GSFlib,
The Generic Sensor Format
Library

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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 verson 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
25	12 December 2024	Various	Updates for GSF version 03.11

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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.

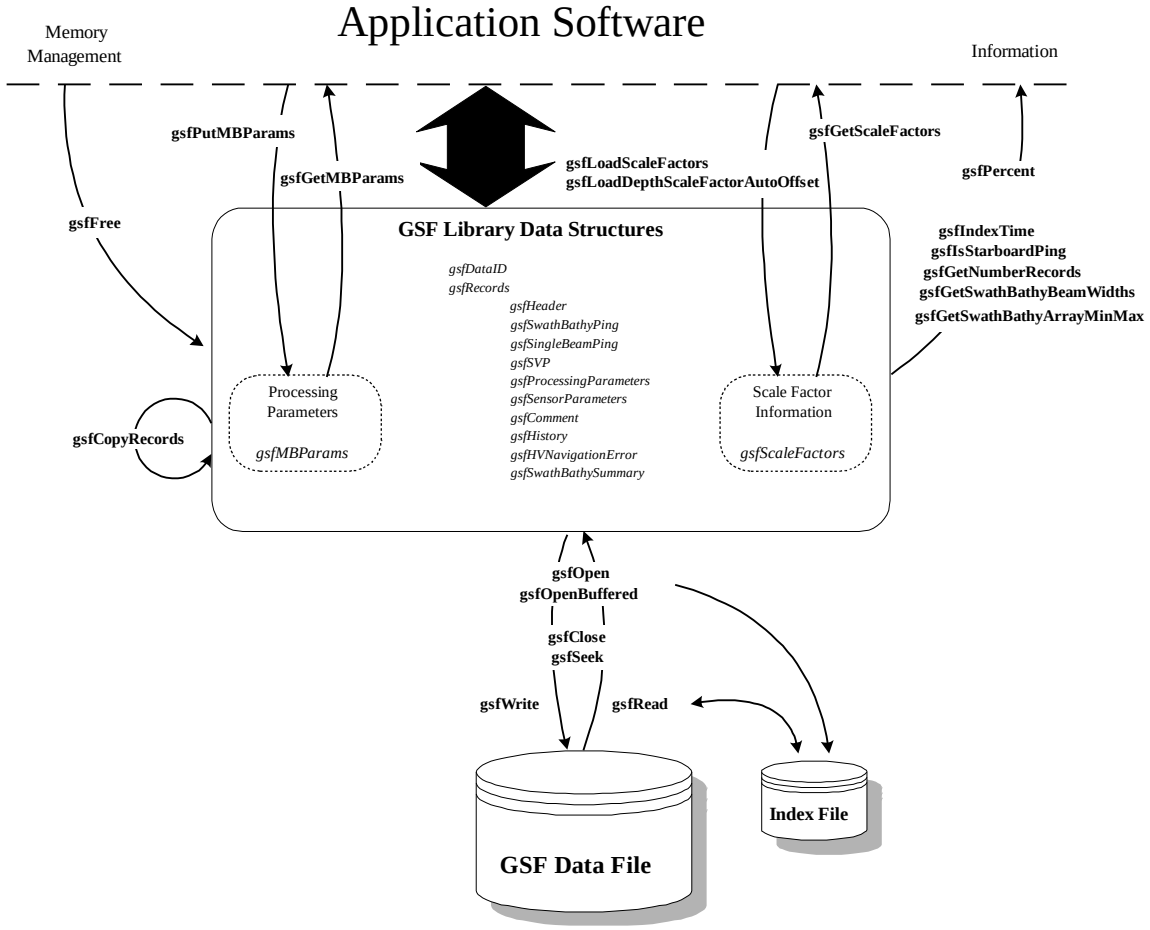

Figure 1-1 GSFLib Functions

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 **gsfRead** and **gsfWrite** API. All pointers to dynamically allocated memory are now maintained by the library.
22 Dec 1995	GSF-v01.02	Added **gsfGetMBParams**, **gsfPutMBParams, gsfIsStarboardPing**, and **gsfGetSwathBathyBeamWidths**. Also added *GSF_APPEND* as a file access mode, and modified *GSF_CREATE* access mode so that files can be updated (read and written).
20 Aug 1996	GSF-v01.03	Added support for single beam echosounders. Added **gsfStringError** 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 *gsfHVNavigationError* that replaces the currently defined navigation error record *gsfNavigationError*. 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 **gsfPrintError** function so that it calls the **gsfStringError** function. **gsfStringError** 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 (*gsfCmpSassSpecific*) specific data structure. Added two new functions **gsfGetSwathBathyArrayMinMax** and **gsfLoadDepthScaleFactorAutoOffset** in support of signed depth. Also added processing in the **gsfGetSwathBathyBeamWidths** function to return the beam width values specified within the EM-3000 series data formats. Increased the *GSF_MAX_PROCESSING_PARAMETERS* macro from sixty-four to one hundred and twenty-eight and the *GSF_MAX_SENSOR_PARAMETERS* macro from thirty-two to one hundred and twenty-eight. Modified **gsfPutMBParameters** 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 gsfIsStarboard 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 gsfLoadDepthScaleFactorAutoOffset 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.
12 December 2024	GSF-v03.11	Fixed bug in beam_angle_forward signage. Fixed bug in start_range_samples not being copied in gsfCopy

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 HPUX 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_indx.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/MSC, 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 as various locations within the file.

2.1.1 FUNCTION: GSFOPEN

Usage:

```
int gsfOpen(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. **gsfOpen** 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 **gsfOpen** 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 gsfOpenBuffered(const char *filename,
                    const int   mode,
                    int        *handle,
                    int         buf_size)
```

Description:

This function attempts to open a GSF data file. If the file exits 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. **gsfOpenBuffered** 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. **gsfOpenBuffered** performs identical processing to **gsfOpen** 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 **gsfOpenBuffered** 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.

`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,
            gsfDataID     *dataID,
            gsfRecords    *rptr,
            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 *gsfDataID* 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 *gsfDataID* structure.

Inputs:

`handle`	the handle to the file as provided by **gsfOpen or gsfOpenBuffered**
`desiredRecord`	the desired record or *GSF_NEXT_RECORD*
`dataID`	a pointer to a *gsfDataID* structure to be populated for the input record.
`rptr`	a pointer to a *gsfRecords* structure to be populated with the data from the input record in internal form.

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

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,
             gsfDataID  *id,
             gsfRecords *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 *gsfDataID* structure. If the file is opened for sequential access (*GSF_CREATE*, or *GSF_UPDATE*) then the `recordID` field of the *gsfDataID* 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 *gsfDataID* 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:

`handle`	the handle for this file as returned by **gsfOpen**
`id`	a pointer to a *gsfDataID* containing the record ID information for the record to write.
`rptr`	a pointer to a *gsfRecords* 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:

`target` a pointer to a *gsfRecords* data structure allocated by the calling application, into which the source data is to be copied.

`source` a pointer to a *gsfRecords* 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:

`rec`	pointer to a *gsfRecords* 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:

p	a pointer to the *gsfMBParams* data structure which contains the parameters in internal form.
rec	a pointer to the *gsfRecords* data structure into which the parameters are to be written in the "KEYWORD=VALUE" form.
handle	the integer handle to the file set by **gsfOpen** or gsfOpenBuffered
numArrays	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:

`rec`	a pointer to the *gsfRecords* data structure from which the parameters in "KEYWORD=VALUE" form are to be read.
`p`	a pointer to the *gsfMBParams* data structure which will be populated.
`numArrays`	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:

`filename`	A fully qualified path to the GSF file.
`sz`	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

GSF_UNRECOGNIZED_FILE

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:

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

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	unsigned short	16	0 to 65535
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:

`sf`	a pointer to the *gsfScaleFactors* structure to be loaded
`subrecordID`	the subrecord id for the beam array data
`c_flag`	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 gsf.h (GSF_FIELD_SIZE_DEFAULT, etc).
`precision`	the precision to which the beam array data are to be stored(a value of 0.1 would indicate decimeter precision for depth)
`offset`	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 **gsfOpen or gsfOpenBuffered**.
`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: GSF_FIELD_SIZE_DEFAULT, GSF_FIELD_SIZE_ONE, GSF_FIELD_SIZE_TWO, or GSF_FIELD_SIZE_FOUR.

`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:

`mb_ping`	a pointer to the *gsfSwathBathyPing* 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:

`ping`	a pointer to the *gsfSwathBathyPing* which contains the depth and tide correction values, and the scale factors data structure.
`subrecordID`	an integer value containing the subrecord ID for the beam array data; this must be either GSF_SWATH_BATHY_SUBRECORD_DEPTH_ARRAY, or GSF_SWATH_BATHY_SUBRECORD_NOMINAL_DEPTH_ARRAY.
`reset`	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.

`min_depth`	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.
`max_depth`	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.
`last_corrector`	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.
`C_flag`	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 gsf.h (GSF_FIELD_SIZE_DEFAULT, etc). See section 2.2.5 on **gsfLoadScaleFactor** for more information.
`precision`	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:

`gp`	Reference position (typically ping position, in degrees).
`offsets`	XYZ offsets from the reference position (in meters).
`heading`	Platform heading (in degrees).
`dist_step`	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:

`gp_from`	Reference position (in degrees).

gp_to	Destination position (in degrees).
heading	Platform heading (in degrees).
dist_step	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:

ping_flags	The contents of the ping_flags field.
usflag	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 gsfSetPingStatus(ping_flags, usflag)
```

Description:

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

Inputs:

`ping_flags`	The original contents of the `ping_flags` field.
`usflag`	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 gsfClearPingStatus(ping_flags, usflag)
```

Description:

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

Inputs:

`ping_flags`	The original contents of the `ping_flags` 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: GSFPRINTERROR

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:

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

`sec`	Seconds since the beginning of the epoch (as defined in the GSF processing parameter record.)
`nsec`	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:

`handle`	gsf file handle assigned by **gsfOpen** or **gsfOpenBuffered**

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:

`handle`	the handle to the file as provided by **gsfOpen or gsfOpenBuffered**
`desiredRecord`	the desired record or *GSF_NEXT_RECORD*

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:

`data`	The address of a *gsfRecords* data structure maintained by the caller which contains a populated *gsfSwathBathyPing* substructure.
`fore_aft`	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.
`athwartship`	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:

`ping`	The address of a *gsfSwathBathyPing* data structure that contains the depth and tide correction values, as well as the scale factors data structure.
`subrecordID`	The subrecord ID for the beam array data.
`min_value`	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.
`max_value`	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 fist 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 *gsfSwathBathyPing* 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 **gsfOpen** or **gsfOpenBuffered**
`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 **gsfOpen** or **gsfOpenBuffered**
`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 **gsfOpen** or **gsfOpenBuffered**
`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 gsfFileContainsMBAmplitude(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 **gsfOpen** or **gsfOpenBuffered**
`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 gsfFileContainsMBImagery(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 **gsfOpen** or **gsfOpenBuffered**
`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:

`handle`	GSF file handle assigned by **gsfOpen** or **gsfOpenBuffered**
`rec`	The address of a *gsfRecords* data structure maintained by the caller which contains a populated *gsfSwathBathyPing* substructure obtained from recent call to gsfRead.
`azimuth_change`	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 gsfIsNewSurveyLine when a new line is detected. The application program should allocate this double such that it's memory persists for all calls to gsfIsNewSurveyLine. 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 gsfInitializeMBParams (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 gsfError	Value	Reason for error
GSF_ATTITUDE_RECORD_DECODE_FAILED	-50	"GSF Error decoding attitude record"
GSF_ATTITUDE_RECORD_ENCODE_FAILED	-49	
GSF_BAD_ACCESS_MODE	-3	"GSF Error illegal access mode"
GSF_BAD_FILE_HANDLE	-24	"GSF Error bad file handle"
GSF_BAD_SEEK_OPTION	-15	"GSF Error unrecognized file seek option"
GSF_CANNOT_REPRESENT_PRECISION	-22	"GSF Error illegal scale factor multiplier specified"
GSF_CHECKSUM_FAILURE	-8	"GSF Error data checksum failure"
GSF_COMMENT_RECORD_DECODE_FAILED	-30	"GSF Error decoding comment record"
GSF_COMMENT_RECORD_ENCODE_FAILED	-30	
GSF_CORRUPT_INDEX_FILE_ERROR	-37	"GSF Error index file is corrupted, delete index file"
GSF_FILE_CLOSE_ERROR	-9	"GSF Error closing gsf file"
GSF_FILE_SEEK_ERROR	-16	"GSF Error file seek failed"
GSF_FILE_TELL_ERROR	-35	"GSF Error file tell failed"
GSF_FLUSH_ERROR	-34	"GSF Error flushing data buffers(s)"
GSF_FOPEN_ERROR	-1	"GSF Unable to open requested file"
GSF_HEADER_RECORD_DECODE_FAILED	-25	"GSF Error decoding header record"
GSF_HEADER_RECORD_ENCODE_FAILED	-25	
GSF_HISTORY_RECORD_DECODE_FAILED	-31	"GSF Error decoding history record"

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

GSF_SCALE_INDEX_CALLOC_ERROR	-38	"GSF Error calloc of scale factor index memory failed"
GSF_SENSOR_PARAM_RECORD_DECODE_FAILED	-29	"GSF Error decoding sensor parameters record"
GSF_SENSOR_PARAM_RECORD_ENCODE_FAILED	-29	
GSF_SETVBUF_ERROR	-33	"GSF Error setting internal file buffering"
GSF_SINGLE_BEAM_ENCODE_FAILED	-46	"GSF Error single beam encode failure"
GSF_STREAM_DECODE_FAILURE *****Note: error code is not used**	-14	"GSF Error stream decode failure"
GSF_SUMMARY_RECORD_DECODE_FAILED	-40	"GSF Error decoding summary record"
GSF_SUMMARY_RECORD_ENCODE_FAILED	-41	"GSF Error encoding summary record"
GSF_SVP_RECORD_DECODE_FAILED	-27	"GSF Error decoding SVP record"
GSF_SVP_RECORD_ENCODE_FAILED	-27	
GSF_TOO_MANY_ARRAY_SUBRECORDS	-10	"GSF Error too many array subrecords"
GSF_TOO_MANY_OPEN_FILES	-11	"GSF Error too many open files"
GSF_UNRECOGNIZED_ARRAY_SUBRECORD_ID	-19	"GSF Error unrecognized array subrecord id "
GSF_UNRECOGNIZED_DATA_RECORD	-18	"GSF Error unrecognized data record id"
GSF_UNRECOGNIZED_FILE	-2	"GSF Error unrecognized file"
GSF_UNRECOGNIZED_RECORD_ID	-13	"GSF Error unrecognized record id"
GSF_UNRECOGNIZED_SENSOR_ID	-17	"GSF Error unrecognized sensor specific subrecord id"
GSF_UNRECOGNIZED_SUBRECORD_ID	-20	"GSF Error unrecognized subrecord id"
GSF_WRITE_ERROR	-5	"GSF Error writing output data"
GSF_QUALITY_FLAGS_DECODE__ERROR	-53	"GSF error decoding quality flags record"
Unrecognized error condition		"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
 *    rolll         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           tvg;
    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         tvg_spreading;        /* tvg spreading coefficient * 4 */
    int         tvg_absorption;       /* tvg 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)elocimiter, (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 frequecy - 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_bandwdth;      /* 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-Chebychhev,
                                                           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-Chebychev, 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_bandwdth;       /* 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-Chebychhev,
                                                              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-Chebychev, 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 compenstation 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             tvg_spreading;          /* tvg spreading coefficient * 4 */

    int             tvg_absorption;         /* tvg 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/Azimauth - Microfix */
#define GSF_SB_MPP_SOURCE_RANGE_TRIS    0x07 /* Range/Azimauth - Trisponder */
#define GSF_SB_MPP_SOURCE_RANGE_OTHER   0x08 /* Range/Azimauth - 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 im 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           tvg_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 coeffieceint 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_gsfEMPUStatus   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_gsfEMPUStatus 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 dada 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 converage 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 soudings */

    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 GSF_SWATH_BATHY_SUBRECORD_EM302_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_EM122_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_EM2040_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_ME70BO_SPECIFIC	gsfEM4Specific
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 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	gsfEM3RawSpecific
GSF_SWATH_BATHY_SUBRECORD_DELTA_T_SPECIFIC	gsfDeltaTSpecific
GSF_SWATH_BATHY_SUBRECORD_R2SONIC_2020_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_R2SONIC_2022_SPECIFIC GSF_SWATH_BATHY_SUBRECORD_R2SONIC_2024_SPECIFIC	gsfR2SonicSpecific
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 coeffiecient 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_tvg_ramp;      /* start range (in samples) of TVG ramp if not
                                            enough dynamic range 0 means not used
*/
    int             stop_tvg_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          tvg_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    tvg_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 */
                                 /* relavent 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 */
```