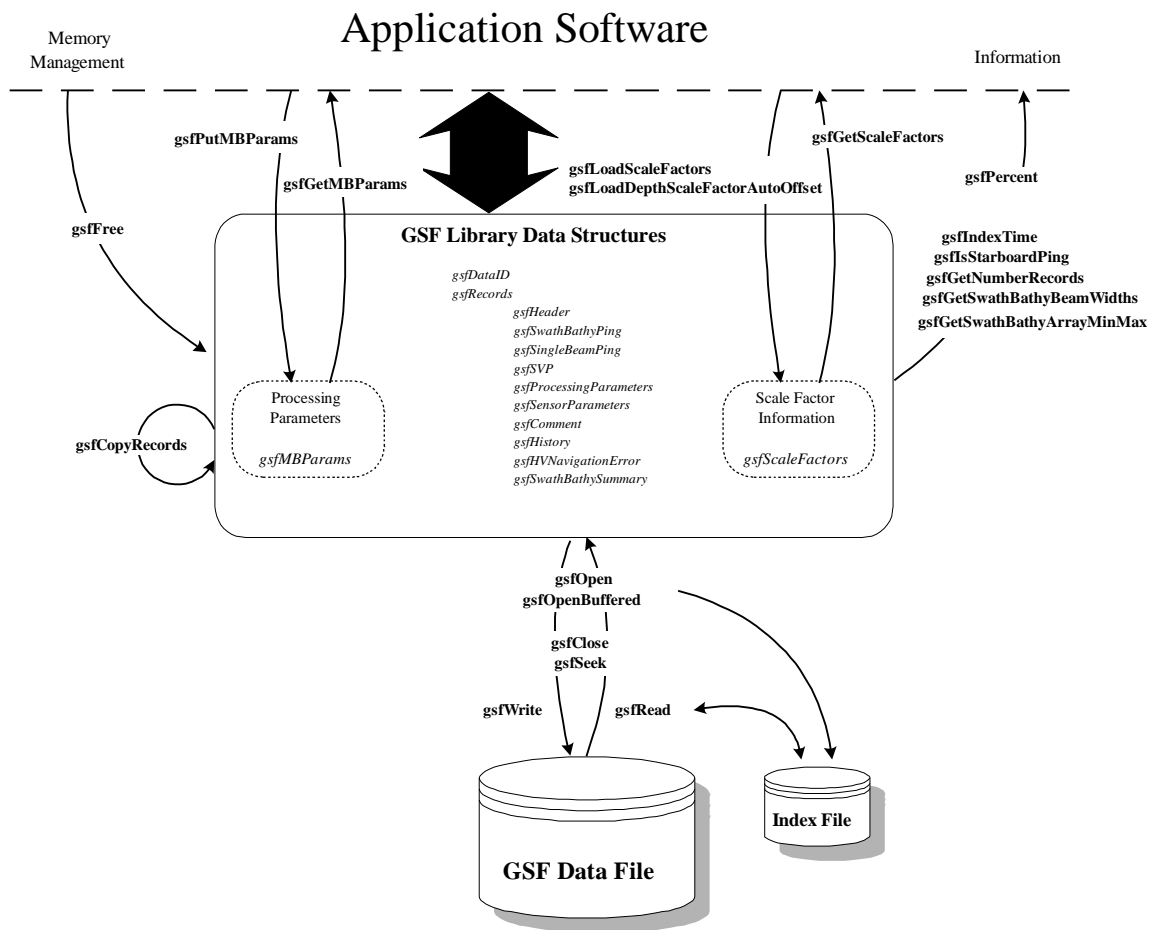
- describing error conditions,



- returning the relative location of the file pointer within the file,
- providing counts of the number of records of a given type,
- discriminating between starboard and port-directed beams in dual transducer configurations
- Providing beam widths for the data being processed.
- Providing the name of the sensor

It should be noted that for some sonars this beam width information is not stored within the data but is provided by lookup tables within the library source code.

The GSF byte stream is a sequentially oriented file but the library provides for direct access to the data via an auxiliary index file. Upon opening a data file for direct access, the disk is inspected for an index file that corresponds to the data file being opened. If there is no index file, one is created. The index file provides direct access to any record in the data file. The creation and maintenance of the index file is transparent to both the application developer and to the user. The normal sequence of events is for the data file to be written sequentially and for the index file to be created by the first program that needs to examine it using direct access. At this time, the index file format is not a part of the GSF data specification but is defined only within the library.



**Figure 1-1** GSFLib Functions

## 1.2 Development History

J. Scott Ferguson and Brad Ward of SAIC and Daniel Chayes of the Naval Research Lab developed the GSF specification. The Defense Mapping Agency supported its development and it was first published on 31 March 1994. The initial author of the GSF library is Shannon Byrne of Leidos (formerly SAIC). The library was first released on 3 May 1994. The U.S. Naval Oceanographic Office (NAVOCEANO) and Naval Sea Systems Command (NAVSEA) supported the development of this library. NAVOCEANO also provided significant direction and feedback during the library's development and initial deployment. After deployment, the GSF Working Group was formed. This group discusses issues relative to the specification and the library, provides direction for GSF development and acts as a configuration control board to accept updates. The working group exchanges technical information mostly via email. The GSF mailing list can be subscribed to by filling out the form located here: <https://www.leidos.com/maritime/gsf>. Both the specification and the GSF library are maintained under configuration control by Leidos with input from members of the GSF working group.

The library's release history is as follows:

Release Date	Version ID	Description
03 May 1994	GSF-v01.00	Initial Release.
14 Aug 1995	GSF-v01.01	Direct and sequential access now works through common <b>gsfRead</b> and <b>gsfWrite</b> API. All pointers to dynamically allocated memory are now maintained by the library.
22 Dec 1995	GSF-v01.02	Added <b>gsfGetMBParams</b> , <b>gsfPutMBParams</b> , <b>gsfIsStarboardPing</b> , and <b>gsfGetSwathBathyBeamWidths</b> . Also added <i>GSF_APPEND</i> as a file access mode, and modified <i>GSF_CREATE</i> access mode so that files can be updated (read and written).
20 Aug 1996	GSF-v01.03	Added support for single beam echosounders. Added <b>gsfStringError</b> function.
24 Mar 1997	GSF-v01.04	Added support for RESON 8101 sonar and enhanced support for “classic” Seabeam sonar. Increased the maximum record size from 4 kbytes to 32 kbytes.
04 Sep 1998	GSF-v01.06	Added support for SeaBeam 2100 series multibeam sonars and for Elac Bottomchart MkII sonars. Minor enhancements to code portability.
12 Nov 1998	GSF-v01.07	Defined a new GSF navigation error record <i>gsfHVNavigationError</i> that replaces the currently defined navigation error record <i>gsfNavigationError</i> . Modified encode of the existing error array subrecords (depth_error, across_track_error, and along_track_error) as two byte quantities. Added two new array subrecords to the GSF swath bathymetry ping data structure, namely horizontal error and vertical error. Modified the <b>gsfPrintError</b> function so that it calls the <b>gsfStringError</b> function. <b>gsfStringError</b> function expanded so that all defined error conditions are handled.
07 Oct 1999	GSF-v01.08	Added support for Simrad multibeam models EM-3000, EM-1002 and EM-300, as well as added a new compressed SASS ( <i>gsfCmpSassSpecific</i> ) specific data structure. Added two new functions <b>gsfGetSwathBathyArrayMinMax</b> and <b>gsfLoadDepthScaleFactorAutoOffset</b> in support of signed depth. Also added processing in the <b>gsfGetSwathBathyBeamWidths</b> function to return the beam width values specified within the EM-3000 series data formats. Increased the <i>GSF_MAX_PROCESSING_PARAMETERS</i> macro from sixty-four to one hundred and twenty-eight and the <i>GSF_MAX_SENSOR_PARAMETERS</i> macro from thirty-two to one hundred and twenty-eight. Modified <b>gsfPutMBParameters</b> function to allow processing parameters to contain the appropriate designator for the vertical datum.

12 Oct 1999	GSF-v01.09	Updated the contents of the compressed SASS (gsfCmpSassSpecific) specific subrecord. Added a comment block to the compressed SASS specific subrecord definition to describe the mapping between SASS and GSF data. Included annotations informing that the gsfCmpSassSpecific data structure is intended to replace the gsfTypeIIISpecific data structure in a future release. All new coding should use the gsfCmpSassSpecific data structure.
20 Oct 2000	GSF-v01.10	Enhancements for index file portability between big and little endian-based host machines. Updates to source code for minor bug fixes.
16 Jan 2001	GSF-v01.11	Updated the contents of the gsfEM3RunTime data structure to include separate elements for port and starboard swath width and for port and starboard coverage sectors. Updated the contents of the gsfEM3RunTime data structure to include the HiLo frequency absorption coefficient ratio. Added checks for LINUX specific defines before defining timespec structure. Added support for more tidal datums. Fixed errors in decoding of HV Navigation Error records.
29 Mar 2002	GSF-v02.00	Modified to support access from c++ applications, address file sharing problems on multiprocessor Linux configurations, resolve compile macros used for Win32, resolved several minor bug fixes, remove unused automatic variables, add support for the Simrad EM120 sonar, reserve subrecord IDs for the latest datagram format for Reson 8101, 8111, 8125, 8150, and 8160 sonar systems, and ensure that a string terminating NULL is applied when strncpy is used.
08 Jul 2002	GSF-v02.01	Added gsfAttitude record to allow storage of full time series of attitude data. Added a new sensor specific subrecord for Reson 8101, 8111, 8125, 8150, and 8160 sonar systems. Expanded the gsfMBOffsets structure to include motion sensor offsets. Updated gsfGetMBParams and gsfPutMBParams to encode and decode new motion sensor offsets in the process_parameters record.
20 Jun 2003	GSF-v02.02	Added support for bathymetric receive beam time series intensity data. Added sensor-specific single-beam information to the multibeam sensor specific subrecords.
29 Dec 2004	GSF-v02.03	Fixed memory leaks, fixed encoding and decoding of 1-byte BRB intensity values, updated gsfLoadDepthScaleFactorAutoOffset to vary the offset interval based on precision, added beam spacing to Reson 8100 sensor-specific subrecord, reserved sensor IDs for Simrad EM3002, EM3002D, and EM3000D, added sensor specific support for Reson Navisound singlebeam, added copy of vertical_error and horizontal_error arrays in

		gsfCopyRecords, and added definitions for RTG position type to gsfHVNavigationError record.
30 Jun 2006	GSF-v2.04	Added support for EM121A data received via Kongsberg SIS. Added support for EM3000D and EM3002D in gsflsStarboard ping function. Added new service to allow calling programs to register a callback function for reporting progress of index file creation. Updated gsfCopyRecords to copy all HV Nav Error data from source to target data structure. Updates to support compilation on 64-bit architectures, and compilation on MAC OSX operating system.
09 Mar 2007	GSF-v2.05	Added support for bathymetry data from the GeoAcoustics Ltd. GS+ Interferrometric side-scan sonar system.  Reserve sub-record IDs for the Kongsberg EM122, EM302, and EM710 systems.
04 Sep 2007	GSF-v2.06, GSF-v2.07	Added support for the Kongsberg EM122, EM302, and EM710 multibeam systems. Added application level control over the field size to be used for a subset of the beam array subrecords. Improved error checking in gsfLoadScaleFactor(). Fixed a problem in DecodeSignedByteArray that was only an issue on the SGI platform.
03 Dec 2007	GSF-v2.08	Modified the approach used to parse the beam array subrecords to no longer depend on the compression flag field of the scale factor subrecord for determining the field size. This dependency on the compression flag field was added in GSFv2.06 on the premise that a default value of zero could (always) be expected.
30 Jan 2008	GSF-v2.09	Added support for Klein 5410 Bathymetric Sidescan.
20 Mar 2009	GSF-v03.01	Added support for the Reson 7125 and EM2000. Added fields for height, separation, and gps tide corrector to the gsfSwathBathyPing record. Added new processing parameter record values: vessel_type, full_raw_data, msb_applied_to_attitude, heave_removed_from_gps_tc. Added new sensor ids for EM3 sensors to differentiate between data logged from the depth datagram and the raw range and beam angle datagram.
24 Sep 2010	GSF-v03.02	Added support for KM2040. Added support for Imagenex Delta-T. Add new query functions to provide calling applications with a simple means to determine what data are contained in the GSF file and what processing operations can be supported given the parameters available in the input file. Added separation uncertainty field to the Navigation uncertainty record. Several bugs resolved.

24 Sep 2011	GSF-v03.03	Added support for Kongsberg EM12 and R2Sonic
18 April 2012	GSF-v03.04	Several bugs resolved.
30 March 2014	GSF-v03.05	Geodetic functions added. Added new ping subarray for sonar's vertical uncertainty. Added support for files larger than 2 gigabytes in size. Added support for different number of multibeam transmitters and receivers. Some bugs resolved.
30 June 2014	GSF-v03.06	Minor update to correct large file support issues new to GSF-v03.06.
31 October 2016	GSF-v03.07	Minor update to correct appending to GSF index files.
2 October 2018	GSF-v03.08	Added support for Reson T Series multibeam systems.
4 April 2019	GSF-v03.09	Added support for Kongsberg Multibeam sonars using the KMALL format. Added functionality for storing GSF compressed. Update <code>gsfLoadDepthScaleFactorAutoOffset</code> to work with ERS corrected pings. Added additional vertical datums.
12 April 2024	GSF-v03.10	Added support for ME70. Added additional fields for swathy pings subrecords. Added additional fields for KMALL subrecords. STIG remediation and bug fixes.

### 1.3 Restrictions and Limitations

The following restrictions or limitations apply to the GSFLib code.

- The library assumes the host computer uses the ASCII character set.
- The library is written in the C language and assumes that the type `short` is 16 bits, and that the type `int` is 32 bits.
- The library provides access to individual data files only and does not support the development of metadata or transmittal files. It should be noted, however, that many of the data items recorded in the files' summary and parameter records may be used to populate metadata records.
- Data compression flags are maintained within the ping scale factors subrecord but data compression is not supported.
- The index function creates separate index files that make assumptions about the file naming convention. The library names the index file the same as the data file name but replaces the third to the last character with an "n". This is because the files are expected to be named using a file naming convention adhered to within NAVOCEANO for data collected by their Integrated Survey Systems (ISS and ISS-60). No protection exists for the case where a GSF data file already has an "n" in the third to the last character. As of GSFv03.05, the GSF library supports files larger than 2 gigabytes in size. As of GSFv03.05, the format of the index files has changed to accommodate 8-byte file offset

pointers. When an older format index file is encountered by the new library, the index file will automatically be recreated. A GSFv03.05 format index file will not be usable by older versions of library.

- Time is recorded in precise form only with fractional seconds included in all time fields. The beginning of the epoch is required to be midnight of 1 January 1970, thus data recorded prior to this date is not supported. All times in GSF are required to be relative to UTC.
- The only horizontal datum supported is “WGS-84”; supported tidal datums include “UNKNOWN”, “MLLW”, “MLW”, “ALAT”, “ESLW”, “ISLW”, “LAT”, “LLW”, “LNLW”, “LWD”, “MLHW”, “MLLWS”, “MLWN”, “MSL”, “ALLW”, “LNT”, “AMLWS”, “AMLLW”, “MLWS”, “AMSL”, “AMLW”, “AISLW”, and “ALLWS”. This is a limitation with the data structure *gsfMBParams* which represents horizontal and vertical datums as integers. Only these datums have integer definitions in *gsf.h*.
- **Data record compression is not supported.**
- The current version of GSFLib library does provide text string translations for all error code returns; however, all definitions do not have unique values.
- The name of the *gsfSwathBathySummary* record implies that the data in this structure is specific to the Swath Bathy Ping Record. This is not the case; the data structure is implemented to represent the Summary Record as defined in the specification.

## 1.4 References

Generic Sensor Format Specification, 26 April 2019, Prepared for: Naval Oceanographic Office, Stennis Space Center, MS, by Leidos, 221 Third Street, Newport RI.

## 1.5 Distribution

The information in this document and the GSF library source code itself is unclassified and may be distributed without restriction. Copyright permission for the GSF sources is made available under the terms of LGPLv2.1. Releases of the GSF library are produced solely by Leidos. Leidos will receive and review source changes provided from contributors and review these with the GSF working group for consideration in future a future GSF release.

## 1.6 Sensors Supported

Multibeam echosounders

- Elac Bottomchart Mk II
- RESON SEABAT 9000 Series
- RESON 7125
- RESON 8101
- RESON 8111
- RESON 8124

- RESON 8125
- RESON 8150
- RESON 8160
- RESON T-SERIES (T-50, T-20)
- SeaBeam 2100 series
- Kongsberg EM12
- Kongsberg EM100
- Kongsberg EM120
- Kongsberg EM121
- Kongsberg EM121A
- Kongsberg EM122
- Kongsberg EM124
- Kongsberg EM300
- Kongsberg EM302
- Kongsberg EM710
- Kongsberg EM712
- Kongsberg EM950
- Kongsberg EM1000
- Kongsberg EM1002
- Kongsberg EM2000
- Kongsberg EM2040
- Kongsberg EM3000 and EM3000D
- Kongsberg EM3002 and EM3002D
- Kongsberg KMALL Systems
- Imagenex Delta-T
- R2Sonic 2022
- R2Sonic 2024
- R2Sonic 2020



## Interferrometric Side-Scan Systems

- SEAMAP
- GeoAcoustics GS+

## Multibeam Archival Formats

- Compressed SASS

## Single-beam Echosounders

- Odom Echotrac
- ODEC Bathy2000
- Reson Navisound

## Single-beam Archival Formats

- MGD77
- BDB
- NOS HDB

## Bathymetric Sidescan Systems

- Klein 5410

## 1.7 Computer Platforms Supported

The GSF library has been used on the following platforms:

- HP Series 7000 workstations running HP-UX 9.0, 10.0, and 11.0
- PCs running IBM OS/2, versions 2.0, 3.0 and 4.0, LINUX (32 bit and 64 bit), and WINDOWS NT, 2000, XP, 7, 8, 10
- Digital Alpha Workstation running Digital UNIX, version
- Silicon Graphics running IRIX 6.3
- Sun
- Mac OSX

In order to support files larger than two gigabytes, redefinitions of the standard functions `fopen`, `stat`, `ftell`, and `fseek` were made in `gsf.c` and `gsf_idx.c`. The function redefinitions are made in these `.c` files to avoid any un-intended redefinition affecting user application code. Compiler directives steer the redefinition of these functions for the appropriate underlying Operation System. The following combinations are supported: Windows using Microsoft Visual Studio and Mingw, Linux using gcc, and MacOS using gcc.

When compiling the source code in Linux, the `-D_LARGEFILE_SOURCE` flag must be used to provide access to the `fopen64`, `stat64`, `ftello64`, and `fseeko64` functions. When compiling in Windows/mingW, these functions are available without this define. When compiling in Windows/MSVC, the `_ftelli64` and `_fseeki64` functions are readily available.

## 1.8 Documentation Conventions

- References to GSF functions are **bolded**.
- References to GSF data structures or definitions are *italicized*.
- Function prototypes, function arguments and other references to C-language source code are in Courier type (e.g., `int`)

## 2. FUNCTION DEFINITIONS

The library function definitions in this section are in three functional categories, those used to access data, those used to perform utility functions, and those that provide information about the data.

### 2.1 Access Functions

Access functions include those used to open and close data files, read and write data and place the file pointer at various locations within the file.

#### 2.1.1 FUNCTION: GSFOpen

##### Usage:

```
int gsfoOpen(const char *filename,
             const int   mode     ,
             int         *handle  )
```

##### Description:

This function attempts to open a GSF data file. If the file exists and is opened for read-only or for update, the GSF header is read to confirm that this is a GSF data file. If the file is opened for creation, the GSF header containing the version number of the software library is written into the header. This function passes an integer handle back to the calling application. The handle is used for all further access to the file. **gsfoOpen** explicitly sets stream buffering to the value specified by *GSF\_STREAM\_BUF\_SIZE*. The internal file table is searched for an available entry whose name matches that specified in the argument list, if no match is found, then the first available entry is used. Up to *GSF\_MAX\_OPEN\_FILES* files may be open by an application at a time.

If a file is opened as *GSF\_READONLY\_INDEX* or *GSF\_UPDATE\_INDEX* a corresponding index file is expected to exist. If the index file exists, its contents are examined to determine if the GSF file has increased in size since the index file was created. If not, subsequent file accesses use the index file. If the index file does not exist, the **gsfoOpen** function automatically creates it. If the GSF file is larger than that recorded in the index file, the index file is updated to correspond to the new records in the GSF file.

##### Inputs:

`filename`     a fully qualified path to the GSF file to be opened

`mode` may have the following values:

- GSF\_READONLY* open an existing file for read-only access
- GSF\_UPDATE* open an existing file for reading and writing
- GSF\_CREATE* create a new GSF file
- GSF\_READONLY\_INDEX* open an existing file for read only access with an index file
- GSF\_UPDATE\_INDEX* open an existing file for reading and writing with an index file
- GSF\_APPEND* open an existing file for appending

`handle` a pointer to an integer to be assigned a handle which will be referenced for all future file access.

#### Returns:

This function returns zero if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

#### Error Conditions:

- GSF\_BAD\_ACCESS\_MODE*
- GSF\_FILE\_SEEK\_ERROR*
- GSF\_FLUSH\_ERROR*
- GSF\_FOPEN\_ERROR*
- GSF\_READ\_ERROR*
- GSF\_SETVBUF\_ERROR*
- GSF\_TOO\_MANY\_OPEN\_FILES*
- GSF\_UNRECOGNIZED\_FILE*
- GSF\_OPEN\_TEMP\_FILE\_FAILED*
- GSF\_CORRUPT\_INDEX\_FILE\_ERROR*
- GSF\_INDEX\_FILE\_OPEN\_ERROR*
- GSF\_FILE\_TELL\_ERROR*
- GSF\_MEMORY\_ALLOCATION\_FAILED*

## 2.1.2 FUNCTION: GSFOpenBuffered

### Usage:

```
int gsfoOpenBuffered(const char *filename,
                     const int  mode,
                     int        *handle,
                     int         buf_size)
```

### Description:

This function attempts to open a GSF data file. If the file exists and is opened read-only or for update, the GSF header is read to confirm that this is a GSF data file. If the file is opened for creation, the GSF header containing the version number of the software library is written into the header. This function passes an integer handle back to the calling application. The handle is used for all further access to the file. **gsfoOpenBuffered** explicitly sets stream buffering to the value specified by the `buf_size` argument. The internal file table is searched for an available entry whose name matches that specified in the argument list, if no match is found, then the first available entry is used. Up to *GSF\_MAX\_OPEN\_FILES* files may be open by an application at a time. **gsfoOpenBuffered** performs identical processing to **gsfoOpen** except that the caller is allowed to explicitly set the I/O buffer size.

If a file is opened as *GSF\_READONLY\_INDEX* or *GSF\_UPDATE\_INDEX*, a corresponding index file is expected to exist. If the index file exists, its contents are examined to determine if the GSF file has increased in size since the index file was created. If not, the index file is used for subsequent file accesses. If the index file does not exist, the **gsfoOpenBuffered** function automatically creates it. If the GSF file is larger than that recorded in the index file, the index file is updated to correspond to the new records in the GSF file.

### Inputs:

<code>filename</code>	a fully qualified path to the GSF file to be opened
-----------------------	---

`mode` may have the following values:

- GSF\_READONLY* open an existing file for read-only access
- GSF\_UPDATE* open an existing file for reading and writing
- GSF\_CREATE* create a new GSF file
- GSF\_READONLY\_INDEX* open an existing file for read-only access with an index file
- GSF\_UPDATE\_INDEX* open an existing file for reading and writing with an index file
- GSF\_APPEND* open an existing file for appending

`handle` a pointer to an integer to be assigned a handle which will be referenced for all future file access.

`buf_size` an integer buffer size in bytes.

#### Returns:

This function returns zero if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

#### Error Conditions:

- GSF\_BAD\_ACCESS\_MODE*
- GSF\_FILE\_SEEK\_ERROR*
- GSF\_FLUSH\_ERROR*
- GSF\_FOPEN\_ERROR*
- GSF\_READ\_ERROR*
- GSF\_SETVBUF\_ERROR*
- GSF\_TOO\_MANY\_OPEN\_FILES*
- GSF\_UNRECOGNIZED\_FILE*
- GSF\_OPEN\_TEMP\_FILE\_FAILED*
- GSF\_CORRUPT\_INDEX\_FILE\_ERROR*
- GSF\_INDEX\_FILE\_OPEN\_ERROR*
- GSF\_FILE\_TELL\_ERROR*

*GSF\_MEMORY\_ALLOCATION\_FAILED*

### 2.1.3 FUNCTION: GSFREAD

#### Usage:

```
int gsfRead(int          handle,
            int          desiredRecord,
            gsfdDataID   *dataID,
            gsfdRecords  *rpPtr,
            unsigned char *buf,
            int           max_size)
```

#### Description:

**gsfRead** supports both direct and sequential access. If the file is opened for sequential access, this function reads the desired record from the GSF data file specified by the handle. Setting the `desiredRecord` argument to *GSF\_NEXT\_RECORD* reads the next record in the data file. The `desiredRecord` argument may be set to specify the record of interest, such as an SVP record. In this case, the file is read, skipping past intervening records. After locating the desired record, it is read and decoded from external to internal form. If the data contains the optional checksum, the checksum is verified. All of the fields of the *gsfdDataID* structure, with the exception of the `record_number` field will be loaded with the values contained in the GSF record byte stream. For sequential access, the `record_number` field is undefined. The `buf` and `max_size` arguments are normally set to NULL, unless the calling application requires a copy of the GSF byte stream.

If the file is opened for direct access, then the combination of the `recordID` and the `record_number` fields of the *dataID* structure are used to uniquely identify the record of interest. The address for this record is retrieved from the index file, which was created on a previous call to **gsfOpen** or **gsfOpenBuffered**. If the record of interest is a ping record that needs new scale factors, the ping record containing the scale factors needed is read first, and then the ping record of interest is read. Direct access applications must set the `desiredRecord` argument equal to the `recordID` field in the *gsfdDataID* structure.

#### Inputs:

<code>handle</code>	the handle to the file as provided by <b>gsfOpen</b> or <b>gsfOpenBuffered</b>
<code>desiredRecord</code>	the desired record or <i>GSF_NEXT_RECORD</i>
<code>dataID</code>	a pointer to a <i>gsfdDataID</i> structure to be populated for the input record.
<code>rpPtr</code>	a pointer to a <i>gsfdRecords</i> structure to be populated with the data from the input record in internal form.



<code>buf</code>	an optional pointer to caller memory to be populated with a copy of the GSF byte stream for this record.
<code>max_size</code>	an optional maximum size to copy into <code>buf</code>

#### Returns:

This function returns the number of bytes read if successful or -1 if an error occurred. *gsfError* is set to indicate the error.

#### Error Conditions:

*GSF\_ATTITUDE\_RECORD\_DECODE\_FAILED*  
*GSF\_BAD\_FILE\_HANDLE*  
*GSF\_CHECKSUM\_FAILURE*  
*GSF\_COMMENT\_RECORD\_DECODE\_FAILED*  
*GSF\_FILE\_SEEK\_ERROR*  
*GSF\_FLUSH\_ERROR*  
*GSF\_HEADER\_RECORD\_DECODE\_FAILED*  
*GSF\_HISTORY\_RECORD\_DECODE\_FAILED*  
*GSF\_HV\_NAV\_ERROR\_RECORD\_DECODE\_FAILED*  
*GSF\_INSUFFICIENT\_SIZE*  
*GSF\_NAV\_ERROR\_RECORD\_DECODE\_FAILED*  
*GSF\_PROCESS\_PARAM\_RECORD\_DECODE\_FAILED*  
*GSF\_READ\_ERROR*  
*GSF\_READ\_TO\_END\_OF\_FILE*  
*GSF\_PARTIAL\_RECORD\_AT\_END\_OF\_FILE*  
*GSF\_RECORD\_SIZE\_ERROR*  
*GSF\_SENSOR\_PARAM\_RECORD\_DECODE\_FAILED*  
*GSF\_SUMMARY\_RECORD\_DECODE\_FAILED*  
*GSF\_SVP\_RECORD\_DECODE\_FAILED*

*GSF\_UNRECOGNIZED\_RECORD\_ID*  
*GSF\_UNRECOGNIZED\_SUBRECORD\_ID*  
*GSF\_INVALID\_RECORD\_NUMBER*  
*GSF\_RECORD\_TYPE\_NOT\_AVAILABLE*  
*GSF\_INDEX\_FILE\_READ\_ERROR*  
*GSF\_QUALITY\_FLAGS\_DECODE\_ERROR*

#### 2.1.4 FUNCTION: GSFWRITE

##### Usage:

```
int gsfWrite(int          handle,  
             gsfdDataID *id,  
             gsfdRecords *rptr)
```

##### Description:

**gsfWrite** encodes the data from internal to external form, and then writes the requested record into the file specified by handle, where handle is the value returned by either **gsfOpen** or **gsfOpenBuffered**. The record is written to the current file pointer for handle. An optional checksum may be computed and encoded with the data if the checksum flag is set in the *gsfdDataID* structure. If the file is opened for sequential access (*GSF\_CREATE*, or *GSF\_UPDATE*) then the *recordID* field of the *gsfdDataID* structure is used to specify the record to be written.

When opening the file for direct access (*GSF\_UPDATE\_INDEX*), the combination of the *recordID* and the *record\_number* fields of the *gsfdDataID* structure uniquely identify the record to write. The address of the record of interest is read from the index file and the file pointer is moved to this offset before the record is encoded and written to disk.

##### Inputs:

<i>handle</i>	the handle for this file as returned by <b>gsfOpen</b>
<i>id</i>	a pointer to a <i>gsfdDataID</i> containing the record ID information for the record to write.
<i>rptr</i>	a pointer to a <i>gsfdRecords</i> structure from which to get the internal form of the record to be written to the file.

### Returns:

This function returns the number of bytes written if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

### Error Conditions:

*GSF\_ATTITUDE\_RECORD\_ENCODE\_FAILED*  
*GSF\_BAD\_FILE\_HANDLE*  
*GSF\_COMMENT\_RECORD\_ENCODE\_FAILED*  
*GSF\_FILE\_SEEK\_ERROR*  
*GSF\_FLUSH\_ERROR*  
*GSF\_HEADER\_RECORD\_ENCODE\_FAILED*  
*GSF\_HISTORY\_RECORD\_ENCODE\_FAILED*  
*GSF\_HV\_NAV\_ERROR\_RECORD\_ENCODE\_FAILED*  
*GSF\_NAV\_ERROR\_RECORD\_ENCODE\_FAILED*  
*GSF\_PROCESS\_PARAM\_RECORD\_ENCODE\_FAILED*  
*GSF\_SENSOR\_PARAM\_RECORD\_ENCODE\_FAILED*  
*GSF\_SINGLE\_BEAM\_ENCODE\_FAILED*  
*GSF\_SUMMARY\_RECORD\_ENCODE\_FAILED*  
*GSF\_SVP\_RECORD\_ENCODE\_FAILED*  
*GSF\_UNRECOGNIZED\_RECORD\_ID*  
*GSF\_UNRECOGNIZED\_SENSOR\_ID*  
*GSF\_WRITE\_ERROR*  
*GSF\_ILLEGAL\_SCALE\_FACTOR\_MULTIPLIER*  
*GSF\_INVALID\_RECORD\_NUMBER*  
*GSF\_RECORD\_TYPE\_NOT\_AVAILABLE*  
*GSF\_INDEX\_FILE\_READ\_ERROR*

### 2.1.5 FUNCTION: GSFSEEK

### Usage:

```
int gsfSeek(int handle,  
            int option)
```

#### Description:

This function moves the file pointer for a previously opened GSF file.

#### Inputs:

`handle` the integer handle returned from **gsfOpen** or `gsfOpenBuffered`

`option` the desired action for moving the file pointer, where:

`GSF_REWIND` moves the pointer to first record in the file.

`GSF_END_OF_FILE` moves the pointer to the end of the file.

`GSF_PREVIOUS_RECORD` backup to the beginning of the record just written or just read.

#### Returns:

This function returns zero if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

#### Error Conditions:

`GSF_BAD_FILE_HANDLE`

`GSF_BAD_SEEK_OPTION`

`GSF_FILE_SEEK_ERROR`

`GSF_FLUSH_ERROR`

#### 2.1.6 FUNCTION: GSFCLOSE

#### Usage:

```
int gsfClose(const int handle)
```

#### Description:

This function closes a GSF file previously opened using **gsfOpen** or `gsfOpenBuffered`.

Inputs:

`handle`                      the handle of the GSF file to be closed.

Returns:

This function returns zero if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

Error Conditions:

`GSF_BAD_FILE_HANDLE`

`GSF_FILE_CLOSE_ERROR`

## 2.2 Utility Functions

Utility functions include those used to copy records, to free memory and to access multibeam processing parameters and scale factors.

### 2.2.1 FUNCTION: GSFCOPYRECORDS

#### Usage:

```
int gsfcopyRecords (gsfRecords *target,  
                   const gsfRecords *source)
```

#### Description:

This function copies all of the data contained in the source *gsfRecords* data structure to the target *gsfRecords* data structure. The target *must* be memset to zero before the first call to **gsfcopyRecords**. This function allocates dynamic memory that is NOT maintained by the library. The calling application must release the memory allocated by maintaining the target data structure as static data, or by using **gsffree** to release the memory.

#### Inputs:

<code>target</code>	a pointer to a <i>gsfRecords</i> data structure allocated by the calling application, into which the source data is to be copied.
<code>source</code>	a pointer to a <i>gsfRecords</i> data structure allocated by the calling application, from which data is to be copied.

#### Returns:

This function returns zero if successful, or -1 if an error occurs. *gsfError* is set to indicate the error.

#### Error Conditions:

*GSF\_MEMORY\_ALLOCATION\_FAILED*

### 2.2.2 FUNCTION: GSFFREE

#### Usage:

```
void gsffree (gsfRecords *rec)
```

### Description:

This function frees all dynamically allocated memory from a *gsfRecords* data structure, and then clears all the data elements in the structure.

### Inputs:

<code>rec</code>	pointer to a <i>gsfRecords</i> data structure
------------------	---

### Returns:

None

### Error Conditions:

None

## 2.2.3 FUNCTION: GSFPUTMBPARAMS

### Usage:

```
int gsfPutMBParams(const gsfMBParams *p,
                  gsfRecords *rec,
                  int handle,
                  int numArrays)
```

### Description:

This function moves swath bathymetry sonar processing parameters from internal form to "KEYWORD=VALUE" form. The internal form parameters are read from an *gsfMBParams* data structure maintained by the caller. The "KEYWORD=VALUE" form parameters are written into the *gsfProcessingParameters* structure of the *gsfRecords* data structure maintained by the caller. Parameters for up to two transmitter array modules and two receiver array modules are supported. If the user sets the 'number\_of\_transmitters' and 'number\_of\_receivers' elements in the *gsfMBParams* data structure in addition to the 'numArrays' command line argument, the 'numArrays' value will be ignored. If 'number\_of\_transmitters' and 'number\_of\_receivers' are equal to 0, then 'numArrays' will be used to populate both these values in the GSF processing parameters record.

### Inputs:

<code>p</code>	a pointer to the <i>gsfMBParams</i> data structure which contains the parameters in internal form.
<code>rec</code>	a pointer to the <i>gsfRecords</i> data structure into which the parameters are to be written in the "KEYWORD=VALUE" form.
<code>handle</code>	the integer handle to the file set by <b>gsfOpen</b> or <code>gsfOpenBuffered</code>
<code>numArrays</code>	the integer value specifying the number of pairs of arrays that need to have separate parameters tracked.

#### Returns:

This function returns zero if successful, or -1 if an error occurs. *gsfError* is set to indicate the error.

#### Error Conditions:

*GSF\_MEMORY\_ALLOCATION\_FAILED*

*GSF\_PARAM\_SIZE\_FIXED*

## 2.2.4 FUNCTION: GSFGETMBPARAMS

#### Usage:

```
int gsfGetMBParams(const gsfRecords *rec,
                  gsfMBParams *p,
                  int *numArrays)
```

#### Description:

This function moves swath bathymetry sonar processing parameters from external form to internal form. The external "KEYWORD=VALUE" format parameters are read from a *gsfProcessingParameters* structure of the *gsfRecords* data structure maintained by the caller. Any parameter not described in a "KEYWORD=VALUE" format will be set to "GSF\_UNKNOWN\_PARAM\_VALUE". The internal form parameters are written into a *gsfMBParams* data structure maintained by the caller. Parameters for up to two transmitters and two receivers are supported. The 'number\_of\_transmitters' and 'number\_of\_receivers' elements of the *gsfMBParams* data structure are set by determining the number



of fields in the parameters for the transmitter(s) and receiver(s), respectively. The 'numArrays' argument is set from the number of fields for the transmitter(s).

#### Inputs:

<code>rec</code>	a pointer to the <i>gsfRecords</i> data structure from which the parameters in "KEYWORD=VALUE" form are to be read.
<code>p</code>	a pointer to the <i>gsfMBParams</i> data structure which will be populated.
<code>numArrays</code>	the integer value specifying the number of pairs of arrays which need to have separate parameters tracked.

#### Returns:

This function returns zero if successful, or -1 if an error occurs. *gsfError* is set to indicate the error.

#### Error Conditions:

None.

### 2.2.5 FUNCTION: GSFSTAT

#### Usage:

```
int gsfStat(char *filename, long long *sz)
```

#### Description:

This function attempts to stat a GSF file. Supports 64 bit file size.

#### Inputs:

<code>filename</code>	A fully qualified path to the GSF file.
<code>sz</code>	A pointer to an 8 byte long long for return of a GSF file size from a stat64 call.

#### Returns:

This function returns zero if successful, or -1 if an error occurs.

#### Error Conditions:

*GSF\_FOPEN\_ERROR*

## 2.2.6 FUNCTION: GSFLOADSCALEFACTOR

Usage:

```
int gsfLoadScaleFactor(gsfScaleFactors *sf,
                      int          subrecordID,
                      char         c_flag,
                      double       precision,
                      int          offset)
```

Description:

**gsfLoadScaleFactor** is used to load the swath bathymetry ping record scale factor structure. This function allows the calling application to specify the precision and offset values used to scale the data from internal form (engineering units) to external form (scaled integer). This function need only be used by applications that are creating a new GSF file from some other data format, or by applications that are updating the numerical values of the beam arrays. In these cases, the application program needs to be aware of the desired data resolution for each beam array and the available dynamic range for each beam array. This is necessary to achieve the desired resolution while avoiding an overflow of the scaled dynamic range. The library does not monitor the scaled values for field level overflow, and no error value will be returned if an overflow occurs. This function should be called at least once for each beam array data type contained in your data, and must be called prior to calling **gsfWrite** by applications creating a new GSF file.

**gsfLoadScaleFactor** can be called for each beam array before each call to **gsfWrite** to achieve the proper field resolution for each ping record. **gsfLoadScaleFactor** populates the *gsfScaleFactors* sub-structure contained within the *gsfRecords* structure. **gsfWrite** will encode the optional *gsfScaleFactors* sub-record once at the beginning of the data file and again whenever the scale factor values change. Once written, the offset and precision for each beam array remain in effect for subsequent data records until the scale factors are changed. On encode from internal form to external form, each beam array value is scaled by adding the specified offset and multiplying by one over the specified precision, or:

$$scaled\_value = (beam\_value + offset) / precision$$

On decode from external form to internal form, the inverse operation is performed, or:

$$beam\_value = \frac{(scaled\_value / precision) - offset}{1}$$

Table 2-1 describes the storage available for each of the array values, and shows the dynamic range of the external form value after the offset and multiplier scaling values are applied. It should be noted that some of the beam arrays support more than one option for the field size. When first creating a GSF file, the calling application can specify the desired field size via the `c_flag` argument to the **gsfLoadScaleFactor** function. The default field size values for each beam array are listed in the table below. The field size is set by using one of the field size macros defined in `gsf.h`. Supported values include: `GSF_FIELD_SIZE_DEFAULT`, `GSF_FIELD_SIZE_ONE`, `GSF_FIELD_SIZE_TWO`, and `GSF_FIELD_SIZE_FOUR`. Once the field size has been set this value cannot be changed without rewriting the entire GSF file.

**Table 2-1 GSF Beam Array Field Size Definitions**

Array Subrecord	Data Representation	Size, bits	Scaled Dynamic Range
DEPTH	unsigned short (default)	16	0 to 65535
	unsigned int (option)	32	0 to 4294967295
NOMINAL_DEPTH	unsigned short (default)	16	0 to 65535
	unsigned int (option)	32	0 to 4294967295
ACROSS_TRACK	signed short (default)	16	-32768 to 32767
	signed int (option)	32	-2147483648 to 2147483647
ALONG_TRACK	signed short (default)	16	-32768 to 32767
	signed int (option)	32	-2147483648 to 2147483647
TRAVEL_TIME	unsigned short (default)	16	0 to 65535
	unsigned int (option)	32	0 to 4294967295
BEAM_ANGLE	signed short	16	-32768 to 32767
MEAN_CAL_AMPLITUDE	signed byte (default)	8	-128 to 127
	signed short (option)	16	-32768 to 32767
MEAN_REL_AMPLITUDE	unsigned byte (default)	8	0 to 255
	unsigned short (option)	16	0 to 65535
ECHO_WIDTH	unsigned byte (default)	8	0 to 255

	unsigned short (option)	16	0 to 65535
QUALITY_FACTOR	unsigned byte	8	0 to 255
RECEIVE_HEAVE	signed byte	8	-128 to 127
DEPTH_ERROR	unsigned short	16	0 to 65535
ACROSS_TRACK_ERROR	unsigned short	16	0 to 65535
ALONG_TRACK_ERROR	unsigned short	16	0 to 65535
QUALITY_FLAGS	unsigned byte	8	0 to 255
BEAM_FLAGS	unsigned byte	8	0 to 255
SIGNAL_TO_NOISE	signed byte	8	-128 to 127
BEAM_ANGLE_FORWARD	signed short	16	-32768 to 32767
VERTICAL_ERROR	unsigned short	16	0 to 65535
HORIZONTAL_ERROR	unsigned short	16	0 to 65535
SECTOR_NUMBER	unsigned byte	8	0 to 255
DETECTION_INFO	unsigned byte	8	0 to 255
INCIDENT_BEAM_ADJUSTEMENT	signed byte	8	-128 to 127
SYSTEM_CLEANING	unsigned byte	8	0 to 255
DOPPLER_CORRECTION	signed byte	8	-128 to 127

#### Inputs:

<code>sf</code>	a pointer to the <i>gsfScaleFactors</i> structure to be loaded
<code>subrecordID</code>	the subrecord id for the beam array data
<code>c_flag</code>	the compression flag for the beam array. This is a bit mask that combines the caller specified field size in the higher order four bits with the lower four bits reserved for future use to specify a compression algorithm. The supported field size values are defined as macros in <i>gsf.h</i> ( <i>GSF_FIELD_SIZE_DEFAULT</i> , etc).
<code>precision</code>	the precision to which the beam array data are to be stored(a value of 0.1 would indicate decimeter precision for depth)
<code>offset</code>	the "DC" offset to scale the data by.

### Returns:

This function returns zero if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

### Error Conditions:

*GSF\_CANNOT\_REPRESENT\_PRECISION*

*GSF\_TOO\_MANY\_ARRAY\_SUBRECORDS*

## 2.2.7 FUNCTION: GSFGETSCALEFACTOR

### Usage:

```
int gsfGetScaleFactor(int          handle,
                      int          subrecordID,
                      unsigned char *c_flag,
                      double        *multiplier,
                      double        *offset)
```

### Description:

**gsfGetScaleFactor** is used to obtain the beam array field size, compression flag, multiplier and DC offset values by which each swath bathymetry ping array subrecord is scaled. **gsfGetScalesFactor** is called once for each array subrecord of interest. At least one swath bathymetry ping record must have been read from, or written to, the file specified by handle prior to calling **gsfGetScaleFactor**.

### Inputs:

Handle	the integer value set by a call to <b>gsfOpen</b> or <b>gsfOpenBuffered</b> .
subrecordID	an integer value containing the subrecord id of the requested scale factors
c_flag	the address of an unsigned character to contain the optional beam array field size in the high order four bits, and the optional compression flag in the low order four bits. If the field size is not specified the default will be used. The high order four bits (beam_array_field_size) will be set to one of the following values: <i>GSF_FIELD_SIZE_DEFAULT</i> , <i>GSF_FIELD_SIZE_ONE</i> , <i>GSF_FIELD_SIZE_TWO</i> , or <i>GSF_FIELD_SIZE_FOUR</i> .

`multiplier`                      the address of a double to contain the scaling multiplier

`offset`                            the address of a double to contain the scaling DC offset.

Returns:

This function returns zero if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

Error Conditions:

*GSF\_BAD\_FILE\_HANDLE*

*GSF\_ILLEGAL\_SCALE\_FACTOR\_MULTIPLIER*

*GSF\_TOO\_MANY\_ARRAY\_SUBRECORDS*

2.2.8    FUNCTION: GSFSETDEFAULTSCALEFACTOR

Usage:

```
int gsfSetDefaultScaleFactor(gsfSwathBathyPing *mb_ping)
```

Description:

`gsfSetDefaultScaleFactor` is a convenience function used to convert files stored in a vendor format to the `gsf` format. The function estimates reasonable scale factors for each of the arrays in the ping record. The function will estimate based on the default compression size and set the values of the ping's scale factors. This function requires some overhead as it will perform operations on each beam in each array contained in the ping record.

Inputs:

<code>mb_ping</code>	a pointer to the <i>gsfSwathBathyPing</i> which contains the beam arrays and will contain the estimated scale factors upon returning from the function.
----------------------	---

Returns:

The function returns 0 to indicate success.

### Error Conditions:

None.

## 2.2.9 FUNCTION: GSFLOADDEPTHSCALEFACTORAUTOOFFSET

### Usage:

```
int gsfLoadDepthScaleFactorAutoOffset(gsfSwathBathyPing *ping,
                                     int subrecordID,
                                     int reset,
                                     double min_depth,
                                     double max_depth,
                                     double *last_corrector,
                                     char c_flag,
                                     double precision)
```

### Description:

**gsfLoadDepthScaleFactorAutoOffset** may be used to load the scale factors for the depth subrecords of the swath bathymetry ping record scale factor structure. The function uses the tide and depth correction fields to help establish the offset component of the scale factor such that negative depth values may be supported. Negative depth values may be encountered when surveying above the tidal datum. In addition, this function may be used for systems mounted on subsea platforms where high depth precision may be supported even in deep water.

### Inputs:

<code>ping</code>	a pointer to the <i>gsfSwathBathyPing</i> which contains the depth and tide correction values, and the scale factors data structure.
<code>subrecordID</code>	an integer value containing the subrecord ID for the beam array data; this must be either <code>GSF_SWATH_BATHY_SUBRECORD_DEPTH_ARRAY</code> , or <code>GSF_SWATH_BATHY_SUBRECORD_NOMINAL_DEPTH_ARRAY</code> .
<code>reset</code>	an integer value that will cause the internal logic to be refreshed when the value is non-zero; the first call to this function should use a non-zero reset, from then on, this value may be passed as zero.

<code>min_depth</code>	a double value that should be set to the minimum depth value contained in the depth array specified by subrecordID; this argument exists for completeness, but is currently not used.
<code>max_depth</code>	a double value that should be set to the maximum depth value contained in the depth array specified by subrecordID; when a depth threshold is exceeded, the offset used to support “signed depth” is no longer required and will no longer be used. This approach is necessary to avoid an integer overflow when the array data are scaled.
<code>last_corrector</code>	an address of a double value stored as permanent memory; successive calls to this function must pass the same address for this argument. This function will take care of setting the value at this address, but the caller is responsible for ensuring that the same permanent memory address is used for each call to this function.
<code>C_flag</code>	the compression flag for the beam array. This is a bit mask that combines the (optional) caller specified field size in the higher order four bits with the lower four bits reserved for future use to specify a compression algorithm. The supported field size values are defined as macros in <code>gsf.h</code> ( <code>GSF_FIELD_SIZE_DEFAULT</code> , etc). See section 2.2.5 on <b>gsfLoadScaleFactor</b> for more information.
<code>precision</code>	the precision to which the beam array data are to be stored (a value of 0.1 would indicate decimeter precision for depth).

#### Returns:

This function returns zero if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

#### Error Conditions:

*GSF\_UNRECOGNIZED\_ARRAY\_SUBRECORD\_ID*

*GSF\_CANNOT\_REPRESENT\_PRECISION*

*GSF\_TOO\_MANY\_ARRAY\_SUBRECORDS*

### 2.2.10 FUNCTION: GSFGETPOSITIONDESTINATION

#### Usage:

```
GSF_POSITION gsfGetPositionDestination(GSF_POSITION gp,
                                       GSF_POSITION_OFFSETS offsets,
                                       double heading,
                                       double dist_step)
```



### Description:

This function calculates a destination position using the 'metric' function as an iterative process. The number of iterations is calculated by dividing each offset by the 'dist\_step' input and using the largest value. The offsets are then evenly divided by the number of iterations and applied to calculate the final destination position.

### Inputs:

<code>gp</code>	Reference position (typically ping position, in degrees).
<code>offsets</code>	XYZ offsets from the reference position (in meters).
<code>heading</code>	Platform heading (in degrees).
<code>dist_step</code>	Distance increment used in step-wise calculation to destination.

### Returns:

This function returns the destination position.

### Error Conditions:

None.

## 2.2.11 FUNCTION: GSFGETPOSITIONOFFSETS

### Usage:

```
GSF_POSITION_OFFSETS gsfGetPositionOffsets(GSF_POSITION gp_from,  
                                           GSF_POSITION gp_to,  
                                           double heading,  
                                           double dist_step)
```

### Description:

This function calculates position offsets from the reference position to the destination position using the 'metric' function as an iterative process. The number of iterations is calculated by dividing the distance between the positions by the 'dist\_step' input. The offsets are calculated by applying the number of iterations to the calculation.

### Inputs:

<code>gp_from</code>	Reference position (in degrees).
----------------------	----------------------------------

<code>gp_to</code>	Destination position (in degrees).
<code>heading</code>	Platform heading (in degrees).
<code>dist_step</code>	Distance increment used in step-wise calculation to destination (typically 5 – 10 meters).

**Returns:**

This function returns the offsets from the reference position to the destination position.

**Error Conditions:**

None.

## 2.2.12 MACRO: GSFTESTPINGSTATUS

**Usage:**

```
unsigned short gsftestPingStatus(ping_flags, usflag)
```

**Description:**

This function returns the value of a single flag within the `ping_flags` field of the *gsfSwathBathymetry* record

**Inputs:**

<code>ping_flags</code>	The contents of the <code>ping_flags</code> field.
<code>usflag</code>	An unsigned short integer with a single bit set to identify the flag being tested.

**Returns:**

This macro returns TRUE if the bit within `ping_flags`, which corresponds to the bit set in `usflags`, is set. Otherwise, the macro returns FALSE.

**Error Conditions:**

None

### 2.2.13 MACRO: GSFSETPINGSTATUS

#### Usage:

```
unsigned short gsfsSetPingStatus(ping_flags, usflag)
```

#### Description:

This function sets a bit within the within the `ping_flags` field of the *gsfSwathBathymetry* record

#### Inputs:

<code>ping_flags</code>	The original contents of the <code>ping_flags</code> field.
<code>usflag</code>	An unsigned short integer with a single bit set to identify the flag to be set.

#### Returns:

A new copy of the `ping_flags` field with the corresponding bit set.

#### Error Conditions:

None

### 2.2.14 MACRO: GSFCLEARPINGSTATUS

#### Usage:

```
unsigned short gsfcClearPingStatus(ping_flags, usflag)
```

#### Description:

This function clears a bit within the within the `ping_flags` field of the *gsfSwathBathymetry* record.

#### Inputs:

<code>ping_flags</code>	The original contents of the <code>ping_flags</code> field.
-------------------------	---

`usflag`      An unsigned short integer with a single bit set to identify the flag to be cleared.

**Returns:**

A new copy of the `ping_flags` field with the corresponding bit cleared.

**Error Conditions:**

None

## **2.3 Information Functions**

Information functions include those that

- decode error conditions,
- return the time associated with a record at a specific location,
- return the location of the file pointer as a percentage of the total file size,
- provide the number and types of records within a file,
- provide information about beam widths of various types of sonar data
- for sonars with two transducers, determine whether a specific data record is from the starboard or port transducer.
- provide the name of the sensor

### **2.3.1 FUNCTION: GSFINTERROR**

**Usage:**

```
int gsfIntError(void)
```

**Description:**

This function returns the integer code for the most recent error encountered. Call this function if a -1 is returned from one of the GSF functions.

**Inputs:**

None

Returns:

The current value of gsfError

Error Conditions:

None

2.3.2 FUNCTION: GSFPRINTERERROR

Usage:

```
void gsfPrintError(FILE * fp)
```

Description:

This function prints a short message describing the most recent error encountered. Call this function if a -1 is returned from one of the GSF functions.

Inputs:

fp      a pointer to a FILE to which the message is written.

Returns:

None

Error Conditions:

None

2.3.3 FUNCTION: GSFSTRINGERROR

Usage:

```
char *gsfStringError(void);
```

Description:

This function returns a short message describing the most recent error encountered. Call this function if a -1 is returned from one of the gsf functions.

Inputs:

None

Returns:

Pointer to a string containing the text message.

Error Conditions:

None

## 2.3.4 FUNCTION: GSFINDEXTIME

Usage:

```
int gsfIndexTime(int    handle,  
                 int     record_type,  
                 int     record_number,  
                 time_t  *sec,  
                 long    *nsec)
```

Description:

This function returns the time associated with a specified record number and type. It also returns the record number that was read.

Inputs:

<code>handle</code>	GSF file handle assigned by <b>gsfOpen</b> or <b>gsfOpenBuffered</b>
<code>record_type</code>	record type to be retrieved
<code>record_number</code>	record number to be retrieved (Setting this argument to -1 will get the time and record number of the last record of type <code>record_type</code> )

<code>sec</code>	Seconds since the beginning of the epoch (as defined in the GSF processing parameter record.)
<code>nsec</code>	Nanoseconds since the beginning of the second.

#### Returns:

This function returns the record number if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

#### Error Conditions:

*GSF\_FILE\_SEEK\_ERROR*

*GSF\_INDEX\_FILE\_READ\_ERROR*

*GSF\_RECORD\_TYPE\_NOT\_AVAILABLE*

### 2.3.5 FUNCTION: GSFPERCENT

#### Usage:

```
int gsfPercent (int handle)
```

#### Description:

This function returns the location of the file pointer expressed as a percentage of the total file size. It may obtain an indication of how far along a program is in reading a GSF data file. The file size is obtained when the file is opened. If the file is being updated by another program, the value returned will be in error and will reflect the percentage based on the file's size at the time that calling program opened the file.

#### Inputs:

<code>handle</code>	gsf file handle assigned by <b>gsfOpen</b> or <b>gsfOpenBuffered</b>
---------------------	--

#### Returns:

This function returns the current file position as a percentage of the file size, or -1 if an error occurred. *gsfError* is set to indicate the error.

Error Conditions:

*GSF\_BAD\_FILE\_HANDLE*

*GSF\_FILE\_TELL\_ERROR*

### 2.3.6 FUNCTION: GSFGETNUMBERRECORDS

Usage:

```
int gsfGetNumberRecords (int handle,  
                          int desiredRecord)
```

Description:

This function returns the number of records of a given type. The number of records is retrieved from the index file, so the file must have been opened for direct access (*GSF\_READONLY\_INDEX*, or *GSF\_UPDATE\_INDEX*).

Inputs:

<i>handle</i>	the handle to the file as provided by <b>gsfOpen</b> or <b>gsfOpenBuffered</b>
<i>desiredRecord</i>	the desired record or <i>GSF_NEXT_RECORD</i>

Returns:

This function returns the number of records of type *desiredRecord* contained in the GSF file designated by *handle*, or -1 if an error occurred. *gsfError* is set to indicate the error.

Error Conditions:

*GSF\_BAD\_FILE\_HANDLE*

*GSF\_BAD\_ACCESS\_MODE*

*GSF\_UNRECOGNIZED\_RECORD\_ID*



### 2.3.7 FUNCTION: GSFGETSWATHBATHYBEAMWIDTHS

#### Usage:

```
int gsfGetSwathBathyBeamWidths(const gsfRecords *data,  
                                double      *fore_aft,  
                                double      *athwartship)
```

#### Description:

This function returns to the caller the fore-aft and the port-starboard beam widths in degrees for a swath bathymetry multibeam sonar, given a *gsfRecords* data structure containing a populated *gsfSwathBathyPing* structure.

#### Inputs:

<code>data</code>	The address of a <i>gsfRecords</i> data structure maintained by the caller which contains a populated <i>gsfSwathBathyPing</i> substructure.
<code>fore_aft</code>	The address of a double allocated by the caller which will be loaded with the sonar's fore/aft beam width in degrees. A value of GSF_BEAM_WIDTH_UNKNOWN is used when the beam width is not known.
<code>athwartship</code>	The address of a double allocated by the caller which will be loaded with the sonar's athwartship beam width in degrees. A value of GSF_BEAM_WIDTH_UNKNOWN is used when the beam width is not known.

#### Returns:

This function returns zero if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

#### Error Conditions:

None.

### 2.3.8 FUNCTION: GSFGETSWATHBATHYARRAYMINMAX

#### Usage:

```
int gsfGetSwathBathyArrayMinMax(const gsfSwathBathyPing *ping,
```

```

int            subrecordID,
double         *min_value,
double         *max_value)

```

#### Description:

This function returns to the caller the minimum and maximum supportable values for each of the swath bathymetry arrays. The minimum and maximum values are determined based on the scale factors and the array type.

#### Inputs:

<code>ping</code>	The address of a <i>gsfSwathBathyPing</i> data structure that contains the depth and tide correction values, as well as the scale factors data structure.
<code>subrecordID</code>	The subrecord ID for the beam array data.
<code>min_value</code>	The address of a double value allocated by the caller into which will be placed the minimum value that may be represented for this array type.
<code>max_value</code>	The address of a double value allocated by the caller into which will be placed the maximum value that may be represented for this array type.

#### Returns:

This function returns zero if successful, or -1 if an error occurred. *gsfError* is set to indicate the error.

#### Error Conditions:

```

GSF_UNRECOGNIZED_ARRAY_SUBRECORD_ID
GSF_ILLEGAL_SCALE_FACTOR_MULTIPLIER

```

### 2.3.9 FUNCTION: GSFISSTARBOARDPING

#### Usage:

```
int gsfIsStarboardPing(const gsfRecords *data)
```

#### Description:

This function uses the sonar specific portion of a *gsfSwathBathymetry* ping structure to determine if the ping is from the starboard arrays of a multibeam installation with dual transducers.

#### Inputs:

`data`     The address of a *gsfRecords* data structure maintained by the caller containing a populated *gsfSwathBathyPing* substructure.

#### Returns:

This function returns non-zero if the ping contained in the passed data represents a starboard looking ping from a dual headed sonar installation. Otherwise, zero is returned. If the sonar does not have dual transducers, a value of zero will be returned.

#### Error Conditions:

None

### 2.3.10 FUNCTION: GSF\_REGISTER\_PROGRESS\_CALLBACK

#### Usage:

```
void gsf_register_progress_callback(GSF_PROGRESS_CALLBACK progressCB)
```

#### Description:

This function registers a callback function, defined by the user, to be called to report the progress of the index file creation. If no progress callback is registered, status is printed to stdout if the `DISPLAY_SPINNER` macro is defined during compilation of the GSF library.

#### Inputs:

`progressCB`     The name of the progress callback function to call when creating the GSF index file. The progress callback will accept two integer arguments, and this function will be called whenever

the percent complete changes. This first argument will be one of the following three values, to represent the state of the progress:

1 = Reading GSF file

2 = Creating new index file

3 = Appending to existing index file

The second argument contains the percent complete of the current state.

Returns:

None

Error Conditions:

None

### 2.3.11 FUNCTION: GSFGETSONARTEXTNAME

Usage:

```
char *gsfGetSonarTextName(const gsfSwathBathyPing *ping)
```

Description:

This function returns the name of the sensor based on the sensor id contained in the ping structure.

Inputs:

Ping	The address of a <i>gsfSwathBathyPing</i> data structure that contains the sensor_id value, as well as the mode value (mode is used for the Reson SeaBat 9001, 9002, and 9003)
------	--

Returns:

Pointer to a string containing the sensor name, or “Unknown” if the sensor id is not defined.

Error Conditions:

None

### 2.3.12 FUNCTION: GSFFILESUPPORTSRECALCULATEXYZ

**Usage:** `int gsfFileSupportsRecalculateXYZ(int handle, int *status)`

**Description:** This function reads the GSF file referenced by handle and determines if the file contains sufficient information to support a full recalculation of the platform relative XYZ values from raw measurements. This function rewinds the file to the first record and reads through the file looking for the information required to support a full swath recalculation from raw measurements and supporting navigation, attitude, SVP and installation offset information. On success, the file pointer is reset to the beginning of the file before the function returns.

#### Inputs:

handle	GSF file handle assigned by <b>gsfOpen</b> or <b>gsfOpenBuffered</b>
status	A pointer to an integer allocated by caller into which the function result is placed. *status is assigned a value of 1 if this file provides sufficient information to support full recalculation of the platform relative XYZ values, otherwise *status is assigned a value of 0.

**Returns:** This function returns zero if successful or -1 if an error occurred.

#### Error Conditions:

GSF\_BAD\_FILE\_HANDLE  
GSF\_FILE\_SEEK\_ERROR  
GSF\_FLUSH\_ERROR  
GSF\_READ\_TO\_END\_OF\_FILE  
GSF\_PARTIAL\_RECORD\_AT\_END\_OF\_FILE  
GSF\_READ\_ERROR  
GSF\_RECORD\_SIZE\_ERROR  
GSF\_INSUFFICIENT\_SIZE  
GSF\_CHECKSUM\_FAILURE  
GSF\_UNRECOGNIZED\_RECORD\_ID

GSF\_HEADER\_RECORD\_DECODE\_FAILED

GSF\_SVP\_RECORD\_DECODE\_FAILED

GSF\_PROCESS\_PARAM\_RECORD\_DECODE\_FAILED

GSF\_SENSOR\_PARAM\_RECORD\_DECODE\_FAILED

GSF\_COMMENT\_RECORD\_DECODE\_FAILED

GSF\_HISTORY\_RECORD\_DECODE\_FAILED

GSF\_NAV\_ERROR\_RECORD\_DECODE\_FAILED

GSF\_ATTITUDE\_RECORD\_DECODE\_FAILED

GSF\_HV\_NAV\_ERROR\_RECORD\_DECODE\_FAILED

GSF\_SUMMARY\_RECORD\_DECODE\_FAILED

GSF\_UNRECOGNIZED\_SUBRECORD\_ID

GSF\_INVALID\_RECORD\_NUMBER

GSF\_RECORD\_TYPE\_NOT\_AVAILABLE

GSF\_INDEX\_FILE\_READ\_ERROR

### 2.3.13 FUNCTION: GSFFILESUPPORTSRECALCULATETPU

**Usage:** `int gsffileSupportsRecalculateTPU(int handle, int *status)`

**Description:** This function reads the GSF file referenced by handle and determines if the file contains sufficient information to support calculation of the total propagated uncertainty (TPU) values. This function rewinds the file to the first record and reads through the file looking for the information required to support calculation of vertical and horizontal propagated uncertainty. The total propagated uncertainty arrays are the horizontal\_error and the vertical\_error beam arrays. On success, the file pointer is reset to the beginning of the file before the function returns.

#### Inputs:

Handle	GSF file handle assigned by <b>gsfOpen</b> or <b>gsfOpenBuffered</b>
Status	A pointer to an integer allocated by caller into which the function result is placed. *status is assigned a value of 1 if this file provides sufficient information to support calculation of the total propagated uncertainty array values, otherwise *status is assigned a value of 0.

Returns: This function returns zero if successful or -1 if an error occurred.

Error Conditions:

GSF\_BAD\_FILE\_HANDLE  
GSF\_FILE\_SEEK\_ERROR  
GSF\_FLUSH\_ERROR  
GSF\_READ\_TO\_END\_OF\_FILE  
GSF\_PARTIAL\_RECORD\_AT\_END\_OF\_FILE  
GSF\_READ\_ERROR  
GSF\_RECORD\_SIZE\_ERROR  
GSF\_INSUFFICIENT\_SIZE  
GSF\_CHECKSUM\_FAILURE  
GSF\_UNRECOGNIZED\_RECORD\_ID  
GSF\_HEADER\_RECORD\_DECODE\_FAILED  
GSF\_SVP\_RECORD\_DECODE\_FAILED  
GSF\_PROCESS\_PARAM\_RECORD\_DECODE\_FAILED  
GSF\_SENSOR\_PARAM\_RECORD\_DECODE\_FAILED  
GSF\_COMMENT\_RECORD\_DECODE\_FAILED  
GSF\_HISTORY\_RECORD\_DECODE\_FAILED  
GSF\_NAV\_ERROR\_RECORD\_DECODE\_FAILED  
GSF\_ATTITUDE\_RECORD\_DECODE\_FAILED  
GSF\_HV\_NAV\_ERROR\_RECORD\_DECODE\_FAILED  
GSF\_SUMMARY\_RECORD\_DECODE\_FAILED  
GSF\_UNRECOGNIZED\_SUBRECORD\_ID  
GSF\_INVALID\_RECORD\_NUMBER  
GSF\_RECORD\_TYPE\_NOT\_AVAILABLE  
GSF\_INDEX\_FILE\_READ\_ERROR

### 2.3.14 FUNCTION: GSFFILESUPPORTSRECALCULATENOMINALDEPTH

**Usage:** `int gsfFileSupportsRecalculateNominalDepth(int handle, int *status)`

**Description:** This function reads the GSF file referenced by handle and determines if the file contains sufficient information to support calculation of the nominal depth array. This function rewinds the file to the first record and reads through the file looking for the information required to support calculation of the optional nominal depth array. The nominal depth values represent the depth relative to a sound speed of 1500 meters second. On success, the file pointer is reset to the beginning of the file before the function returns.

#### Inputs:

handle	GSF file handle assigned by <b>gsfOpen</b> or <b>gsfOpenBuffered</b>
status	A pointer to an integer allocated by caller into which the function result is placed. *status is assigned a value of 1 if this file provides sufficient information to support calculation of the nominal depth array, otherwise *status is assigned a value of 0.

**Returns:** This function returns zero if successful or -1 if an error occurred.

#### Error Conditions:

GSF\_BAD\_FILE\_HANDLE  
GSF\_FILE\_SEEK\_ERROR  
GSF\_FLUSH\_ERROR  
GSF\_READ\_TO\_END\_OF\_FILE  
GSF\_PARTIAL\_RECORD\_AT\_END\_OF\_FILE  
GSF\_READ\_ERROR  
GSF\_RECORD\_SIZE\_ERROR  
GSF\_INSUFFICIENT\_SIZE  
GSF\_CHECKSUM\_FAILURE  
GSF\_UNRECOGNIZED\_RECORD\_ID



GSF\_HEADER\_RECORD\_DECODE\_FAILED

GSF\_SVP\_RECORD\_DECODE\_FAILED

GSF\_PROCESS\_PARAM\_RECORD\_DECODE\_FAILED

GSF\_SENSOR\_PARAM\_RECORD\_DECODE\_FAILED

GSF\_COMMENT\_RECORD\_DECODE\_FAILED

GSF\_HISTORY\_RECORD\_DECODE\_FAILED

GSF\_NAV\_ERROR\_RECORD\_DECODE\_FAILED

GSF\_ATTITUDE\_RECORD\_DECODE\_FAILED

GSF\_HV\_NAV\_ERROR\_RECORD\_DECODE\_FAILED

GSF\_SUMMARY\_RECORD\_DECODE\_FAILED

GSF\_UNRECOGNIZED\_SUBRECORD\_ID

GSF\_INVALID\_RECORD\_NUMBER

GSF\_RECORD\_TYPE\_NOT\_AVAILABLE

GSF\_INDEX\_FILE\_READ\_ERROR

### 2.3.15 FUNCTION: GSFFILECONTAINSMBAMPLITUDE

**Usage:** `int gsffileContainsMBAmpitude(int handle, int *status)`

**Description:** This function reads the GSF file referenced by handle and determines if the file contains the average per receive beam amplitude data. This function rewinds the file to the first record and reads through the file up to and including the first ping record. If amplitude data are contained in the first ping record it is assumed that amplitude data are contained with all ping records in this file. On success, the file pointer is reset to the beginning of the file before the function returns.

#### Inputs:

handle	GSF file handle assigned by <b>gsfOpen</b> or <b>gsfOpenBuffered</b>
status	A pointer to an integer allocated by caller into which the function result is placed. *status is assigned a value of 1 if this file contains the optional per-receive-beam average amplitude beam array, otherwise *status is assigned a value of 0.

Returns: This function returns zero if successful or -1 if an error occurred.

Error Conditions:

GSF\_BAD\_FILE\_HANDLE  
GSF\_FILE\_SEEK\_ERROR  
GSF\_FLUSH\_ERROR  
GSF\_READ\_TO\_END\_OF\_FILE  
GSF\_PARTIAL\_RECORD\_AT\_END\_OF\_FILE  
GSF\_READ\_ERROR  
GSF\_RECORD\_SIZE\_ERROR  
GSF\_INSUFFICIENT\_SIZE  
GSF\_CHECKSUM\_FAILURE  
GSF\_UNRECOGNIZED\_RECORD\_ID  
GSF\_HEADER\_RECORD\_DECODE\_FAILED  
GSF\_SVP\_RECORD\_DECODE\_FAILED  
GSF\_PROCESS\_PARAM\_RECORD\_DECODE\_FAILED  
GSF\_SENSOR\_PARAM\_RECORD\_DECODE\_FAILED  
GSF\_COMMENT\_RECORD\_DECODE\_FAILED  
GSF\_HISTORY\_RECORD\_DECODE\_FAILED  
GSF\_NAV\_ERROR\_RECORD\_DECODE\_FAILED  
GSF\_ATTITUDE\_RECORD\_DECODE\_FAILED  
GSF\_HV\_NAV\_ERROR\_RECORD\_DECODE\_FAILED  
GSF\_SUMMARY\_RECORD\_DECODE\_FAILED  
GSF\_UNRECOGNIZED\_SUBRECORD\_ID  
GSF\_INVALID\_RECORD\_NUMBER  
GSF\_RECORD\_TYPE\_NOT\_AVAILABLE  
GSF\_INDEX\_FILE\_READ\_ERROR

### 2.3.16 FUNCTION: GSFFILECONTAINSMBIMAGERY

**Usage:** `int gsffFileContainsMBImagery(int handle, int *status)`

**Description:** This function reads the GSF file referenced by handle and determines if the file contains the per-receive-beam imagery time series data. This function rewinds the file to the first record and reads through the file up to and including the first ping record. If MB imagery data are contained in the first ping record it is assumed that MB imagery data are contained with all ping records in this file. On success, the file pointer is reset to the beginning of the file before the function returns.

#### Inputs:

handle	GSF file handle assigned by <b>gsfOpen</b> or <b>gsfOpenBuffered</b>
status	A pointer to an integer allocated by caller into which the function result is placed. *status is assigned a value of 1 if this file contains the optional per-receive-beam imagery time series data, otherwise *status is assigned a value of 0.

**Returns:** This function returns zero if successful or -1 if an error occurred.

#### Error Conditions:

GSF\_BAD\_FILE\_HANDLE  
GSF\_FILE\_SEEK\_ERROR  
GSF\_FLUSH\_ERROR  
GSF\_READ\_TO\_END\_OF\_FILE  
GSF\_PARTIAL\_RECORD\_AT\_END\_OF\_FILE  
GSF\_READ\_ERROR  
GSF\_RECORD\_SIZE\_ERROR  
GSF\_INSUFFICIENT\_SIZE  
GSF\_CHECKSUM\_FAILURE  
GSF\_UNRECOGNIZED\_RECORD\_ID  
GSF\_HEADER\_RECORD\_DECODE\_FAILED  
GSF\_SVP\_RECORD\_DECODE\_FAILED

GSF\_PROCESS\_PARAM\_RECORD\_DECODE\_FAILED  
 GSF\_SENSOR\_PARAM\_RECORD\_DECODE\_FAILED  
 GSF\_COMMENT\_RECORD\_DECODE\_FAILED  
 GSF\_HISTORY\_RECORD\_DECODE\_FAILED  
 GSF\_NAV\_ERROR\_RECORD\_DECODE\_FAILED  
 GSF\_ATTITUDE\_RECORD\_DECODE\_FAILED  
 GSF\_HV\_NAV\_ERROR\_RECORD\_DECODE\_FAILED  
 GSF\_SUMMARY\_RECORD\_DECODE\_FAILED  
 GSF\_UNRECOGNIZED\_SUBRECORD\_ID  
 GSF\_INVALID\_RECORD\_NUMBER  
 GSF\_RECORD\_TYPE\_NOT\_AVAILABLE  
 GSF\_INDEX\_FILE\_READ\_ERROR

### 2.3.17 FUNCTION: GSFISNEWSURVEYLINE

**Usage:** `int gsfIsNewSurveyLine (int handle, const gsfRecords *rec, double azimuth_change, double *last_heading)`

**Description:** This function provides an approach for calling applications to determine if the last ping read from a GSF file is from the same survey transect line, or if the last ping is from a newly started survey line. The implementation looks for a change in platform heading to determine that the last ping read is from a new survey line. External to this function, calling applications can decide on their own if the first ping read from a newly opened GSF file should be considered to be from a new survey transect line or not. This function assumes that the GSF file is read in chronological order from the beginning of the file, file access can be either direct or sequential

#### Inputs:

<code>handle</code>	GSF file handle assigned by <b>gsfOpen</b> or <b>gsfOpenBuffered</b>
<code>rec</code>	The address of a <i>gsfRecords</i> data structure maintained by the caller which contains a populated <i>gsfSwathBathyPing</i> substructure obtained from recent call to <code>gsfRead</code> .
<code>azimuth_change</code>	A trigger value set by the calling application to be used as the threshold for detecting the end heading change associated with the end of a survey line.

`last_heading`      The address of a double allocated by the calling that is set by `gsflsNewSurveyLine` when a new line is detected. The application program should allocate this double such that it's memory persists for all calls to `gsflsNewSurveyLine`. The function depends on this value persisting from one call to the next.

Returns: This function returns zero when ping is not considered to be from a new survey line and non-zero when the ping is considered to be from a new survey line.

Error Conditions:

None.

### 2.3.18 FUNCTION: GSFINITIALIZEMBPARAMS

Usage: `int gsflInitializeMBParams (gsfMBParams *p)`

Description: This function provides way to initialize all the sonar processing parameters to "unknown".

Inputs:

`p`      pointer to the *gsfMBParams* data structure which will be populated with "unknown"

Returns:

None.

Error Conditions:

None.

### 3. ERROR CODE DESCRIPTIONS

Any GSF function that returns an error code also sets the value of *gsfError* before returning. Table 3-1 lists the reasons for error. **gsfPrintError** or **gsfStringError** can be used to generate a text string of the reason for the error.

Note that the current version of GSFLib does provide text string translations for all error code returns; however, not all definitions have unique values. A future release will address this issue. Table 3-1 presents all the reasons supported by **gsfPrintError**. The following table is a complete listing of all error return codes.

**Table 3-1 GSF Error Codes**

Value of <i>gsfError</i>	Value	Reason for error
<i>GSF_ATTITUDE_RECORD_DECODE_FAILED</i>	-50	"GSF Error decoding attitude record"
<i>GSF_ATTITUDE_RECORD_ENCODE_FAILED</i>	-49	
<i>GSF_BAD_ACCESS_MODE</i>	-3	"GSF Error illegal access mode"
<i>GSF_BAD_FILE_HANDLE</i>	-24	"GSF Error bad file handle"
<i>GSF_BAD_SEEK_OPTION</i>	-15	"GSF Error unrecognized file seek option"
<i>GSF_CANNOT_REPRESENT_PRECISION</i>	-22	"GSF Error illegal scale factor multiplier specified"
<i>GSF_CHECKSUM_FAILURE</i>	-8	"GSF Error data checksum failure"
<i>GSF_COMMENT_RECORD_DECODE_FAILED</i>	-30	"GSF Error decoding comment record"
<i>GSF_COMMENT_RECORD_ENCODE_FAILED</i>	-30	
<i>GSF_CORRUPT_INDEX_FILE_ERROR</i>	-37	"GSF Error index file is corrupted, delete index file"
<i>GSF_FILE_CLOSE_ERROR</i>	-9	"GSF Error closing gsf file"
<i>GSF_FILE_SEEK_ERROR</i>	-16	"GSF Error file seek failed"
<i>GSF_FILE_TELL_ERROR</i>	-35	"GSF Error file tell failed"
<i>GSF_FLUSH_ERROR</i>	-34	"GSF Error flushing data buffers(s)"
<i>GSF_FOPEN_ERROR</i>	-1	"GSF Unable to open requested file"
<i>GSF_HEADER_RECORD_DECODE_FAILED</i>	-25	"GSF Error decoding header record"
<i>GSF_HEADER_RECORD_ENCODE_FAILED</i>	-25	
<i>GSF_HISTORY_RECORD_DECODE_FAILED</i>	-31	"GSF Error decoding history record"

<i>GSF_HISTORY_RECORD_ENCODE_FAILED</i>	-31	
<i>GSF_HV_NAV_ERROR_RECORD_DECODE_FAILED</i>	-48	"GSF Error decoding horizontal/vertical navigation error record"
<i>GSF_HV_NAV_ERROR_RECORD_ENCODE_FAILED</i>	-47	"GSF Error encoding horizontal/vertical navigation error record"
<i>GSF_ILLEGAL_SCALE_FACTOR_MULTIPLIER</i>	-21	"GSF Error illegal scale factor multiplier specified"
<i>GSF_INDEX_FILE_OPEN_ERROR</i>	-36	"GSF Error open of index file failed"
<i>GSF_INDEX_FILE_READ_ERROR</i>	-44	"GSF Error index file read error"
<i>GSF_INSUFFICIENT_SIZE</i>	-6	"GSF Error insufficient size specified"
<i>GSF_INVALID_NUM_BEAMS</i>	-42	"GSF Error invalid number of beams"
<i>GSF_INVALID_RECORD_NUMBER</i>	-43	"GSF Error invalid record number"
<i>GSF_MB_PING_RECORD_DECODE_FAILED</i>	-26	"GSF Error decoding multibeam ping record"
<i>GSF_MB_PING_RECORD_ENCODE_FAILED</i>	-26	
<i>GSF_MEMORY_ALLOCATION_FAILED</i>	-12	"GSF Error memory allocation failure"
<i>GSF_NAV_ERROR_RECORD_DECODE_FAILED</i>	-32	"GSF Error decoding latitude/longitude navigation error record"
<i>GSF_NAV_ERROR_RECORD_ENCODE_FAILED</i>	-32	
<i>GSF_NORMAL</i>	0	
<i>GSF_OPEN_TEMP_FILE_FAILED</i>	-51	"GSF Failed to open temporary file for index creation"
<i>GSF_PARAM_SIZE_FIXED</i>	-45	"GSF Error unable to update existing file with increased record size"
<i>GSF_PARTIAL_RECORD_AT_END_OF_FILE</i>	-52	"GSF Error corrupt/partial record at end of the file"
<i>GSF_PROCESS_PARAM_RECORD_DECODE_FAILED</i>	-28	"GSF Error decoding processing parameters record"
<i>GSF_PROCESS_PARAM_RECORD_ENCODE_FAILED</i>	-28	
<i>GSF_READ_ERROR</i>	-4	"GSF Error reading input data"
<i>GSF_READ_TO_END_OF_FILE</i>	-23	"GSF End of file encountered"
<i>GSF_RECORD_SIZE_ERROR</i>	-7	"GSF Error record size is out of bounds"
<i>GSF_RECORD_TYPE_NOT_AVAILABLE</i>	-39	"GSF Error requested indexed record type not in gsf file"

<i>GSF_SCALE_INDEX_CALLOC_ERROR</i>	-38	"GSF Error calloc of scale factor index memory failed"
<i>GSF_SENSOR_PARAM_RECORD_DECODE_FAILED</i>	-29	"GSF Error decoding sensor parameters record"
<i>GSF_SENSOR_PARAM_RECORD_ENCODE_FAILED</i>	-29	
<i>GSF_SETVBUF_ERROR</i>	-33	"GSF Error setting internal file buffering"
<i>GSF_SINGLE_BEAM_ENCODE_FAILED</i>	-46	"GSF Error single beam encode failure"
<i>GSF_STREAM_DECODE_FAILURE</i> <b>***Note: error code is not used</b>	-14	"GSF Error stream decode failure"
<i>GSF_SUMMARY_RECORD_DECODE_FAILED</i>	-40	"GSF Error decoding summary record"
<i>GSF_SUMMARY_RECORD_ENCODE_FAILED</i>	-41	"GSF Error encoding summary record"
<i>GSF_SVP_RECORD_DECODE_FAILED</i>	-27	"GSF Error decoding SVP record"
<i>GSF_SVP_RECORD_ENCODE_FAILED</i>	-27	
<i>GSF_TOO_MANY_ARRAY_SUBRECORDS</i>	-10	"GSF Error too many array subrecords"
<i>GSF_TOO_MANY_OPEN_FILES</i>	-11	"GSF Error too many open files"
<i>GSF_UNRECOGNIZED_ARRAY_SUBRECORD_ID</i>	-19	"GSF Error unrecognized array subrecord id "
<i>GSF_UNRECOGNIZED_DATA_RECORD</i>	-18	"GSF Error unrecognized data record id"
<i>GSF_UNRECOGNIZED_FILE</i>	-2	"GSF Error unrecognized file"
<i>GSF_UNRECOGNIZED_RECORD_ID</i>	-13	"GSF Error unrecognized record id"
<i>GSF_UNRECOGNIZED_SENSOR_ID</i>	-17	"GSF Error unrecognized sensor specific subrecord id"
<i>GSF_UNRECOGNIZED_SUBRECORD_ID</i>	-20	"GSF Error unrecognized subrecord id"
<i>GSF_WRITE_ERROR</i>	-5	"GSF Error writing output data"
<i>GSF_QUALITY_FLAGS_DECODE__ERROR</i>	-53	"GSF error decoding quality flags record"
<i>Unrecognized error condition</i>		"GSF unknown error"



## 4. C-LANGUAGE DEFINITIONS OF STRUCTURES USED BY GSFLIB

GSFLib is built upon several complex data structures that are passed to applications using the library to access data. This section describes these complex data structures.

### 4.1 Definition of GSF Data Records

Eleven data records define GSF data. Subsequent sections define each of these records. The `gsfRecords` structure allows all records to be addressed as a unit.

```
typedef struct t_gsfRecords
{
    gsfHeader          header;
    gsfSwathBathySummary summary;
    gsfSwathBathyPing  mb_ping;
    gsfSingleBeamPing  sb_ping;
    gsfSVP              svp;
    gsfProcessingParameters process_parameters;
    gsfSensorParameters sensor_parameters;
    gsfComment          comment;
    gsfHistory          history;
    gsfNavigationError  nav_error;
    gsfHVNavigationError hv_nav_error;
    gsfAttitude         attitude;
} gsfRecords;
```

#### 4.1.1 HEADER RECORD

A header record is required to be the first record of every GSF data file.

```
#define GSF_VERSION_SIZE 12
typedef struct t_gsfHeader
{
    char          version[GSF_VERSION_SIZE];
}
gsfHeader;
```

#### 4.1.2 SWATH BATHYMETRY PING RECORD

```
typedef struct t_gsfSwathBathyPing
```

```
{
```

```
    struct timespec    ping_time;           /* seconds and nanoseconds */
    double             latitude;            /* in degrees, north is positive */
    double             longitude;           /* in degrees, west is positive */
    double             height;              /* height above ellipsoid */
    double             sep;                 /* ellipsoid to chart datum */
    short              number_beams;        /* in this ping */
    short              center_beam;         /* offset into array (0 = portmost outer) */
    unsigned short     ping_flags;         /* flags to mark status of this ping */
    short              reserved;            /* for future use */
    double             tide_corrector;       /* in meters */
    double             gps_tide_corrector;  /* in meters */
    double             depth_corrector;     /* in meters */
    double             heading;             /* in degrees */
    double             pitch;               /* in degrees */
    double             roll;                /* in degrees */
    double             heave;              /* in meters */
    double             course;              /* in degrees */
    double             speed;               /* in knots */
    gsfScaleFactors    scaleFactors;        /* The array scale factors for this data */
    double             *depth;              /* depth array (meters) */
    double             *nominal_depth;     /* Array of depth relative to 1500 m/s */
    double             *across_track;       /* across track array (meters) */
    double             *along_track;        /* along track array (meters) */
    double             *travel_time;        /* roundtrip travel time array (seconds) */
    double             *beam_angle;         /* beam angle array degrees from vertical */
    double             *mc_amplitude;       /* mean, calibrated beam amplitude array (dB
                                           re 1V/micro pascal at 1 meter) */
    double             *mr_amplitude;       /* mean, relative beam amplitude array (dB
                                           re 1V/micro pascal at 1 meter) */
    double             *echo_width;         /* echo width array (seconds) */
    double             *quality_factor;     /* quality factor array (dimensionless) */
    double             *receive_heave;      /* Array of heave data (meters) */
```

```

double          *depth_error;          /* Array of estimated vertical error
                                         (meters) */
double          *across_track_error;   /* Array of estimated across track error
                                         (meters) */
double          *along_track_error;    /* Array of estimated along track error
                                         (meters) */
unsigned char    *quality_flags;        /* Two bit beam detection flags provided by
                                         Reson sonar */
unsigned char    *beam_flags;          /* Array of beam status flags */
double          *signal_to_noise;      /* signal to noise ratio (dB) */
double          *beam_angle_forward;   /* beam angle forward array (degrees
                                         counterclockwise from stbd.) */
double          *vertical_error;       /* Array of estimated vertical error
                                         (meters, at 95% confidence) */
double          *horizontal_error;     /* Array of estimated horizontal error
                                         (meters, at 95% confidence) */
unsigned short   *sector_number;        /* Array of values that specify the transit
                                         sector for this beam */
unsigned short   *detection_info;      /* Array of values that specify the method
                                         of bottom detection */
double          *incident_beam_adj;    /* Array of values that specify incident
                                         beam angle adjustment from beam_angle */
unsigned short   *system_cleaning;     /* Array of values that specify data
                                         cleaning information from the sensor
                                         system */
double          *doppler_corr;         /* Array of values used to correct the
                                         travel times for Doppler when
                                         transmission is FM */
double          *sonar_vert_uncert;    /* vertical uncertainty from sonar */
double          *sonar_horz_uncert;    /* horizontal uncertainty provided by the
                                         sonar (Added in KMALL) */
double          *detection_window;    /* Length of the detection window in seconds
                                         provided by the sonar (Added in KMALL) */
double          *mean_abs_coeff;       /* Mean absolute coefficient provided by the
                                         sonar (Added in KMALL) */
double          *TVG_dB;               /* decibels, real time TVG applies nadir
                                         suppression and a lambertian correction */
int             sensor_id;             /* a definition which specifies the sensor*/
gsfSensorSpecific sensor_data;         /* union of known sensor specific data */
gsfBRBIntensity *brb_inten;           /* Structure containing bathymetric receive
                                         beam time series intensities */

} gsfSwathBathyPing;

```

#### 4.1.2.1 Scale Factor Subrecord

```
typedef struct t_gsfScaleInfo
{
    unsigned char    compressionFlag; /* Specifies bytes of storage in high order nibble
                                      and type of compression in low order nibble */

    double           multiplier;      /* the scale factor (millionths)for the array */
    double           offset;          /* dc offset to scale data by */
} gsfScaleInfo;

typedef struct t_gsfScaleFactors
{
    int              numArraySubrecords; /* number of scaling factors we actually have */
    gsfScaleInfo     scaleTable[GSF_MAX_PING_ARRAY_SUBRECORDS];
} gsfScaleFactors;
```

#### 4.1.2.2 Multibeam Sensor-specific Subrecords

```
/* Define the typeIII specific data structure */
typedef struct t_gsfTypeIIISpecific
{
    unsigned short   leftmost_beam; /* 0 - leftmost possible beam */
    unsigned short   rightmost_beam;
    unsigned short   total_beams;
    unsigned short   nav_mode;
    unsigned short   ping_number;
    unsigned short   mission_number;
}

t_gsfTypeIIISpecific;

/* The gsfCmpSassSpecific data structure is intended to replace the gsfTypeIII Specific
 * data structure in a future release. All new coding should use the gsfCmpSassSpecific
 * data structure.
 */

/* Define the CMP (Compressed) SASS specific data structure (from sass.h) */
typedef struct t_gsfCmpSassSpecific
```

```

{
/*****
*
*   Mapping from Compressed SASS (BOSDAT) to GSF record
*
*   from          to          comment
*   =====
*
*   lntens        ping.heave    mapped only when year is post 1991 or
*                               user has elected to force mapping.
*   lfreq         not-mapped
*   ldraft        comment      APPLIED_DRAFT comment record
*   svp.svel      svp.sound_velocity  at <= 1000 ... FATHOMS
*                               at <= 2500 ... METERS
*                               otherwise ... FEET
*   svp.deptl     svp.depth     (see sound_velocity)
*   lmishn        comment      MISSION_NUMBER comment record
*   luyr          ping_time     GSF time record from 1960 to 1970 base
*   pitchl        ping.pitch
*   rol1l        ping.roll
*   lbear         ping.heading  SASS specific (not Seabeam)
*   pinhd         ping.heading  Seabeam specific (not SASS)
*   depth         ping.nominal_depth  FATHOMS_TO_METERS_NOMINAL
*   pslatl        ping.across_track  YARDS_TO_METERS_EXACT
*   bltime        ping.travel_time
*   ampl          ping.mr_amplitude
*   <ftaf file>   ping.beam_flags  HMPS_FLAGS
*   alpos         ping.along_track  SASS specific YARDS_TO_METERS_EXACT
*
*****/

    double lfreq; /* sea-surface sound velocity in feet/sec from bosdat(lfreq) */
    double lntens; /* since 1992 this value has represented the heave associated with
                    the ping; prior to 1992, field description unknown */

```

```

}

t_gsfCmpSassSpecific;

/* Define the 16 Beam SeaBeam specific data structure */
typedef struct t_gsfSeabeamSpecific
{
    unsigned short  EclipseTime; /* In 10ths of seconds */
}

t_gsfSeaBeamSpecific;

typedef struct t_gsfSBAMPspecific
{
    unsigned char    hour;
    unsigned char    minute;
    unsigned char    second;
    unsigned char    hundredths;
    unsigned int     block_number;
    short            avg_gate_depth;
}

t_gsfSBAMPspecific;

/* Define the Seamap specific data structure */
typedef struct t_gsfSeamapSpecific
{
    double           portTransmitter[2];
    double           stbdTransmitter[2];
    double           portGain;
    double           stbdGain;
    double           portPulseLength;
    double           stbdPulseLength;
    double           pressureDepth;
    double           altitude;
    double           temperature;
}

```

```

t_gsfSeamapSpecific;

/* Define the EM950/EM1000 specific data structure */
typedef struct t_gsfEM950Specific
{
    int          ping_number;
    int          mode;
    int          ping_quality;
    double       ship_pitch;
    double       transducer_pitch;
    double       surface_velocity;
}
t_gsfEM950Specific;

/* Define the EM100 specific data structure */
typedef struct t_gsfEM100Specific
{
    double       ship_pitch;
    double       transducer_pitch;
    int          mode;
    int          power;
    int          attenuation;
    int          tvlg;
    int          pulse_length;
    int          counter;
}
t_gsfEM100Specific;

/* Define the EM121A specific data structure */
typedef struct t_gsfEM121ASpecific
{
    int          ping_number;
    int          mode;
    int          valid_beams;

```

```

    int        pulse_length;
    int        beam_width;
    int        tx_power;
    int        tx_status;
    int        rx_status;
    double     surface_velocity;
}

t_gsfEM121ASpecific;

/* Define a data structure to hold the Simrad EM3000 series run time parameters. */
typedef struct t_gsfEM3RunTime
{
    int        model_number;           /* from the run-time parameter datagram */
    struct timespec dg_time;          /* from the run-time parameter datagram */
    int        ping_number;           /* sequential counter 0 - 65535 */
    int        serial_number;         /* The sonar head serial number */
    int        system_status;         /* normally = 0 */
    int        mode;                  /* 0=nearfield, 1=normal, 2=target,
                                     3=deep, 4=very deep */
    int        filter_id;
    double     min_depth;             /* meters */
    double     max_depth;             /* meters */
    double     absorption;            /* dB/km */
    double     pulse_length;          /* micro seconds */
    double     transmit_beam_width;   /* degrees */
    int        power_reduction;       /* dB */
    double     receive_beam_width;    /* degrees */
    int        receive_bandwidth;     /* Hz */
    int        receive_gain;          /* dB */
    int        cross_over_angle;      /* degrees */
    int        ssv_source;            /* 0=sensor, 1>manual, 2=profile */
    int        swath_width;           /* total swath width in meters */
    int        beam_spacing;          /* 0=beamwidth, 1=equiangle,
                                     2=equidistant, 3=intermediate */

```



```

    int            coverage_sector;        /* total coverage in degrees */
    int            stabilization;
    int            port_swath_width;        /* maximum port swath width in meters */
    int            stbd_swath_width;        /* maximum starboard swath width in
                                           meters */

    int            port_coverage_sector;    /* maximum port coverage in degrees */
    int            stbd_coverage_sector;    /* maximum starboard coverage in degrees */
    int            hilo_freq_absorp_ratio;
    int            spare1;                  /* four spare bytes */
}

t_gsfEM3RunTime;

/* Define the Simrad EM3000 series specific data structure */
typedef struct t_gsfEM3Specific
{
    /* The first nine values are updated with each depth datagram */
    int            model_number;            /* ie: 3000, ... */
    int            ping_number;            /* 0 - 65535 */
    int            serial_number;          /* 100 - 65535 */
    double         surface_velocity;        /* in m/s */
    double         transducer_depth;        /* transmit transducer depth in meters */
    int            valid_beams;            /* number of valid beams for this ping */
    int            sample_rate;            /* in Hz */
    double         depth_difference;        /* in meters between sonar heads in em3000d
                                           configuration */

    int            offset_multiplier;        /* transducer depth offset multiplier */
/* The gsfEM3RunTime data structure is updated with each run-time parameter datagram*/
    gsfEM3RunTime run_time[2]; /* A two element array is needed to support em3000d */
}

t_gsfEM3Specific;

/* Define the Reson SeaBat specific data structure */
typedef struct t_gsfSeaBatSpecific

```

```

{
    int            ping_number;
    double         surface_velocity;
    int            mode;
    int            sonar_range;
    int            transmit_power;
    int            receive_gain;
}

t_gsfSeaBatSpecific;

/* The gsfSeaBatIISpecific data structure is intended to replace the
 * gsfSeaBatSpecific data structure as of GSF_1.04.
 */

typedef struct t_gsfSeaBatIISpecific
{
    int            ping_number;          /* 1 - 32767 */
    double         surface_velocity;     /* meters/second */
    int            mode;                  /* bit mapped, see macros below */
    int            sonar_range;          /* meters */
    int            transmit_power;
    int            receive_gain;
    double         fore_aft_bw;          /* fore/aft beam width in degrees */
    double         athwart_bw;           /* athwartships beam width in degrees */
    char           spare[4];             /* Four bytes of spare space, for future use */
}

t_gsfSeaBatIISpecific;

/* Macro definitions for the SeaBatSpecific and SeaBatIISpecific mode field */
#define GSF_SEABAT_WIDE_MODE      0x01  /* if set 10 deg fore-aft */
#define GSF_SEABAT_9002           0x02  /* if set two sonar heads */
#define GSF_SEABAT_STBD_HEAD      0x04  /* if set starboard ping (seabat head 2) */
#define GSF_SEABAT_9003           0x08  /* if set 9003 series sonar (40 beams) */

/* Define the Reson SeaBat specific data structure */

```

```

typedef struct t_gsfSeaBat8101Specific
{
    int      ping_number;          /* 1 - 65535 */
    double   surface_velocity;     /* meters/second */
    int      mode;                  /* bit mapped, see macros below */
    int      range;                 /* meters */
    int      power;                 /* 0-8 + status bits */
    int      gain;                  /* 1-45 + status bits */
    int      pulse_width;          /* in microseconds */
    int      tv_g_spreading;       /* tv_g spreading coefficient * 4 */
    int      tv_g_absorption;      /* tv_g absorption coefficient */
    double   fore_aft_bw;          /* fore/aft beam width in degrees */
    double   athwart_bw;          /* athwartships beam width in degrees */
    double   range_filt_min; /* range filter, minimum value, meters (future use) */
    double   range_filt_max; /* range filter, maximum value, meters (future use) */
    double   depth_filt_min; /* depth filter, minimum value, meters (future use) */
    double   depth_filt_max; /* depth filter, maximum value, meters (future use) */
    int      projector;           /* projector type (future use) */
    char     spare[4];            /* Four bytes of spare space, for future use */
}

t_gsfSeaBat8101Specific;

/* Macro definitions for the SeaBat8101Specific and SeaBat8101Specific mode field */
#define GSF_8101_WIDE_MODE      0x01    /* set if transmit on receiver */
#define GSF_8101_TWO_HEADS     0x02    /* set if two sonar heads */
#define GSF_8101_STBD_HEAD     0x04    /* set if starboard ping (seabat head 2) */
#define GSF_8101_AMPLITUDE     0x08    /* set if beam amplitude is available (RITHETA
                                         packet) */

/* Define the SeaBeam 2112/36 specific data structure */
typedef struct t_gsfSeaBeam2112Specific
{
    int      mode;                  /* bit mapped, see macros below */
    double   surface_velocity;     /* meters/second */

```

```

    char    ssv_source;                /* (V)elocimeter, (M)anual, (T)emperature,
                                        (E)xternal, or (U)nknown */

    int     ping_gain;                 /* dB */
    int     pulse_width;               /* in milliseconds */
    int     transmitter_attenuation;    /* dB */
    int     number_algorithms;         /* algorithms per beam (1-4) */
    char     algorithm_order[5];        /* null terminated string, each char will be
                                        either a space, W(MT), or B(DI).  If
                                        number_algorithms equals one, this will be
                                        four spaces */

    char     spare[2];                 /* Two bytes of spare space, for future use */
}

t_gsfSeaBeam2112Specific;

/* Macro definitions for the SeaBeam2112Specific mode field */
#define GSF_2112_SVP_CORRECTION 0x01 /* set if true depth, true position corrections
                                        are used */
#define GSF_2112_LOW_FREQUENCY 0x02 /* set if using 12kHz frequency - 36kHz if not
                                        set */
#define GSF_2112_AUTO_DEPTH_GATE 0x04 /* set if depth gate mode is automatic - manual
                                        if not set */

/* SeaBeam 2112 specific macro definitions for the quality factor array */
#define GSF_2112_POOR_QUALITY 0x01 /* set if the beam was flagged by the SeaBeam
                                        as poor quality */
#define GSF_2112_DATA_SOURCE_WMT 0x10 /* set if the data source is WMT - source is
                                        BDI if not set */

/* Define the Elac MkII specific data structure */
typedef struct t_gsfElacMkIISpecific
{
    int     mode;                      /* bit mapped, see macros below */
    int     ping_num;
    int     sound_vel;                 /* 0.1 m/s */
    int     pulse_length;              /* 0.01 ms */
    int     receiver_gain_stbd;        /* db */

```

```

        int                receiver_gain_port;        /* db */
        int                reserved;
    }

    t_gsfElacMkIISpecific;

/* Macro definitions for the ElacMkIISpecific mode field */
#define GSF_MKII_LOW_FREQUENCY    0x01    /* set if using 12kHz frequency - 36kHz if not
                                           set */
#define GSF_MKII_SOURCE_MODE      0x02    /* set if RDT transmit used, otherwise omni */
#define GSF_MKII_SOURCE_POWER     0x04    /* set if transmit high power - low power if
                                           not set */
#define GSF_MKII_STBD_HEAD        0x08    /* set if starboard ping */

/* Define the Reson SeaBat specific data structure */
typedef struct t_gsfReson7100Specific
{
    unsigned int            protocol_version;        /* Obtained from the Data Record Frame
                                                       (DRF) */
    unsigned int            device_id;               /* i.e. 7101, 7111, 7125, etc. Obtained
                                                       from the DRF */
    unsigned char           reserved_1[16];          /* Placeholder for growth of fields from
                                                       DRF */
    unsigned int            major_serial_number;     /* high order 4 bytes of sonar serial
                                                       number, from record 7000 */
    unsigned int            minor_serial_number;     /* low order 4 bytes of sonar serial
                                                       number, from record 7000 */
    unsigned int            ping_number;             /* sequential number, unique for each
                                                       ping, wraps at boundary */
    unsigned int            multi_ping_seq;          /* 0 if not in multi-ping mode, otherwise
                                                       number of pings in a multi-ping
                                                       sequence */
    double                  frequency;               /* Sonar operating frequency in Hz. From
                                                       record 7000 */
    double                  sample_rate;             /* Sonar system sampling rate in Hz. From

```

```

record 7000 */

double      receiver_bandwidth;  /* Sonar system signal bandwidth in Hz.
                                   From record 7000 */

double      tx_pulse_width;      /* Transmit pulse length in seconds. From
                                   record 7000 */

unsigned int tx_pulse_type_id;    /* 0=CW, 1=Linear chirp, from
                                   record 7000 */

unsigned int tx_pulse_envlp_id;   /* 0=Tapered rectangular, 1=Tukey, from
                                   record 7000 */

double      tx_pulse_envlp_param; /* four byte field containing envelope
                                   parameter, no definition or units
                                   available, from record 7000 */

unsigned int tx_pulse_reserved;   /* four byte field reserved for future
                                   growth, from record 7000 */

double      max_ping_rate;        /* Maximum ping rate in pings per second,
                                   from record 7000 */

double      ping_period;          /* seconds since last ping, from
                                   record 7000 */

double      range;                /* Sonar range selection in meters, from
                                   record 7000 */

double      power;                /* Power selection in dB re 1 microPa,
                                   from record 7000 */

double      gain;                 /* Gain selection in dB, from
                                   record 7000 */

unsigned int control_flags;        /* 0-3: Auto range method
                                   4-7: Auto bottom detect filter
                                   method
                                   8: Bottom detect range filter
                                   9: Bottom detect depth filter
                                   10-14: Auto receiver gain method
                                   15-31: Reserved */

unsigned int projector_id;         /* projector selection, from
                                   record 7000 */

double      projector_steer_angl_vert; /* degrees, from record 7000 */

```

```

double      projector_steer_angl_horz;  /* degrees, from record 7000 */
double      projector_beam_wdth_vert;   /* degrees, from record 7000 */
double      projector_beam_wdth_horz;   /* degrees, from record 7000 */
double      projector_beam_focal_pt;    /* meters, from record 7000 */
unsigned int projector_beam_weighting_window_type; /* 0-Rectangular,
                                                    1-Chebyshev,
                                                    from record 7000 */
unsigned int projector_beam_weighting_window_param; /* four byte projector
                                                    weighting parameter, no
                                                    definition or units
                                                    available, from record
                                                    7000 */

unsigned int transmit_flags;             /* 0-3: Pitch stabilization method
                                           4-6: Yaw stabilization method
                                           8-31: Reserved */
unsigned int hydrophone_id;              /* hydrophone selection,
                                           from record 7000 */
unsigned int receiving_beam_weighting_window_type; /* 0-Chebyshev, 1-Kaiser,
                                                    from record 7000 */
unsigned int receiving_beam_weighting_window_param; /* four byte receiver
                                                    weighting parameter, no
                                                    definition or units
                                                    available, from record
                                                    7000 */

unsigned int receive_flags;              /* 0-3: Roll stabilization method
                                           4-7: Dynamic focusing method
                                           8-11: Doppler compensation method
                                           12-15: Match filtering method
                                           16-19: TVG method
                                           20-23: Multi-Ping Mode
                                           24-31: Reserved */
double      receive_beam_width;          /* angle in degrees, from record 7000 */
double      range_filt_min;              /* range filter, minimum value, meters,
                                           from record 7000 */

```

```

double        range_filt_max;        /* range filter, maximum value, meters,
                                       from record 7000 */
double        depth_filt_min;        /* depth filter, minimum value, meters,
                                       from record 7000 */
double        depth_filt_max;        /* depth filter, maximum value, meters,
                                       from record 7000 */
double        absorption;             /* absorption in dB/km, from
                                       record 7000 */
double        sound_velocity;         /* sound speed in m/s at transducer, from
                                       record 7006 */
double        spreading;              /* spreading loss in dB from
                                       record 7000 */
char          reserved_2[16];         /* spare space, for future use */
unsigned char sv_source;              /* (0: measured, 1: manual), from
                                       record 7006 */
unsigned char layer_comp_flag;        /* (0: off, 1: on), from record 7006 */
char          reserved_3[8];         /* spare space, for future use */
}
t_gsfReson7100Specific;

#define GSF_7100_PITCH_STAB          0x0001 /* set if pitch stabilized */
#define GSF_7100_ROLL_STAB           0x0001 /* set if roll stabilized */

/* Define the Reson T50/20 Series specific data structure */
typedef struct t_gsfResonTSeriesSpecific
{
    unsigned int    protocol_version;    /* Obtained from the Data Record Frame
                                           (DRF) */
    unsigned int    device_id;           /* i.e. 7101, 7111, 7125, etc.
                                           Obtained from the DRF */
    unsigned int    number_devices;      /* Number of devices from the 7001
                                           record */
    unsigned short  system_enumerator;   /* From Data Record Frame. In Dual
                                           head configuration, specifies sensor
                                           0 - Both Sonars
                                           1 - Port Sonar
                                           2 - Starboard Sonar */

```



unsigned char	reserved_1[10];	/* Placeholder for growth of fields from DRF */
unsigned int	major_serial_number;	/* high order 4 bytes of sonar serial number, from record 7000 */
unsigned int	minor_serial_number;	/* low order 4 bytes of sonar serial number, from record 7000 */
unsigned int	ping_number;	/* sequential number, unique for each ping, wraps at boundary */
unsigned int	multi_ping_seq;	/* 0 if not in multi-ping mode, otherwise number of pings in a multi-ping sequence */
double	frequency;	/* Sonar operating frequency in Hz. From record 7000 */
double	sample_rate;	/* Sonar system sampling rate in Hz. From record 7027 */
double	receiver_bandwidth;	/* Sonar system signal bandwidth in Hz. From record 7000 */
double	tx_pulse_width;	/* Transmit pulse length in seconds. From record 7000 */
unsigned int	tx_pulse_type_id;	/* 0=CW, 1=Linear chirp, from record 7000 */
unsigned int	tx_pulse_envlp_id;	/* 0=Tapered rectangular, 1=Tukey, from record 7000 */
double	tx_pulse_envlp_param;	/* Field containing envelope parameter, no definition or units available, from record 7000 */
unsigned short	tx_pulse_mode;	/* 1 - single ping, 2 - multi-ping 2, 3 - multi-ping 3, 4 - multi-ping 4 */
unsigned short	tx_pulse_reserved;	/* two byte field reserved for future growth, from record 7000 */
double	max_ping_rate;	/* Maximum ping rate in pings per second, from record 7000 */
double	ping_period;	/* seconds since last ping, from record 7000 */
double	range;	/* Sonar range selection in meters, from record 7000 */
double	power;	/* Power selection in dB re 1 microPa, from record 7000 */
double	gain;	/* Gain selection in dB, from record 7000 */

```

unsigned int      control_flags;      /* 0-3: Auto range method
                                       4-7: Auto bottom detect filter
                                       method
                                       8: Bottom detect range filter
                                       9: Bottom detect depth filter
                                       10: Receiver gain method Auto Gain
                                       11: Receiver gain method Fixed Gain
                                       12: Receiver gain method Reserved
                                       13: Reserved
                                       14: Trigger out High for entire RX
                                       duration (0: Disabled,
                                       1: Enabled)
                                       15: 0: System inactive, 1: Active
                                       16-19: Reserved for bottom detection
                                       20: Pipe gating filter
                                       (0: Disabled, 1: Enabled)
                                       21: Adaptive gate depth filter fixed
                                       (0: Follow seafloor,
                                       1: Fix depth)
                                       22: Adaptive gate
                                       (0: Disabled, 1: Enabled)
                                       23: Adaptive gate depth filter
                                       (0: Disabled, 1: Enabled)
                                       24: Trigger out
                                       (0: Disabled, 1: Enabled)
                                       25: Trigger in edge
                                       (0: Positive, 1: Negative)
                                       26: PPS Edge
                                       (0: Positive, 1: Negative)
                                       27-28: Timestamp state (
                                       0: Not applicable,
                                       1: Error / not valid,
                                       2: warning,
                                       3: ok)
                                       29: Depth filter follows seafloor
                                       (0 : Fix depth,
                                       1: Follow seafloor)
                                       30: Reduced coverage for constant
                                       spacing
                                       (0: Always maintain swath
                                       coverage,
                                       1: Allow swath coverage to be
                                       reduced)
                                       31: 0: 7K. 1: Simulator*/

unsigned int      projector_id;      /* projector selection, from record
                                       7000 */

double           projector_steer_angl_vert; /* degrees, from record 7000 */
double           projector_steer_angl_horz; /* degrees, from record 7000 */
double           projector_beam_wdth_vert; /* degrees, from record 7000 */
double           projector_beam_wdth_horz; /* degrees, from record 7000 */
double           projector_beam_focal_pt; /* meters, from record 7000 */

```

unsigned int	projector_beam_weighting_window_type;	/* 0-Rectangular, 1-Chebyshev, from record 7000 */
double	projector_beam_weighting_window_param;	/* four byte projector weighting parameter, no definition or units available, from record 7000 */
unsigned int	transmit_flags;	/* 0-3: Pitch stabilization method 4-6: Yaw stabilization method 8-31: Reserved */
unsigned int	hydrophone_id;	/* hydrophone selection, from record 7000 */
unsigned int	receiving_beam_weighting_window_type;	/* 0-Chebyshev, 1-Kaiser, from record 7000 */
double	receiving_beam_weighting_window_param;	/* four byte receiver weighting parameter, no definition or units available, from record 7000 */
unsigned int	receive_flags;	/* 0: Roll stabilization indicator 1: Reserved 2: Heave compensation indicator 3: Reserved 4-7: Dynamic focusing method 8-11: Doppler compensation method 12-15: Match filtering method 16-19: TVG method 20-23: Multi-Ping Mode 24-31: Reserved */
double	receive_beam_width;	/* angle in degrees, from record 7000 */
double	range_filt_min;	/* range filter, minimum value, meters, from record 7000 */
double	range_filt_max;	/* range filter, maximum value, meters, from record 7000 */
double	depth_filt_min;	/* depth filter, minimum value, meters, from record 7000 */
double	depth_filt_max;	/* depth filter, maximum value, meters, from record 7000 */
double	absorption;	/* absorption in dB/km, from record 7000 */
double	sound_velocity;	/* sound speed in m/s at transducer, from record 7000 (in T Series) */

```

unsigned char    sv_source;          /* (0: measured, 1: manual), from
                                     record 7504 */

double          spreading;          /* spreading loss in dB from record
                                     7000 */

unsigned short   beam_spacing_mode;  /* Beam spacing mode from 7503 record
                                     (1: Equiangle,
                                     2: Equidistant,
                                     3: Flex,
                                     4: Intermediate)*/

unsigned short   sonar_source_mode;  /* 7k sonar source mode from record
                                     7503
                                     (0: Normal,
                                     1: Autopilot,
                                     2: Calibration (IQ)) */

unsigned char    coverage_mode;      /* Coverage mode from 7503 record
                                     (0: Reduce Spacing,
                                     1: Reduce Beams) */

double          coverage_angle;      /* Coverage angle from 7503 record in
                                     degrees */

double          horizontal_receiver_steering_angle; /* Steering angle in
                                                     degrees (positive to
                                                     starboard) from 7503
                                                     record */

unsigned char    reserved_2[3];      /* spare space, for future use */

unsigned int     uncertainty_type;    /* (0: not calculated, 1: Rob Hare's
                                     method, 2: Ifremer's method) from
                                     7027 record */

double          transmitter_steering_angle; /* applied transmitter steering
                                             angle, in radians from 7027 in
                                             GSF sign convention (+pitch =
                                             bow up)*/

double          applied_roll;        /* roll value (in radians) applied to
                                     gates, zero if roll stabilization is
                                     ON from 7027 record */

unsigned short   detection_algorithm; /* Detection algorithm from 7027 record
                                     */

unsigned int     detection_flags;     /* Detection flags from 7027 record */

char            device_description[60]; /* Device description (serial number)
                                     from 7001 record */

unsigned char    reserved_7027[60];   /* Space space from 7027 record, for
                                     future use */

unsigned int     match_filter_control; /* Flag that describes the match filter
operation (0: Off, 1: On) [7002 record] */

double          match_filter_start_freq; /* Frequency the filter starts at in Hz
[7002 record] */

```

```

    double                match_filter_end_freq; /* Frequency the filter ends at in Hz [7002
record] */

    unsigned int          match_filter_window_type; /* Match window type (0: Rect, 1:
Kaiser, 2: Hamming, 3: Blackmann, 4:Triangular, 5:X-Taylor) [7002 record] */

    double                match_filter_shading_value; /* Match filter shading value [7002
record] */

    double                match_filter_effect_pulse_width; /* Match Filter Effective Pulse
Width after FM compression in seconds [7002 record] */

    unsigned int          reserved_7002[13]; /* Match filter spare space [Filled with 0xFB
in 7002 record] */

    unsigned char         reserved_3[32];          /* spare space, for future use */
    unsigned char         reserved_4[288];         /* spare space, for future use */
}

t_gsfResonTSeriesSpecific;

/* Define the Reson 8100 specific data structure */
typedef struct t_gsfReson8100Specific
{
    int                   latency;                /* time from ping to output (milliseconds) */
    int                   ping_number;            /* 4 byte ping number */
    int                   sonar_id;               /* least significant 4 bytes of Ethernet
address */
    int                   sonar_model;           /* */
    int                   frequency;             /* KHz */
    double                surface_velocity;       /* meters/second */
    int                   sample_rate;           /* A/D samples per second */
    int                   ping_rate;            /* pings per second * 1000 */
    int                   mode;                 /* bit mapped, see macros below */
    int                   range;                /* meters */
    int                   power;               /* 0-8 + status bits */
    int                   gain;                /* 1-45 + status bits */
    int                   pulse_width;          /* in microseconds */
    int                   tv_g_spreading;       /* tv_g spreading coefficient * 4 */
    int                   tv_g_absorption;      /* tv_g absorption coefficient */
    double                fore_aft_bw;          /* fore/aft beam width in degrees */
    double                athwart_bw;          /* athwartships beam width in degrees */

```

```

    int            projector_type;        /* projector type */
    int            projector_angle;       /* projector pitch steering angle (degrees *
                                           100) */

    double         range_filt_min;       /* range filter, minimum value, meters */
    double         range_filt_max;       /* range filter, maximum value, meters */
    double         depth_filt_min;       /* depth filter, minimum value, meters */
    double         depth_filt_max;       /* depth filter, maximum value, meters */
    int            filters_active;        /* bit 0 - range filter, bit 1 - depth filter */
    int            temperature;           /* temperature at sonar head (deg C * 10) */
    double         beam_spacing;          /* across track receive beam angular spacing
                                           */
    char           spare[2];              /* Two bytes of spare space, for future use */
}

t_gsfReson8100Specific;

/* Macro definitions for the SeaBat8100Specific mode field */
#define GSF_8100_WIDE_MODE            0x01 /* set if transmit on receiver */
#define GSF_8100_TWO_HEADS            0x02 /* set if two sonar heads */
#define GSF_8100_STBD_HEAD            0x04 /* set if starboard ping (seabat head 2) */
#define GSF_8100_AMPLITUDE            0x08 /* set if beam amplitude is available (RITHETA
packet) */
#define GSF_8100_PITCH_STAB           0x10 /* set if pitch stabilized */
#define GSF_8100_ROLL_STAB            0x20 /* set if roll stabilized */

/* Define the Echotrac Single-Beam sensor specific data structure. */

#define GSF_SB_MPP_SOURCE_UNKNOWN      0x00 /* Unknown MPP source */
#define GSF_SB_MPP_SOURCE_GPS_3S       0x01 /* GPS 3S */
#define GSF_SB_MPP_SOURCE_GPS_TASMAN   0x02 /* GPS Tasman */
#define GSF_SB_MPP_SOURCE_DGPS_TRIMBLE 0x03 /* DGPS Trimble */
#define GSF_SB_MPP_SOURCE_DGPS_TASMAN  0x04 /* DGPS Tasman */
#define GSF_SB_MPP_SOURCE_DGPS_MAG     0x05 /* DGPS MagMPPox */
#define GSF_SB_MPP_SOURCE_RANGE_MFIX    0x06 /* Range/Azimuth - Microfix */
#define GSF_SB_MPP_SOURCE_RANGE_TRIS    0x07 /* Range/Azimuth - Trisponder */
#define GSF_SB_MPP_SOURCE_RANGE_OTHER  0x08 /* Range/Azimuth - Other */

```

```

typedef struct t_gsfSBEchotracSpecific
{
    int            navigation_error;
    unsigned short mpp_source;      /* Flag To determine mpp source - See above */
    unsigned short tide_source;     /* in GSF Version 2.02+ this is in ping flags */
    double         dynamic_draft;   /* speed induced draft in meters */
    char           spare[4];        /* four bytes of reserved space */
}
t_gsfSBEchotracSpecific;

/* Define the MGD77 Single-Beam sensor specific data structure. */
typedef struct t_gsfSBMGD77Specific
{
    unsigned short time_zone_corr;
    unsigned short position_type_code;
    unsigned short correction_code;
    unsigned short bathy_type_code;
    unsigned short quality_code;
    double         travel_time;
    char           spare[4];        /* four bytes of reserved space */
}
t_gsfSBMGD77Specific;

/* Define the BDB sensor specific data structure */
typedef struct t_gsfSBBDBSpecific
{
    int    doc_no;          /* Document number (5 digits) */
    char   eval;            /* Evaluation (1-best, 4-worst) */
    char   classification; /* Classification ((U)nclass, (C)onfidential,
                                (S)ecret, (P)roprietary/Unclass,
                                (Q)Proprietary/Class) */
    char   track_adj_flag; /* Track Adjustment Flag (Y,N) */
    char   source_flag;    /* Source Flag ((S)urvey, (R)andom, (O)cean Survey) */
}

```

```

    char  pt_or_track_ln; /* Discrete Point (D) or Track Line (T) Flag */
    char  datum_flag;     /* Datum Flag ((W)GS84, (D)atumless) */
    char  spare[4];       /* four bytes of reserved space */
}

t_gsfSBBDBSpecific;

/* Define the NOS HDB sensor specific data structure */
typedef struct t_gsfSBNOSHDBSpecific
{
    unsigned short  type_code;    /* Depth type code */
    unsigned short  carto_code;   /* Cartographic code */
    char            spare[4];     /* four bytes of reserved space */
}

t_gsfSBNOSHDBSpecific;

/* Define the Navisound sensor specific data structure */
typedef struct t_gsfSBNavisoundSpecific
{
    double          pulse_length; /* pulse length in cm */
    char            spare[8];     /* eight bytes of reserved space */
}

t_gsfSBNavisoundSpecific;

/* Define the GeoSwath sensor specific data structure */
typedef struct t_gsfGeoSwathPlusSpecific
{
    int             data_source;   /* 0 = CBF, 1 = RDF */
    int             side;          /* 0 = port, 1 = stbd */
    int             model_number;  /* ie: 100, 250, 500, ... */
    double          frequency;     /* Hz */
    int             echosounder_type; /* ? */
    long            ping_number;   /* 0 - 4,294,967,295 */
    int             num_nav_samples; /* number of navigation samples in this ping */
}

```



```

    int            num_attitude_samples;    /* number of attitude samples in this ping
                                           */

    int            num_heading_samples;     /* number of heading samples in this ping
                                           */

    int            num_miniSVS_samples;     /* number of miniSVS samples in this ping
                                           */

    int            num_echosounder_samples; /* number of echosounder samples in ping */

    int            num_raa_samples;         /* number of RAA (Range/Angle/Amplitude)
                                           samples in ping */

    double         mean_sv;                 /* meters per second */

    double         surface_velocity;        /* in m/s */

    int            valid_beams;             /* number of valid beams for this ping */

    double         sample_rate;             /* Hz */

    double         pulse_length;            /* micro seconds */

    int            ping_length;             /* meters */

    int            transmit_power;          /* ? */

    int            sidescan_gain_channel;   /* RDF documentation = 0 - 3 */

    int            stabilization;           /* 0 or 1 */

    int            gps_quality;             /* ? */

    double         range_uncertainty;       /* meters */

    double         angle_uncertainty;       /* degrees */

    char           spare[32];               /* 32 bytes of reserved space */
}

t_gsfGeoSwathPlusSpecific;

#define GSF_GEOSWATH_PLUS_PORT_PING 0
#define GSF_GEOSWATH_PLUS_STBD_PING 1

/* Macro definitions for EM4 series sector data details */
#define GSF_MAX_EM4_SECTORS      9

/* Macro definitions for EM3 series sector data details */
#define GSF_MAX_EM3_SECTORS      20

/* Define sub-structure for the transmit sectors */
#define GSF_EM_WAVEFORM_CW      0

```

```

#define GSF_EM_WAVEFORM_FM_UP 1
#define GSF_EM_WAVEFORM_FM_DOWN 2

typedef struct t_gsfEM4TxSector
{
    double        tilt_angle;           /* transmitter tilt angle in degrees */
    double        focus_range;          /* focusing range, 0.0 for no focusing */
    double        signal_length;        /* transmit signal duration in seconds */
    double        transmit_delay;        /* Sector transmit delay from first
transmission in seconds */
    double        center_frequency;     /* center frequency in Hz */
    double        mean_absorption;       /* mean absorption coefficient in 0.01
dB/kilometer */
    int           waveform_id;           /* signal waveform ID 0=CW; 1=FM upsweep;
2=FM downsweep */
    int           sector_number;         /* transmit sector number */
    double        signal_bandwidth;     /* signal bandwidth in Hz */
    unsigned char spare[16];            /* spare space */
}

t_gsfEM4TxSector;

typedef struct t_gsfEM3RawTxSector
{
    double        tilt_angle;           /* transmitter tilt angle in degrees */
    double        focus_range;          /* focusing range, 0.0 for no focusing */
    double        signal_length;        /* transmit signal duration in seconds */
    double        transmit_delay;        /* Sector transmit delay from first
transmission in seconds */
    double        center_frequency;     /* center frequency in Hz */
    int           waveform_id;           /* signal waveform ID 0=CW; 1=FM upsweep;
2=FM downsweep */
    int           sector_number;         /* transmit sector number */
    double        signal_bandwidth;     /* signal bandwidth in Hz */
    unsigned char spare[16];            /* spare space */
}

```

```

t_gsfEM3RawTxSector;

/* The following macro definitions are to aid in interpretation of the sonar mode field
*/

#define GSF_EM_MODE_VERY_SHALLOW 0x00      /* Bits 2,1,0 cleared means very shallow
                                             mode */

#define GSF_EM_MODE_SHALLOW      0x01      /* Bit zero set means shallow mode */

#define GSF_EM_MODE_MEDIUM        0x02      /* Bit one set means medium mode */

#define GSF_EM_MODE_DEEP          0x03      /* Bits one and zero set means deep
                                             mode */

#define GSF_EM_MODE_VERY_DEEP     0x04      /* Bit two set means very deep mode */

#define GSF_EM_MODE_EXTRA_DEEP    0x05      /* Bits two and one set means extra deep
                                             mode */

#define GSF_EM_MODE_MASK          0x07      /* Mask off bits 2,1,0 to determine just
                                             the mode */

/* Exact definition of bits 5,4,3 not
clear from document rev J. */

#define GSF_EM_MODE_DS_OFF        0xC0      /* bits 7 and 6 cleared means dual swath
                                             off */

#define GSF_EM_MODE_DS_FIXED      0x40      /* bit 6 set means dual swath in fixed
                                             mode */

#define GSF_EM_MODE_DS_DYNAMIC    0x80      /* bit 7 set means dual swath in dynamic
                                             mode */

/* Define a data structure to hold the Simrad EM series run time parameters per datagram
document rev I. */

typedef struct t_gsfEMRunTime
{
    int          model_number;      /* from the run-time parameter datagram */
    struct timespec dg_time;        /* from the run-time parameter datagram */
    int          ping_counter;      /* sequential counter 0 - 65535 */
    int          serial_number;     /* The primary sonar head serial number */
    unsigned char operator_station_status; /* Bit mask of status information for
                                             operator station */
}

```

unsigned char	processing_unit_status;	/* Bit mask of status information for sonar processor unit */
unsigned char	bsp_status;	/* Bit mask of status information for BSP status */
unsigned char	head_transceiver_status;	/* Bit mask of status information for sonar head or sonar transceiver */
unsigned char	mode;	/* Bit mask of sonar operating information, see mode bit mask definitions */
unsigned char	filter_id;	/* one byte tit mask for various sonar processing filter settings */
double	min_depth;	/* meters */
double	max_depth;	/* meters */
double	absorption;	/* dB/km */
double	tx_pulse_length;	/* in micro seconds */
double	tx_beam_width;	/* degrees */
double	tx_power_re_max;	/* The transmit power referenced to maximum power in dB */
double	rx_beam_width;	/* degrees */
double	rx_bandwidth;	/* Hz */
double	rx_fixed_gain;	/* dB */
double	tvq_cross_over_angle;	/* degrees */
unsigned char	ssv_source;	/* one byte bit mask defining SSSV source -> 0=sensor, 1>manual, 2=profile */
int	max_port_swath_width;	/* total swath width to port side in meters */
unsigned char	beam_spacing;	/* one byte bit mask -> 0=beamwidth, 1=equiangle, 2=equidistant, 3=intermediate */
int	max_port_coverage;	/* coverage to port side in degrees */
unsigned char	stabilization;	/* one byte bit mask defining yaw and pitch stabilization mode */
int	max_stbd_coverage;	/* coverage to starboard side in degrees */
int	max_stbd_swath_width;	/* total swath width to starboard side in meters */
double	durotong_speed;	/* Sound speed in durotong for the EM1002 transducer, zero if not available */
double	hi_low_absorption_ratio;	/* Absorption coeffiecent ratio */
double	tx_along_tilt;	/* Transmit fan along track tilt angle in

```

degrees */

unsigned char    filter_id_2;          /* two lowest order bits define the
                                        penetration filter setting: off, weak,
                                        medium, or strong */

unsigned char    spare[16];           /* 16 spare bytes */
}

t_gsfEMRunTime;

/* Macro definitions for bits of pu_status field */
#define GSF_EM_VALID_1_PPS            0x0001    /* If set, then 1 PPS timing is valid */
#define GSF_EM_VALID_POSITION         0x0002    /* If set, then position input is valid */
#define GSF_EM_VALID_ATTITUDE         0x0004    /* If set, then attitude input is valid */
#define GSF_EM_VALID_CLOCK            0x0008    /* If set, then clock status is valid */
#define GSF_EM_VALID_HEADING          0x0010    /* If set, then heading status is valid */
#define GSF_EM_PU_ACTIVE               0x0020    /* If set, then PU is active (i.e.
                                        pinging) */

/* Define a data structure to hold the Simrad EM series PU status values per datagram
document rev I. */
typedef struct t_gsfEMPUStatus
{
    double        pu_cpu_load;          /* Percent CPU load in the processor unit */
    unsigned short sensor_status;        /* Bit mask containing status of sensor
inputs */
    int           achieved_port_coverage; /* Achieved coverage to port in degrees */
    int           achieved_stbd_coverage; /* Achieved coverage to starboard in
degrees */
    double        yaw_stabilization;     /* in degrees */
    unsigned char spare[16];
}

t_gsfEMPUStatus;

/* Define sensor specific data structures for the Kongsberg 710/302/122 */
typedef struct t_gsfEM4Specific
{

```

```

/* values from the XYZ datagram and raw range datagram */
int          model_number;          /* 122, or 302, or 710, 850 for ME70BO */
int          ping_counter;          /* Sequential ping counter, 1 through
                                     65535 */
int          serial_number;         /* System unique serial number, 100 - ? */
double       surface_velocity;      /* Measured sound speed near the surface
                                     in m/s */
double       transducer_depth;      /* The transmit transducer depth in meters
                                     re water level at ping time */
int          valid_detections;      /* number of beams with a valid bottom
                                     detection for this ping */
double       sampling_frequency;    /* The system digitizing rate in Hz */
unsigned int  doppler_corr_scale;    /* Scale factor value to be applied to
                                     Doppler correction field prior to
                                     applying corrections */
double       vehicle_depth;         /* From 0x66 datagram, non-zero when
                                     sonar head is mounted on a sub-sea
                                     platform */

unsigned char spare_1[16];

int          transmit_sectors;      /* The number of transmit sectors for
                                     this ping */

t_gsfEM4TxSector sector[GSF_MAX_EM4_SECTORS]; /* Array of structures with transmit
                                               sector information */

unsigned char spare_2[16];

/* Values from the run-time parameters datagram */
t_gsfEMRunTime run_time;

/* Values from the PU status datagram */
t_gsfEMPUSStatus pu_status;
}

t_gsfEM4Specific;

/* Define sensor specific data structures for the Kongsberg 3000, etc which use raw
range and beam angle */
typedef struct t_gsfEM3RawSpecific
{
    /* values from the XYZ datagram and raw range datagram */

```

```

int            model_number;           /* ie 3000 ... */
int            ping_counter;           /* Sequential ping counter, 0 through
                                       65535 */
int            serial_number;          /* System unique serial number,
                                       100 - ? */
double         surface_velocity;       /* Measured sound speed near the surface
                                       in m/s */
double         transducer_depth;       /* The transmit transducer depth in
                                       meters re water level at ping time */
int            valid_detections;        /* number of beams with a valid bottom
                                       detection for this ping */
double         sampling_frequency;     /* The system digitizing rate in Hz */
double         vehicle_depth;          /* vechicle depth in 0.01 m */
double         depth_difference;        /* in meters between sonar heads in
                                       em3000d configuration */
int            offset_multiplier;       /* transducer depth offset multiplier */
unsigned char   spare_1[16];
int            transmit_sectors;       /* The number of transmit sectors for
                                       this ping */

t_gsfEM3RawTxSector sector[GSF_MAX_EM3_SECTORS]; /* Array of structures with
                                       transmit sector information */

unsigned char   spare_2[16];

/* Values from the run-time parameters datagram */
t_gsfEMRunTime  run_time;

/* Values from the PU status datagram */
t_gsfEMPUSatus  pu_status;
}

t_gsfEM3RawSpecific;

/* Define the Klein 5410 Bathy Sidescan sensor specific data structure */
typedef struct t_gsfKlein5410BssSpecific

```

```

{
    int            data_source;           /* 0 = SDF */
    int            side;                  /* 0 = port, 1 = stbd */
    int            model_number;          /* ie: 5410 */
    double         acoustic_frequency;    /* system frequency in Hz */
    double         sampling_frequency;    /* sampling frequency in Hz */
    unsigned int   ping_number;           /* 0 - 4,294,967,295 */
    unsigned int   num_samples;           /* total number of samples in this ping */
    unsigned int   num_raa_samples;       /* number of valid range, angle, amplitude
samples in ping */
    unsigned int   error_flags;           /* error flags for this ping */
    unsigned int   range;                 /* sonar range setting */
    double         fish_depth;            /* reading from the towfish pressure sensor
in Volts */
    double         fish_altitude;         /* towfish altitude in m */
    double         sound_speed;           /* speed of sound at the transducer face in
m/sec */
    int            tx_waveform;           /* transmit pulse: 0 = 132 microsec CW; 1 =
132 microsec FM; */
                                           /* 2 = 176 microsec CW; 3 = 176 microsec FM */
    int            altimeter;             /* altimeter status: 0 = passive, 1 =
active */
    unsigned int   raw_data_config;       /* raw data configuration */
    char           spare[32];             /* 32 bytes of reserved space */
}

t_gsfKlein5410BssSpecific;

/* Define the Imagenex Delta T sensor specific data structure */
typedef struct t_gsfDeltaTSpecific
{
    char           decode_file_type[4];   /* contains the decoded files extension. */
    char           version;               /* contains the minor version number of the
delta t */
    int            ping_byte_size;        /* size in bytes of this ping (256 +
(((byte 117[1 or 0])*2) + 2) * number of beams) */
    struct timespec interrogation_time;    /* The sonar interrogation time */
    int            samples_per_beam;      /* number of samples per beam */
}

```



```

    double        sector_size;           /* size of the sector in degrees */
    double        start_angle;           /* the angle that beam 0 starts at in
degrees. */
    double        angle_increment;       /* the number of degrees the angle
increments per beam */
    int           acoustic_range;        /* acoustic range in meters */
    int           acoustic_frequency;    /* acoustic frequency in kHz */
    double        sound_velocity;        /* the velocity of sound at the transducer
face in m/s */
    double        range_resolution;      /* range resolution in centimeters
(documentation says mm but all example data is in cm) */
    double        profile_tilt_angle;    /* the mounting offset */
    double        repetition_rate;       /* time between pings in milliseconds */
    unsigned long ping_number;           /* the current ping number of this ping.
*/
    unsigned char intensity_flag;         /* this tells whether the GSF will have
intensity data (1=true) */
    double        ping_latency;          /* time from sonar ping interrogation to
actual ping in seconds */
    double        data_latency;          /* time from sonar ping interrogation to
83P UDP datagram in seconds */
    unsigned char sample_rate_flag;      /* sampling rate 0 = (1 in 500); 1 = (1 in
5000) */
    unsigned char option_flags;          /* this flag states whether the data is
roll corrected or raybend corrected (1 = roll, 2 = raybend, 3 = both) */
    int           num_pings_avg;         /* number of pings averaged 1 - 25 */
    double        center_ping_time_offset; /* the time difference in seconds between
the center ping interrogation and the current ping interrogation */
    unsigned char user_defined_byte;     /* contains a user defined byte */
    double        altitude;              /* the height of the fish above the ocean
floor. */
    char          external_sensor_flags; /* this flag is a bit mask where (1 =
external heading, 2 = external roll, 4 = external pitch, 8 = external heave) */
    double        pulse_length;          /* acoustic pulse length in seconds */
    double        fore_aft_beamwidth;    /* Effective f/a beam width in degrees */
    double        athwartships_beamwidth; /* Effective athwartships beam width in
degrees */
    unsigned char spare[32];            /* room to grow */
}

t_gsfDeltaTSpecific;

```

```

/* Define sensor specific data structures for the EM12 */
typedef struct t_gsfEM12Specific
{
    int          ping_number;          /* 0 to 65535 */
    int          resolution;           /* 1 = high, 2 = low */
    int          ping_quality;         /* 21 to 81; number of beams with accepted
                                         bottom detections */
    double       sound_velocity;       /* m/s */
    int          mode;                 /* 1 to 8; shallow, deep, type of beam
                                         spacing */
    unsigned char spare[32];           /* room to grow */
} t_gsfEM12Specific;

/* Define the R2Sonic sensor specific data structure */
typedef struct t_gsfR2SonicSpecific
{
    unsigned char model_number[12];    /* Model number, e.g. "2024". Unused chars
                                         are nulls */
    unsigned char serial_number[12];  /* Serial number, e.g. "100017". Unused
                                         chars are nulls */
    struct timespec dg_time;           /* Ping time, re 00:00:00, Jan 1, 1970
                                         ("Unix time") */
    unsigned int ping_number;          /* Sequential ping counter relative to power
                                         up or reboot */
    float        ping_period;          /* Time interval between two most recent
                                         pings, seconds */
    float        sound_speed;          /* Sound speed at transducer face, m/s */
    float        frequency;            /* Sonar center frequency (Hz) */
    float        tx_power;             /* TX source level, dB re 1uPa at 1 meter */
    float        tx_pulse_width;       /* pulse width, seconds */
    float        tx_beamwidth_vert;    /* fore-aft beamwidth, radians */
    float        tx_beamwidth_horiz; /* athwartship beamwidth, radians */

```

```

float      tx_steering_vert;    /* fore-aft beam steering angle, radians, -pi
                                to +pi */
float      tx_steering_horiz;  /* athwartship beam steering angle, radians,
                                -pi to +pi */
unsigned int tx_misc_info;      /* reserved for future use */
float      rx_bandwidth;        /* receiver bandwidth, Hz */
float      rx_sample_rate;      /* receiver sample rate, Hz */
float      rx_range;            /* receiver range setting */
float      rx_gain;             /* receiver gain setting, 2dB increments
                                between steps */
float      rx_spreading;        /* TVG spreading law coefficient,
                                e.g. 20log10(range) */
float      rx_absorption;       /* TVG absorption coefficient, dB/km */
float      rx_mount_tilt;       /* radians, -pi to +pi */
unsigned int rx_misc_info;      /* reserved for future use */
unsigned short reserved;        /* reserved for future use */
unsigned short num_beams;        /* number of beams in this ping */

/* These fields are from the BTH0 packet only */
float      A0_more_info[6];     /* Additional fields associated with
                                equi-angular mode; first element
                                of array is roll */
float      A2_more_info[6];     /* Additional fields associated with
                                equi-distant mode; first element of
                                array is roll */
float      G0_depth_gate_min;    /* global minimum gate in seconds (twtt) */
float      G0_depth_gate_max;    /* global maximum gate in seconds (twtt) */
float      G0_depth_gate_slope; /* slope of depth gate (radians, -pi to +pi) */
unsigned char spare[32];         /* saved for future expansion */
}

t_gsfR2SonicSpecific;

/* The following macro definitions are for the KMALL structures */
#define GSF_MAX_KMALL_EXTRA_CLASSES 11

```

```

#define GSF_MAX_KMALL_EXTRA_DETECT    1024
#define GSF_KMALL_MRZ                  1

typedef struct t_gsfKMALLTxSector
{
    int            txSectorNumb;        /* transmit sector number */
    int            txArrNumber;         /* transmit array number */
    int            txSubArray;          /* transmit sub-array number: 0 = Port, 1 =
                                         Middle, 2 = Starboard */
    double         sectorTransmitDelay_sec; /* seconds, time difference of midpoint of
                                         current tx pulse over first tx pulse of
                                         ping (which is equivalent to the datagram
                                         header time) */
    double         tiltAngleReTx_deg;    /* degrees, transmitter beam along ship
                                         steering angle wrt. transmitter coordinate
                                         system */
    double         txNominalSourceLevel_dB; /* decibels, relative 1 microPascal */
    double         txFocusRange_m;        /* meters, 0 = no focusing applied */
    double         centreFreq_Hz;         /* Hertz, center frequency */
    double         signalBandWidth_Hz;    /* Hertz, FM mode: effective bandwidth, CW
                                         mode: 1/(effective tx pulse length) */
    double         totalSignalLength_sec; /* seconds, transmit pulse length */
    int            pulseShading;          /* Percent amplitude shading. Shading in
                                         time. Cos2 function used for shading */
    int            signalWaveForm;        /* 0 = CW, 1 = FM upsweep, 2 = FM
                                         downsweep */
    float          highVoltageLevel_dB;   /* voltage level in dB */
    float          sectorTrackiongCorr_dB; /* Sector Tracking Correction in dB
                                         */
    float          effectiveSignalLength_sec; /* Effective Signal Length in
                                         seconds */
    unsigned char  spare1[8];
}

t_gsfKMALLTxSector;

typedef struct t_gsfKMALLExtraDetClass
{
    int            numExtraDetInClass; /* number of extra detections of this class */

```

```

    int            alarmFlag;           /* 0 = no alarm, 1 = alarm */
    unsigned char   spare[32];
}

t_gsfKMALLExtraDet;

typedef struct t_gsfKMALLSpecific
{
    int            gsfKMALLVersion;     /* == 1 for GSF_03.10 */
    /* values from the header of #MRZ */
    int            dgmType;             /* a one byte integer value: 1 == #MRZ, ... */
    int            dgmVersion;          /* a one byte integer value */
    int            systemID;            /* parameter used to identify datagrams from
                                         separate echosounders when multiple
                                         echosounders are connected */
    int            echoSounderID;       /* 122, 302, 710, 712, 2040,850 for ME70BO */
    unsigned char   spare1[8];
    /* values from the cmnPart of #MRZ */
    int            numBytesCmnPart;     /* Size of cmnPart */
    int            pingCnt;             /* (short in kmall) Sequential ping counter, 1
                                         through 65535 */
    int            rxFansPerPing;       /* Number of rx fans per ping, together with
                                         swaths per ping determines number of
                                         datagrams per swath */
    int            rxFanIndex;          /* Index of rx fan, 0 = aft, port swath */
    int            swathsPerPing;       /* Swaths per ping, swath is a complete set of
                                         across track data, may contain several
                                         transmit sectors and RX fans */
    int            swathAlongPosition; /* Alongship index for swath in multi-swath
                                         mode, 0 = aftmost */
    int            txTransducerInd;     /* Transducer used in this rx fan: 0 =
                                         TRAI_TX1, 1 = TRAI_TX2, ... */
    int            rxTransducerInd;     /* Transducer used in this rx fan: 0 =
                                         TRAI_RX1, 1 = TRAI_RX2, ... */
    int            numRxTransducers;    /* Total number of recieving units */
    int            algorithmType;       /* Future use. 0 = current, else future */
    unsigned char   spare2[16];
    /* values from the pingInfo of #MRZ */
    int            numBytesInfoData;    /* Size of ping info structure */

```

double	pingRate_Hz;	/* Ping rate computed by the sonar */
int	beamSpacing;	/* 0 = Equidistance, 1 = Equiangle, 2 = High Density */
int	depthMode;	/* 0 = Very shallow, 1 = Shallow, 2 = Medium, 3 = Deep, 4 = Deeper, 5 = Very Deep, 6 = Extra Deep, 7 = Extreme deep */
int	subDepthMode;	/* Advanced use for manual depth mode, 0 = unused */
int	distanceBtwSwath;	/* achieved istance between swaths as percentage of requirement: 0=unused, 100=achieved equals required */
int	detectionMode;	/* Bottom detection: 0 = normal, 1 = waterway, 2 = tracking, 3 = minimum depth */
int	pulseForm;	/* 0 = CW, 1 = mix, 2 = FM */
double	frequencyMode_Hz;	/* A code if < 100, otherwise the transmit frequency Hz. Codes: -1 = not used, 0 = 40-100 khz, 1 = 50-100khz, 2 = 70-100khz, 3 = 50khz, 4 = 40khz */
double	freqRangeLowLim_Hz;	/* In hertz, lowest center frequency of swath's sectors */
double	freqRangeHighLim_Hz;	/* In hertz, highest center frequency of swath's sectors */
double	maxTotalTxPulseLength_sec;	/* In seconds, longest tx pulse of swath's sectors */
double	maxEffTxPulseLength_sec;	/* In seconds, longest effective tx pulse of swath's sectors */
double	maxEffTxBandWidth_Hz;	/* Effective bandwidth (-3dB envelope) of the sector with the highest bandwidth */
double	absCoeff_dBPerkm;	/* Average absorption coefficient, in dB/km for vertical beam at current depth */
double	portSectorEdge_deg;	/* Port sector edge, for use by beamformer, referenced to z of SCS */
double	starbSectorEdge_deg;	/* Starboard sector edge, for use by beamformer, referenced to z of SCS */
double	portMeanCov_deg;	/* Coverage achieved in degrees, corrected for raybending, referenced to z of SCS */
double	starbMeanCov_deg;	/* Coverage achieved in degrees, corrected for raybending, referenced to z of SCS */
double	portMeanCov_m;	/* Coverage achieved in meters, corrected for raybending, referenced to z of SCS */

```

double          starbMeanCov_m;          /* Coverage achieved in meters,
                                           corrected for raybending, referenced to
                                           z of SCS */

int             modeAndStabilisation;    /* Bit mask: 1 = Pitch, 2 = yaw, 3 =
                                           sonar mode, 4 = angular coverage mode,
                                           5 = sector mode, 6 = swath along
                                           position, 7 & 8 = future use */

int             runtimeFilter1;          /* Bit mask: 1 = Slope, 2 = Aeration, 3
                                           = Sector, 4 = Interference, 5 = Special
                                           Amplitude, 6 - 8 = future use */

int             runtimeFilter2;          /* Bit mask: 1-4 = range gate, 5-8 =
                                           spike filter, 9-12 penetration filter,
                                           13-16 phase ramp */

int             pipeTrackingStatus;      /* Pipe tracking status. Describes how
                                           angle and range of top of pipe is
                                           determined. 0 = for future use, 1 = PU
                                           uses guidance from SIS */

double          transmitArraySizeUsed_deg; /* degrees, transmit array size along
                                           ship */

double          receiveArraySizeUsed_deg; /* degrees, receiver array size
                                           across ship */

double          transmitPower_dB;        /* dB, transmit power relative to
                                           maximum (0 dB, -10 dB, -20 dB ...) */

int             SLrampUpTimeRemaining;    /* percentage, time remaining until max
                                           source level is acheived */

double          yawAngle_deg;            /* degrees, yaw correction angle */

int             numTxSectors;            /* The number of transmit sectors for
                                           this ping */

int             numBytesPerTxSector;      /* Number of bytes in the
                                           EMDgmMRZ_txSectorInfo */

double          headingVessel_deg;        /* Degrees, Heading of vessel at time of
                                           midpoint of first tx pulse */

double          soundSpeedAtTxDepth_mPerSec; /* Measured sound speed at the
                                           transducer depth in m/s at time
                                           of midpoint of first tx pulse,
                                           (Source set in K-controller) */

double          txTransducerDepth_m;      /* meters, the transmit
                                           transducer depth in meters re
                                           water level at time of midpoint
                                           of first tx pulse */

double          z_waterLevelReRefPoint_m; /* meters, the vertical distance
                                           between the waterline and vessel
                                           reference point, measured in SCS
                                           */

```

```

double          x_kmallToall_m;      /* meters, distance between *.all reference
                                     point and *.kmall reference point, measured
                                     in SCS */

double          y_kmallToall_m;      /* meters, distance between *.all reference
                                     point and *.kmall reference point, measured
                                     in SCS */

int             latLongInfo;         /* Sensor Position data method: 0 = last
                                     position received, 1 = interpolated, 2 =
                                     processed*/

int             posSensorStatus;     /* Position sensor status 0 = valid data, 1
                                     = invalid data, 2 = reduced performance
                                     (Format TBD) */

int             attitudeSensorStatus; /* Attitude sensor status 0 = valid
                                     data, 1 = invalid data, 2 = reduced
                                     performance (Format TBD) */

double          latitude_deg;        /* decimal degrees, location of vessel
                                     reference point reported by sensor,
                                     determined by method in lat_lon_info */

double          longitude_deg;       /* decimal degrees, location of vessel
                                     reference point reported by sensor,
                                     determined by method in lat_lon_info */

double          ellipsoidHeightReRefPoint_m; /* meters, height of vessel
                                     reference point above ellipsoid,
                                     derived from active GGA sensor */

unsigned char    spare3[32];

/* values from the sectorInfo of #MRZ */

    t_gsfKMALLTxSector  sector[GSF_MAX_KMALL_SECTORS]; /* Array of structures with
                                                         transmit sector information */

/* values from the rxInfo of #MRZ */

int             numBytesRxInfo;      /* Size of the rxInfo structure portion
                                     of the datagram */

int             numSoundingsMaxMain; /* Number of beams (valid and non valid)
                                     recorded in sounding array */

int             numSoundingsValidMain; /* Number of beams with a valid bottom
                                     detection for this ping */

int             numBytesPerSounding; /* Bytes per loop of soundings */

double          WCSampleRate;        /* The system digitizing rate in Hz, value
                                     retrieved from the imagery datagram */

double          seabedImageSampleRate; /* Sample frequency divided by seabed
                                     image decimation factor in hertz */

double          BSnormal_dB;         /* normal incidence BS in dB */

double          BSoblique_dB;        /* oblique incidence BS in dB */

```



```

    int                extraDetectionAlarmFlag;    /* sum of alarm flags from extra
                                                    detections */

    int                numExtraDetections;        /* The number of extra detections
                                                    (soundings in water column) */

    int                numExtraDetectionClasses;    /* The number of extra detection
                                                    classes */

    int                numBytesPerClass;          /* Size of the extra detection class */

    unsigned char      spare4[32];

/* Values from the extraDetClassInfo array */

    t_gsfKMALLExtraDet  extraDetClassInfo[GSF_MAX_KMALL_EXTRA_CLASSES]; /* Array of
                                                    extra detection classes */

    unsigned char      spare5[32];
}

t_gsfKMALLSpecific;

/* Define a union of the known sensor specific ping subrecords */
typedef union t_gsfSensorSpecific
{
    t_gsfSeaBeamSpecific    gsfSeaBeamSpecific;
    t_gsfEM100Specific      gsfEM100Specific;
    t_gsfEM121ASpecific     gsfEM121ASpecific;
    t_gsfEM121ASpecific     gsfEM121Specific;
    t_gsfSeaBatSpecific     gsfSeaBatSpecific;
    t_gsfEM950Specific      gsfEM950Specific;
    t_gsfEM950Specific      gsfEM1000Specific;
    t_gsfSeamapSpecific     gsfSeamapSpecific;

    #if 1
    /* 03-30-99 wkm/dbj: Obsolete replaced with gsfCmpSassSpecific */
    t_gsfTypeIIISpecific    gsfTypeIIISeaBeamSpecific;
    t_gsfTypeIIISpecific    gsfSASSSpecific;
    #endif

    t_gsfCmpSassSpecific    gsfCmpSassSpecific;

```

```

t_gsfSBampSpecific      gsfSBampSpecific;
t_gsfSeaBatIISpecific   gsfSeaBatIISpecific;
t_gsfSeaBat8101Specific gsfSeaBat8101Specific;
t_gsfSeaBeam2112Specific gsfSeaBeam2112Specific;
t_gsfElacMkIISpecific   gsfElacMkIISpecific;
t_gsfEM3Specific        gsfEM3Specific;          /* used for EM120, EM300, EM1002,
                                                    EM3000, EM3002, and EM121A_SIS */
t_gsfEM3RawSpecific     gsfEM3RawSpecific;        /* used for EM120, EM300, EM1002,
                                                    EM3000, EM3002, and EM121A_SIS
                                                    with raw range and beam angle */

t_gsfReson8100Specific  gsfReson8100Specific;
t_gsfReson7100Specific  gsfReson7100Specific;
t_gsfResonTSeriesSpecific gsfResonTSeriesSpecific; /* used for T50 and T20 */
t_gsfEM4Specific        gsfEM4Specific;          /* used for EM710, EM302, EM122,
                                                    ,EM2040, and ME70BO */
t_gsfGeoSwathPlusSpecific gsfGeoSwathPlusSpecific; /* DHG 2006/09/27 Use for
                                                    GeoSwath+ interferometer */
t_gsfKlein5410BssSpecific gsfKlein5410BssSpecific; /* Use for Klein 5410 Bathy
                                                    Sidescan. */

t_gsfDeltaTSpecific     gsfDeltaTSpecific;
t_gsfEM12Specific       gsfEM12Specific;
t_gsfR2SonicSpecific    gsfR2SonicSpecific;
t_gsfKMALLSpecific      gsfKMALLSpecific;        /* used for KMALL compliant
                                                    sensors */

    /* Single beam sensors added */
t_gsfSBEchoTracSpecific gsfSBEchoTracSpecific;
t_gsfSBEchoTracSpecific gsfSBBathy2000Specific;
t_gsfSBMGD77Specific    gsfSBMGD77Specific;
t_gsfSBBDBSpecific      gsfSBBDBSpecific;
t_gsfSBNOSHDBSpecific   gsfSBNOSHDBSpecific;
t_gsfSBEchoTracSpecific gsfSBPDDSpecific;
t_gsfSBNavisoundSpecific gsfSBNavisoundSpecific;
} gsfSensorSpecific;

```

**Table 4-1 Sensor ID allocation to Sensor Specific Subrecord Data Structure**

Sensor ID	Sensor Specific Subrecord Structure
GSF_SWATH_BATHY_SUBRECORD_SEABEAM_SPECIFIC	gsfSeaBeamSpecific
GSF_SWATH_BATHY_SUBRECORD_EM100_SPECIFIC	gsfEM100Specific
GSF_SWATH_BATHY_SUBRECORD_EM12_SPECIFIC	gsfEM12Specific
GSF_SWATH_BATHY_SUBRECORD_EM121A_SPECIFIC	gsfEM121ASpecific
GSF_SWATH_BATHY_SUBRECORD_EM121_SPECIFIC	gsfEM121Specific
GSF_SWATH_BATHY_SUBRECORD_SEABAT_SPECIFIC	gsfSeaBatSpecific
GSF_SWATH_BATHY_SUBRECORD_EM950_SPECIFIC	gsfEM950Specific
GSF_SWATH_BATHY_SUBRECORD_EM1000_SPECIFIC	gsfEM1000Specific
GSF_SWATH_BATHY_SUBRECORD_SEAMAP_SPECIFIC	gsfSeamapSpecific
GSF_SWATH_BATHY_SUBRECORD_TYPEIII_SEABEAM_SPECIFIC	gsfTypeIIISeaBeamSpecific
GSF_SWATH_BATHY_SUBRECORD_SASS_SPECIFIC	gsfSASSSpecific
GSF_SWATH_BATHY_SUBRECORD_CMP_SASS_SPECIFIC	gsfCmpSassSpecific
GSF_SWATH_BATHY_SUBRECORD_SB_AMP_SPECIFIC	gsfSBampSpecific
GSF_SWATH_BATHY_SUBRECORD_SEABAT_II_SPECIFIC	gsfSeaBatIISpecific
GSF_SWATH_BATHY_SUBRECORD_SEABAT_8101_SPECIFIC	gsfSeaBat8101Specific
GSF_SWATH_BATHY_SUBRECORD_SEABEAM_2112_SPECIFIC	gsfSeaBeam2112Specific
GSF_SWATH_BATHY_SUBRECORD_ELAC_MKII_SPECIFIC	gsfElacMkIISpecific
GSF_SWATH_BATHY_SUBRECORD_EM3000_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_EM1002_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_EM300_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_EM120_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_EM3002_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_EM3000D_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_EM3002D_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_EM121A_SIS_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_EM2000_SPECIFIC	gsfEM3Specific
GSF_SWATH_BATHY_SUBRECORD_RESON_8101_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_RESON_8111_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_RESON_8124_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_RESON_8125_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_RESON_8150_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_RESON_8160_SPECIFIC	gsfReson8100Specific

GSF_SWATH_BATHY_SUBRECORD_GEOSWATH_PLUS_SPECIFIC	gsfGeoSwathPlusSpecific
GSF_SWATH_BATHY_SUBRECORD_EM710_SPECIFIC	gsfEM4Specific
GSF_SWATH_BATHY_SUBRECORD_EM302_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_EM122_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_EM2040_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_ME70BO_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_KLEIN_5410_BSS_SPECIFIC	gsfKlein5410BssSpecific
GSF_SWATH_BATHY_SUBRECORD_RESON_7125_SPECIFIC	gsfReson7100Specific
GSF_SWATH_BATHY_SUBRECORD_RESON_TSERIES_SPECIFIC	gsfResonTSeriesSpecific
GSF_SWATH_BATHY_SUBRECORD_EM300_RAW_SPECIFIC	gsfEM3RawSpecific
GSF_SWATH_BATHY_SUBRECORD_EM1002_RAW_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_EM2000_RAW_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_EM3000_RAW_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_EM120_RAW_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_EM3002_RAW_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_EM3000D_RAW_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_EM3002D_RAW_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_EM121A_SIS_RAW_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_DELTA_T_SPECIFIC	gsfDeltaTSpecific
GSF_SWATH_BATHY_SUBRECORD_R2SONIC_2020_SPECIFIC	gsfR2SonicSpecific
GSF_SWATH_BATHY_SUBRECORD_R2SONIC_2022_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_R2SONIC_2024_SPECIFIC	
GSF_SWATH_BATHY_SUBRECORD_KMALL_SPECIFIC	gsfKMALLSpecific
GSF_SWATH_BATHY_SUBRECORD_ME70BO_SPECIFIC	t_gsfEM4Specific

### 4.1.2.3 Bathymetric Receive Beam Time Series Intensity Subrecord

```
typedef struct gsfTimeSeriesIntensity
{
    unsigned short sample_count;          /* number of amplitude samples per beam */
    unsigned short detect_sample;         /* index of bottom detection sample for the beam */
    unsigned short start_range_samples; /* Kmall start of sample index*/
    unsigned char  spare[6];              /* for future use */
}
```

```

        unsigned int    *samples;           /* Array of per-beam time series intensity
                                           samples */
    } gsfTimeSeriesIntensity;

#define GSF_INTENSITY_LINEAR      (unsigned)0x01
#define GSF_INTENSITY_CALIBRATED (unsigned)0x02
#define GSF_INTENSITY_POWER      (unsigned)0x04
#define GSF_INTENSITY_GAIN       (unsigned)0x08

typedef struct t_gsfBRBIntensity
{
    unsigned char        bits_per_sample;    /* bits per intensity sample */
    unsigned int         applied_corrections; /* flags to describe corrections
                                           applied to intensity values */

    unsigned char        spare[16];         /* spare header space */
    gsfsensorimagery     sensor_imagery;     /* sensor specific per-ping imagery
                                           information */

    gsfTimeSeriesIntensity *time_series;     /* array of per-beam time series
                                           intensity records */
} gsfBRBIntensity;

typedef struct t_gsfEM3ImagerySpecific
{
    unsigned short range_norm;              /* range to normal incidence used to correct
                                           sample amplitudes (in samples) */

    unsigned short start_tvg_ramp;          /* start range sample of TVG ramp if not enough
                                           dynamic range (0 else) */

    unsigned short stop_tvg_ramp;           /* stop range sample of TVG ramp if not enough
                                           dynamic range (0 else) */

    char              bsn;                  /* normal incidence BS in dB */
    char              bso;                  /* oblique BS in dB */
    double            mean_absorption;      /* mean absorption coefficient in dB/km,
                                           resolution of 0.01 dB/km */

```

```

        short            offset;                /* Value that has been added to all imagery
                                                samples to convert to a positive value */

        short            scale;                /* Manufacturer's specified scale value for each
                                                sample. This value is 2 for data from
                                                EM3000EM3002/EM1002/EM300/EM120 */

        unsigned char    spare[4];            /* spare sensor specific subrecord space,
                                                reserved for future expansion */
    } t_gsfEM3ImagerySpecific;

typedef struct t_gsfReson7100ImagerySpecific
{
    unsigned short size;

    unsigned char    spare[64];                /* spare sensor specific subrecord space,
                                                reserved for future expansion */
} t_gsfReson7100ImagerySpecific;

typedef struct t_gsfResonTSeriesImagerySpecific
{
    unsigned short size;

    unsigned char    spare[64];                /* spare sensor specific subrecord space,
                                                reserved for future expansion */
} t_gsfResonTSeriesImagerySpecific;

typedef struct t_gsfReson8100ImagerySpecific
{
    unsigned char    spare[8];                /* spare sensor specific subrecord space,
                                                reserved for future expansion */
} t_gsfReson8100ImagerySpecific;

typedef struct t_gsfEM4ImagerySpecific
{
    double            sampling_frequency;    /* The system digitizing rate in Hz, value
                                                retrieved from the imagery datagram */

    double            mean_absorption;        /* mean absorption coefficient in dB/km, from
                                                0x53 datagram, 0 if data is from 0x59 */

    double            tx_pulse_length;        /* transmit pulse length in microseconds from
                                                imagery datagram 0x53, or 0x59 */

    int                range_norm;            /* range to normal incidence used to correct
                                                sample amplitudes (in samples) */

```

```

        int            start_tvlg_ramp;        /* start range (in samples) of TVG ramp if not
                                                enough dynamic range 0 means not used
*/
        int            stop_tvlg_ramp;        /* stop range (in samples) of TVG ramp if not
                                                enough dynamic range 0 means not used */

        double         bsn;                   /* normal incidence BS in dB */
        double         bso;                   /* oblique incidence BS in dB */
        double         tx_beam_width;         /* transmit beam width in degrees from imagery
                                                datagram */

        double         tvlg_cross_over;       /* The TVG law crossover angle in degrees */
        short          offset;                /* Value that has been added to all imagery
                                                samples to convert to a positive value */

        short          scale;                 /* Manufacturer's specified scale value for each
                                                sample. This value is 10 for data from
                                                EM710/EM302/EM122 */

        unsigned char   spare[20];           /* spare sensor specific subrecord space,
                                                reserved for future expansion */

} t_gsfEM4ImagerySpecific;

typedef struct t_gsfKlein5410BssImagerySpecific
{
    unsigned int        res_mode;             /* Descriptor for resolution mode: 0 = normal; 1
= high */
    unsigned int        tvlg_page;           /* TVG page number */
    unsigned int        beam_id[5];          /* array of identifiers for five sidescan beam
magnitude time series, starting with beam id 1 as the forward-most */
    unsigned char        spare[4];           /* spare sensor specific subrecord space,
reserved for future expansion */
} t_gsfKlein5410BssImagerySpecific;

typedef struct t_gsfR2SonicImagerySpecific
{
    unsigned char        model_number[12];    /* Model number, e.g. "2024". Unused chars
                                                are nulls */
    unsigned char        serial_number[12];  /* Serial number, e.g. "100017". Unused
                                                chars are nulls */

```

```

struct timespec dg_time;          /* Ping time, re 00:00:00, Jan 1, 1970
                                   ("Unix time") */

unsigned int    ping_number;      /* Sequential ping counter relative to power
                                   up or reboot */

float           ping_period;      /* Time interval between two most recent
                                   pings, seconds */

float           sound_speed;      /* Sound speed at transducer face, m/s */
float           frequency;        /* Sonar center frequency (Hz) */
float           tx_power;         /* TX source level, dB re 1uPa at 1 meter */
float           tx_pulse_width;   /* pulse width, seconds */
float           tx_beamwidth_vert; /* fore-aft beamwidth, radians */
float           tx_beamwidth_horiz; /* athwartship beamwidth, radians */
float           tx_steering_vert; /* fore-aft beam steering angle, radians,
                                   -pi to +pi */
float           tx_steering_horiz; /* athwartship beam steering angle, radians,
                                   -pi to +pi */

unsigned int    tx_misc_info;      /* reserved for future use */
float           rx_bandwidth;      /* receiver bandwidth, Hz */
float           rx_sample_rate;    /* receiver sample rate, Hz */
float           rx_range;          /* receiver range setting, seconds in doc */
float           rx_gain;           /* receiver gain setting, 2dB increments
                                   between steps */
float           rx_spreading;      /* TVG spreading law coefficient,
                                   e.g. 20log10(range) */
float           rx_absorption;     /* TVG absorption coefficient, dB/km */
float           rx_mount_tilt;     /* radians, -pi to +pi */
unsigned int    rx_misc_info;      /* reserved for future use */
unsigned short  reserved;          /* reserved for future use */
unsigned short  num_beams;         /* number of beams in this ping */
float           more_info[6];      /* reserved for future use, from SNI0
                                   datagram */

unsigned        spare[32];         /* saved for future expansion */
}

t_gsfR2SonicImagerySpecific;

```



```

typedef union t_gsfSensorImagery
{
    t_gsfEM3ImagerySpecific      gsfEM3ImagerySpecific;      /* used for EM120,
                                                                EM300, EM1002,
                                                                EM3000 */

    t_gsfReson7100ImagerySpecific  gsfReson7100ImagerySpecific; /* For Reson 71P
                                                                "snippet"
                                                                imagery */

    t_gsfReson8100ImagerySpecific  gsfReson8100ImagerySpecific; /* For Reson 81P
                                                                "snippet"
                                                                imagery */

    t_gsfResonTSeriesImagerySpecific gsfResonTSeriesImagerySpecific; /* For Reson
                                                                TSeries
                                                                "snippet"
                                                                imagery */

    t_gsfEM4ImagerySpecific      gsfEM4ImagerySpecific;      /* used for EM122,
                                                                EM302, EM710 */

    t_gsfKlein5410BssImagerySpecific gsfKlein5410BssImagerySpecific; /* used for Klein
                                                                5410 Bathy
                                                                Sidescan */

    t_gsfR2SonicImagerySpecific    gsfR2SonicImagerySpecific; /* used for R2Sonic
                                                                */

    t_gsfKMALLImagerySpecific      gsfKMALLImagerySpecific;   /* used for KMALL
                                                                compliant sensors
                                                                */

} gsfSensorImagery;

```

#### 4.1.3 SINGLE-BEAM BATHYMETRY RECORD

/\* Define a single beam record structure \*/

```

typedef struct t_gsfSingleBeamPing
{
    struct timespec ping_time;      /* Time the sounding was made */

    double          latitude;       /* latitude (degrees) of sounding */

    double          longitude;      /* longitude (degrees) of sounding */

    double          tide_corrector; /* in meters */

    double          depth_corrector; /* in meters, draft corrector for sensor */

    double          heading;        /* in degrees */

    double          pitch;          /* in meters */
}

```

```

double      roll;                /* in meters */
double      heave;              /* in meters */
double      depth;              /* in meters */
double      sound_speed_correction; /* in meters */
unsigned short positioning_system_type;
int         sensor_id;
gsfSBSensorSpecific sensor_data;
}

gsfSingleBeamPing;

```

Note that while GSF maintains both read and write support for the Single-Beam record definition, users are actively discouraged from using this record. The preferred means of saving single beam data is to use the `gsfSwathBathyPing` record definition, with the `number_beams` field set to one.

#### 4.1.3.1 Single-beam Sensor-specific Subrecords

```

/* Define the Echotrac Single-Beam sensor specific data structure. */
typedef struct t_gsfEchotracSpecific
{
    int          navigation_error;
    unsigned short mpp_source;      /* Flag To determine if nav was mpp */
    unsigned short tide_source;
}

t_gsfEchotracSpecific;

/* Define the MGD77 Single-Beam sensor specific data structure. */
typedef struct t_gsfMGD77Specific
{
    unsigned short time_zone_corr;
    unsigned short position_type_code;
    unsigned short correction_code;
    unsigned short bathy_type_code;
    unsigned short quality_code;
    double travel_time;
}

```

```

}

t_gsfMGD77Specific;

/* Define the BDB sensor specific data structure */
typedef struct t_gsfBDBSpecific
{
    int    doc_no;           /* Document number (5 digits) */
    char   eval;            /* Evaluation (1-best, 4-worst) */
    char   classification; /* Classification ((U)nclass, (C)onfidential,
                           (S)ecret, (P)roprietary/Unclass,
                           (Q)Proprietary/Class) */
    char   track_adj_flag; /* Track Adjustment Flag (Y,N) */
    char   source_flag;    /* Source Flag ((S)urvey, (R)andom, (O)cean Survey) */
    char   pt_or_track_ln; /* Discrete Point (D) or Track Line (T) Flag */
    char   datum_flag;     /* Datum Flag ((W)GS84, (D)atumless) */
}

t_gsfBDBSpecific;

/* Define the NOS HDB sensor specific data structure */
typedef struct t_gsfNOSHDBSpecific
{
    unsigned short type_code; /* Depth type code */
    unsigned short carto_code; /* Cartographic code */
}

t_gsfNOSHDBSpecific;

```

#### 4.1.4 SOUND VELOCITY PROFILE (SVP) RECORD

```

typedef struct t_gsfSVP
{
    struct timespec observation_time; /* time the SVP measurement was made */
    struct timespec application_time; /* time the SVP was used by the sonar */
    double          latitude;         /* latitude (degrees) of SVP measurement */
}

```

```

    double    longitude;          /* longitude (degrees) of SVP measurement */
    int        number_points;      /* number of data points in the profile */
    double     *depth;             /* array of profile depth values in meters */
    double     *sound_speed;       /* array of profile sound velocity values in m/s */
}
gsfSVP;

```

#### 4.1.5 PROCESSING PARAMETERS RECORD

```

#define GSF_MAX_PROCESSING_PARAMETERS 128
typedef struct t_gsfProcessingParameters
{
    struct timespec param_time;
    int    number_parameters;
    short  param_size[GSF_MAX_PROCESSING_PARAMETERS]; /* array of sizes of param text*/
    char   *param[GSF_MAX_PROCESSING_PARAMETERS];     /* array of parameters:
                                                         "param_name=param_value" */
}
gsfProcessingParameters;

```

##### 4.1.5.1 Internal Structure for Processing Parameters

```

#define GSF_MAX_OFFSETS          2
#define GSF_COMPENSATED          1
#define GSF_UNCOMPENSATED        0
#define GSF_TRUE_DEPTHS          1
#define GSF_DEPTHS_RE_1500_MS    2
#define GSF_DEPTH_CALC_UNKNOWN   3
#define GSF_UNKNOWN_PARAM_VALUE  DBL_MIN    /* defined in <float.h> */
#define GSF_TRUE                  1
#define GSF_FALSE                  0

/* Macro definitions for type of platform */
#define GSF_PLATFORM_TYPE_SURFACE_SHIP  0    /* Add for AUV vs Surface Ship

```

```

discrimination */

#define GSF_PLATFORM_TYPE_AUV          1      /* Add for AUV vs Surface Ship
discrimination */

#define GSF_PLATFORM_TYPE_ROTV         2

typedef struct t_gsfMBOffsets
{
    double    draft[GSF_MAX_OFFSETS];          /* meters */
    double    roll_bias[GSF_MAX_OFFSETS];       /* degrees */
    double    pitch_bias[GSF_MAX_OFFSETS];      /* degrees */
    double    gyro_bias[GSF_MAX_OFFSETS];       /* degrees */
    double    position_x_offset;                /* meters */
    double    position_y_offset;                /* meters */
    double    position_z_offset;                /* meters */
    double    antenna_x_offset;                 /* meters */
    double    antenna_y_offset;                 /* meters */
    double    antenna_z_offset;                 /* meters */
    double    transducer_x_offset[GSF_MAX_OFFSETS]; /* meters */
    double    transducer_y_offset[GSF_MAX_OFFSETS]; /* meters */
    double    transducer_z_offset[GSF_MAX_OFFSETS]; /* meters */
    double    transducer_pitch_offset[GSF_MAX_OFFSETS]; /* degrees */
    double    transducer_roll_offset[GSF_MAX_OFFSETS]; /* degrees */
    double    transducer_heading_offset[GSF_MAX_OFFSETS]; /* degrees */
    double    mru_roll_bias;                    /* degrees */
    double    mru_pitch_bias;                   /* degrees */
    double    mru_heading_bias;                 /* degrees */
    double    mru_x_offset;                     /* meters */
    double    mru_y_offset;                     /* meters */
    double    mru_z_offset;                     /* meters */
    double    center_of_rotation_x_offset;       /* meters */
    double    center_of_rotation_y_offset;       /* meters */
    double    center_of_rotation_z_offset;       /* meters */
    double    position_latency;                  /* seconds */
    double    attitude_latency;                  /* seconds */

```

```

double    depth_sensor_latency;                /* seconds */
double    depth_sensor_x_offset;               /* meters */
double    depth_sensor_y_offset;               /* meters */
double    depth_sensor_z_offset;               /* meters */
double    rx_transducer_x_offset[GSF_MAX_OFFSETS]; /* meters */
double    rx_transducer_y_offset[GSF_MAX_OFFSETS]; /* meters */
double    rx_transducer_z_offset[GSF_MAX_OFFSETS]; /* meters */
double    rx_transducer_pitch_offset[GSF_MAX_OFFSETS]; /* degrees */
double    rx_transducer_roll_offset[GSF_MAX_OFFSETS]; /* degrees */
double    rx_transducer_heading_offset[GSF_MAX_OFFSETS]; /* degrees */
double    altimeter_z_offset; /* degrees */
double    altimeter_x_offset; /* degrees */
double    altimeter_y_offset; /* degrees */
} gsFMBOffsets;

/* Define a data structure to hold multibeam sonar processing parameters */
typedef struct t_gsFMBParams
{
    /* These parameters define reference points */
    char start_of_epoch[64];
    int horizontal_datum;
    int vertical_datum;
    int utc_offset;      /* Offset in hours from UTC to local time of collection. */
    /* These parameters defined the installed hardware */
    int number_of_transmitters;
    int number_of_receivers;

    /* These parameters specify what corrections have been applied to the data */
    int roll_reference;      /* = roll is horizontal or rotated pitch axis */
    int roll_compensated;    /* = GSF_COMPENSATED if depth data roll corrected */
    int pitch_compensated;   /* = GSF_COMPENSATED if depth data pitch corrected */
    int heave_compensated;  /* = GSF_COMPENSATED if depth data heave corrected */
    int tide_compensated;    /* = GSF_COMPENSATED if depth data tide corrected */

```

```

int ray_tracing;          /* = GSF_COMPENSATED if travel time/angle pairs are
                           compensated for ray tracing */

int depth_calculation;    /* = GSF_TRUE_DEPTHS, or GSF_DEPTHS_RE_1500_MS,
                           applicable to the depth field */

int vessel_type;          /* Surface ship, AUV, etc. */

int full_raw_data;        /* = GSF_TRUE all data required for full
                           recalculation */

int msb_applied_to_attitude; /* = GSF_TRUE if contains motion sensor biases */

int heave_removed_from_gps_tc; /* = GSF_TRUE if heave removed from
                                gps_tide_corrector */

/* These parameters specify known offsets that have NOT been corrected.
 * If each of these values are zero, then all known offsets have been
 * corrected for.
 */

gsfMBOffsets to_apply;

/* These parameters specify offsets which have already been corrected. */

gsfMBOffsets applied;
} gsfMBParams;

```

#### 4.1.6 SENSOR PARAMETERS RECORD

```

#define GSF_MAX_SENSOR_PARAMETERS 128

typedef struct t_gsfSensorParameters
{
    struct timespec param_time;

    int      number_parameters;

    short    param_size[GSF_MAX_SENSOR_PARAMETERS]; /* array of sizes of param text*/

    char      *param[GSF_MAX_SENSOR_PARAMETERS];    /* array of parameters:
                                                         "param_name=param_value" */
}

gsfSensorParameters;

```

#### 4.1.7 COMMENT RECORD

```
typedef struct t_gsfComment
{
    struct timespec comment_time;
    int             comment_length;
    char            *comment;
}
gsfComment;
```

#### 4.1.8 HISTORY RECORD

```
#define GSF_OPERATOR_LENGTH 64
#define GSF_HOST_NAME_LENGTH 64
typedef struct t_gsfHistory
{
    struct timespec history_time;
    char            host_name[GSF_HOST_NAME_LENGTH + 1];
    char            operator_name[GSF_OPERATOR_LENGTH + 1];
    char            *command_line;
    char            *comment;
}
gsfHistory;
```

#### 4.1.9 NAVIGATION ERROR RECORD

Note: As of GSF v1.07, the *gsfNavigationError* record has been replaced by *gsfHVNavigationError*. All newly created files should be written using *gsfHVNavigationError*, instead of *gsfNavigationError*.

```
typedef struct t_gsfNavigationError /* obsolete, as of GSF v1.07 */
{
    struct timespec nav_error_time;
    int             record_id;        /* Containing nav with these errors */
    double          latitude_error;   /* 90% CE in meters */
    double          longitude_error;  /* 90% CE in meters */
}
```



```
gsfNavigationError;
```

```
typedef struct t_gsfHVNavigationError
{
    struct timespec nav_error_time;
    int             record_id;          /* Containing nav with these errors */
    double          horizontal_error;    /* RMS error in meters */
    double          vertical_error;     /* RMS error in meters */
    double          SEP_uncertainty;    /* RMS error in meters */
    char            spare[2];           /* Two bytes reserved for future use */
    char            *position_type;     /* 4 character string code specifying type of
                                         positioning system */
}
gsfHVNavigationError;
```

#### 4.1.10 SWATH BATHYMETRY SUMMARY RECORD

```
typedef struct t_gsfSwathBathySummary
{
    struct timespec start_time;
    struct timespec end_time;
    double          min_latitude;
    double          min_longitude;
    double          max_latitude;
    double          max_longitude;
    double          min_depth;
    double          max_depth;
}
gsfSwathBathySummary;
```

#### 4.1.11 ATTITUDE RECORD

```
typedef struct t_gsfAttitude
```

```

{
    short          num_measurements;    /* number of attitude measurements in this
record */

    struct timespec *attitude_time;    /* seconds and nanoseconds */

    double         *pitch;             /* in degrees */

    double         *roll;             /* in degrees */

    double         *heave;           /* in meters */

    double         *heading;          /* in degrees */

}

gsfAttitude;

```

## 4.2 Supporting Data Structures and Definitions

### 4.2.1 RECORD IDENTIFIER

```

typedef struct t_gsfDataID
{
    int          checksumFlag;    /* boolean */

    int          reserved;       /* up to 9 bits */

    int          recordID;       /* bits 00-11 => data type number */
                                /* bits 12-22 => registry number */

    int          record_number;  /* specifies the nth occurrence of */
                                /* record type specified by recordID */
                                /* relevant only for direct access */
                                /* the record_number counts from 1 */

}

gsfDataID;

```

### 4.2.2 TIME STRUCTURE

```

struct timespec
{
    time_t      tv_sec;

    long        tv_nsec;

```

```
};
```

### 4.2.3 NULL VALUES USED TO REPRESENT MISSING DATA

```
/* Define null values to be used for missing data */  
  
#define GSF_NULL_LATITUDE          91.0  
#define GSF_NULL_LONGITUDE        181.0  
#define GSF_NULL_HEADING          361.0  
#define GSF_NULL_COURSE           361.0  
#define GSF_NULL_SPEED            99.0  
#define GSF_NULL_PITCH            99.0  
#define GSF_NULL_ROLL             99.0  
#define GSF_NULL_HEAVE            99.0  
#define GSF_NULL_DRAFT            0.0  
#define GSF_NULL_DEPTH_CORRECTOR  99.99  
#define GSF_NULL_TIDE_CORRECTOR   99.99  
#define GSF_NULL_SOUND_SPEED_CORRECTION 99.99  
#define GSF_NULL_HORIZONTAL_ERROR -1.00  
#define GSF_NULL_VERTICAL_ERROR  -1.00  
#define GSF_NULL_HEIGHT           9999.99  
#define GSF_NULL_SEP              9999.99  
#define GSF_NULL_SEP_UNCERTAINTY  0.0  
  
  
/* Define null values for the swath bathymetry ping array types. Note that  
 * these zero values do not necessarily indicate a non-valid value. The  
 * beam flags array should be used to determine data validity.  
 */  
  
#define GSF_NULL_DEPTH              0.0  
#define GSF_NULL_ACROSS_TRACK       0.0  
#define GSF_NULL_ALONG_TRACK        0.0  
#define GSF_NULL_TRAVEL_TIME        0.0  
#define GSF_NULL_BEAM_ANGLE         0.0
```

```

#define GSF_NULL_MC_AMPLITUDE      0.0
#define GSF_NULL_MR_AMPLITUDE      0.0
#define GSF_NULL_ECHO_WIDTH        0.0
#define GSF_NULL_QUALITY_FACTOR     0.0
#define GSF_NULL_RECEIVE_HEAVE     0.0
#define GSF_NULL_DEPTH_ERROR       0.0
#define GSF_NULL_ACROSS_TRACK_ERROR 0.0
#define GSF_NULL_ALONG_TRACK_ERROR  0.0
#define GSF_NULL_NAV_POS_ERROR     0.0

```

#### 4.2.4 POSITIONING SYSTEM TYPE CODES

/\* Define a set of macros that may be used to set the position type field \*/

```

#define GSF_POS_TYPE_UNKN  "UNKN"    /* Unknown positioning system type          */
#define GSF_POS_TYPE_GPSU  "GPSU"    /* GPS Position, unknown positioning service */
#define GSF_POS_TYPE_PPSD  "PPSD"    /* Precise positioning service - differential */
#define GSF_POS_TYPE_PPSK  "PPSK"    /* Precise positioning service - kinematic    */
#define GSF_POS_TYPE_PPSS  "PPSS"    /* Precise positioning service - standalone  */
#define GSF_POS_TYPE_PPSG  "PPSG"    /* Precise positioning service - gypsy       */
#define GSF_POS_TYPE_SPSD  "SPSD"    /* Standard positioning service - differential */
#define GSF_POS_TYPE_SPSK  "SPSK"    /* Standard positioning service - kinematic  */
#define GSF_POS_TYPE_SPSS  "SPSS"    /* Standard positioning service - standalone */
#define GSF_POS_TYPE_SPSG  "SPSG"    /* Standard positioning service - gypsy      */
#define GSF_POS_TYPE_GPPP  "GPPP"    /* Post Processing - Precise Point Positioning */
#define GPS_POS_TYPE_GPPK  "GPPK"    /* Post Processing - Post Processed Kinematic */
#define GSF_POS_TYPE_INUA  "INUA"    /* Inertial measurements only, unaided */
#define GSF_POS_TYPE_INVA  "INVA"    /* Inertial measurements with absolute
                                     velocity aiding */
#define GSF_POS_TYPE_INWA  "INWA"    /* Inertial measurements with water-relative
                                     velocity aiding */
#define GSF_POS_TYPE_LBLN  "LBLN"    /* One or more long-baseline acoustic
                                     navigation lines of position */
#define GSF_POS_TYPE_USBL  "USBL"    /* ultra-short baseline acoustic navigation */
#define GSF_POS_TYPE_PIUA  "PIUA"    /* Post-processed inertial measurements only,

```

```
                                unaided */
#define GSF_POS_TYPE_PIVA "PIVA" /* Post-processed Inertial measurements with
                                absolute velocity aiding */
#define GSF_POS_TYPE_PIWA "PIWA" /* Post-processed Inertial measurements with
                                water-relative velocity aiding */
#define GSF_POS_TYPE_PLBL "PLBL" /* Post-processed One or more long-baseline
                                acoustic navigation lines of position */
#define GSF_POS_TYPE_PSBL "PSBL" /* Post-processed ultra-short baseline
                                acoustic navigation */
```