

QPE Pilot Acoustic (TL) results QPE '09 Acoustic Adaptive Sampling Plans

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Acoustic Runs
3 days (of 5 planned)

Sept. 6
Shallow water (110m)
Single OMAS - Linear

Sept. 8
Shallow water (120m)
Single OMAS - L pattern
Lost signal in deeper water

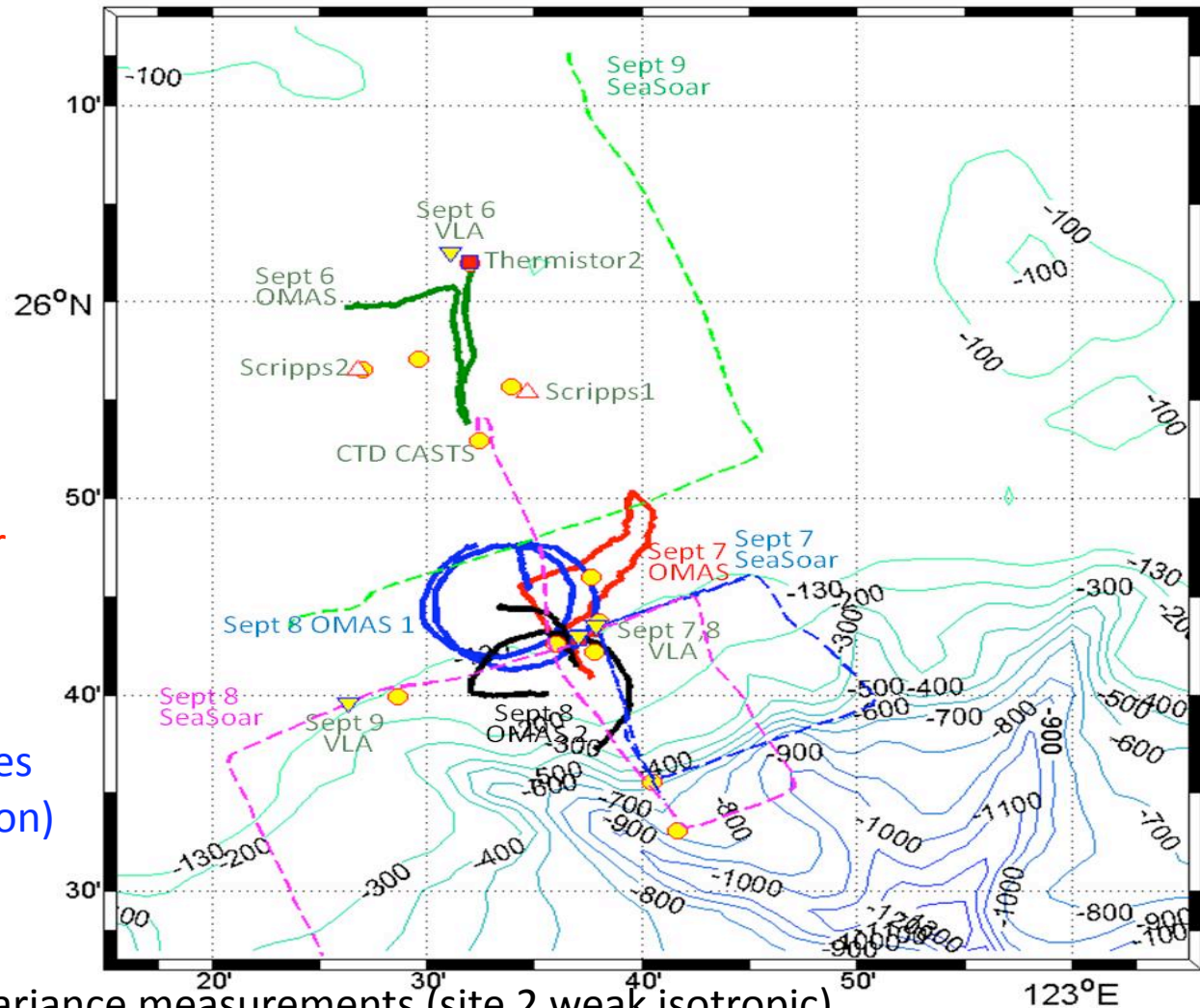
Sept. 9
Two circular OMAS
TL measured for both circles
Coherence Studies (Emerson)
Loss of signal off of shelf

Acoustic Pilot Results:

- Isotropy/horizontal invariance measurements (site 2 weak isotropic)
- Established baseline model from data (site 1/2)
- Significant bathymetric effects on TL

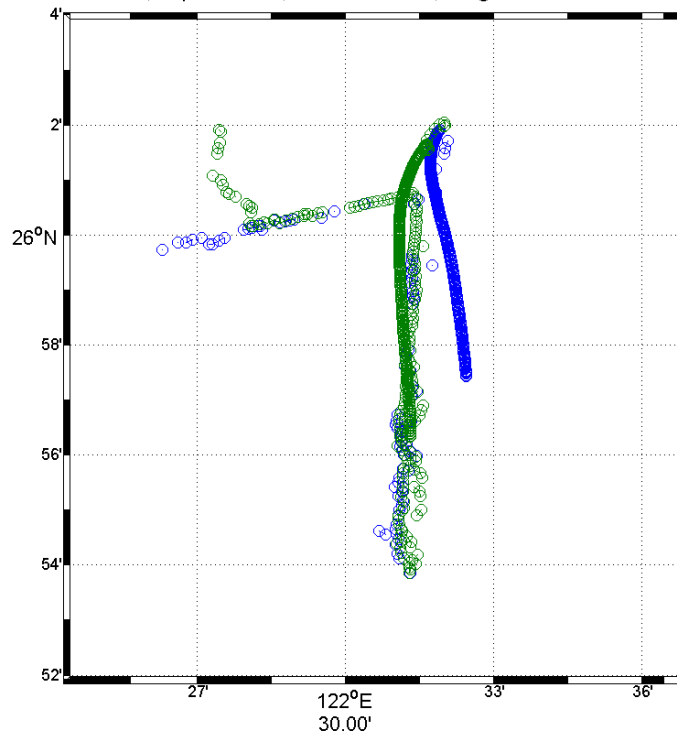
Successfully Demonstrated:

- Night Ops/Deployment from NTU-Vessel

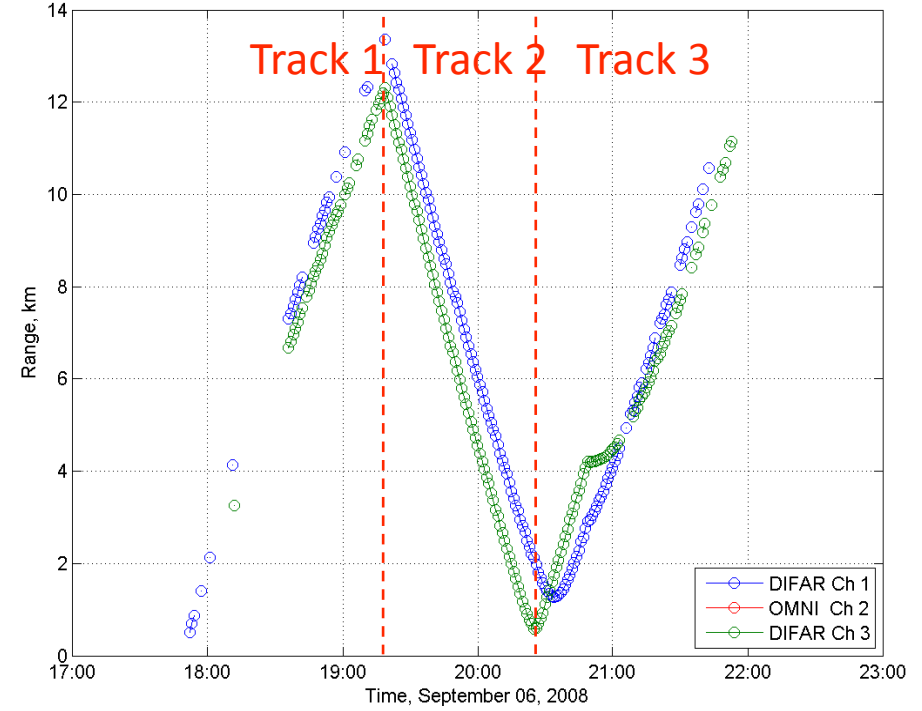


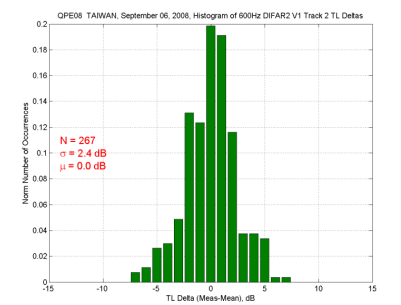
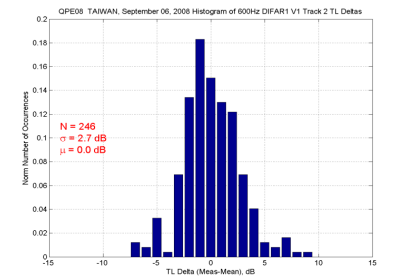
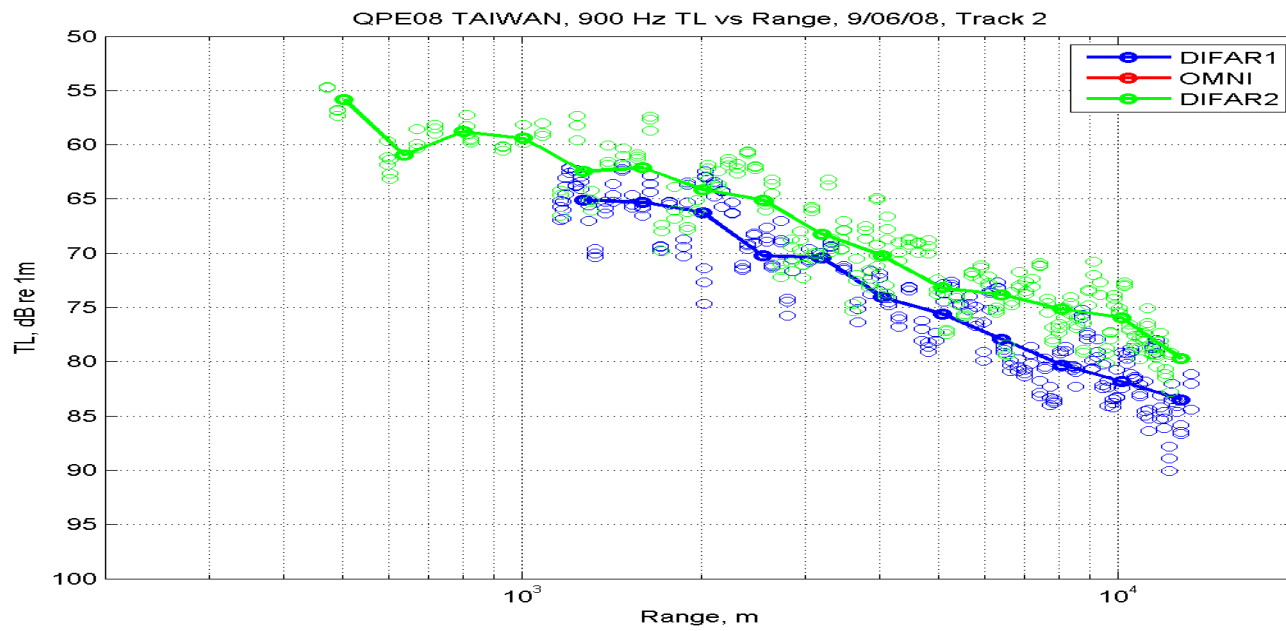
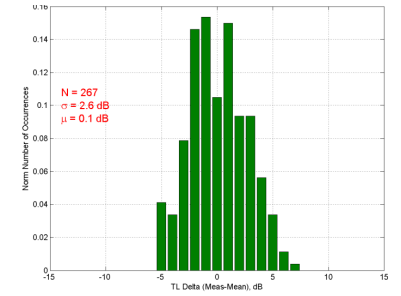
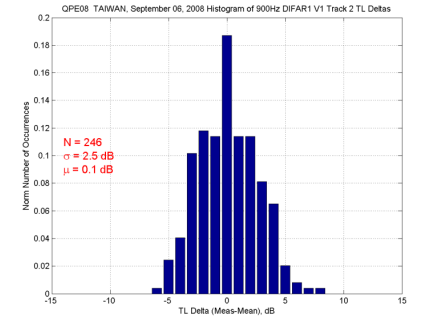
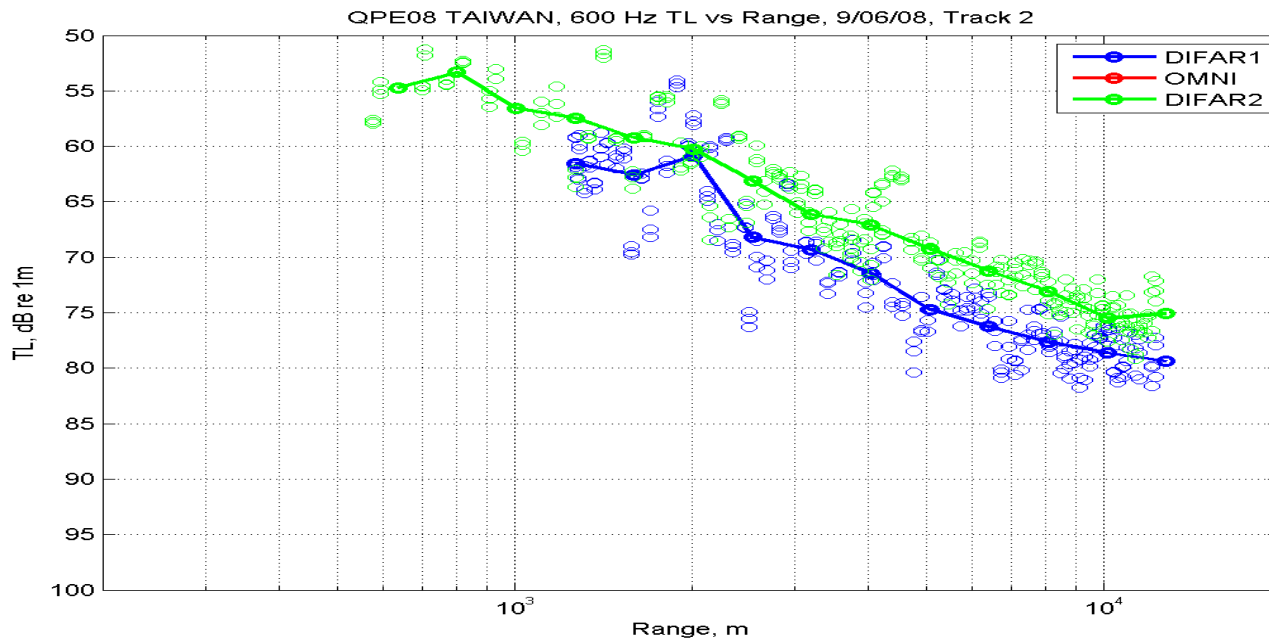
~ Range Independent TL Run
QPE08 TAIWAN, September 6,
OMAS # 15304 , ds=90ft, dr = 90ft

QPE08 TAIWAN, September 06, 2008 Smoothed, Triangulated Drift Corrected



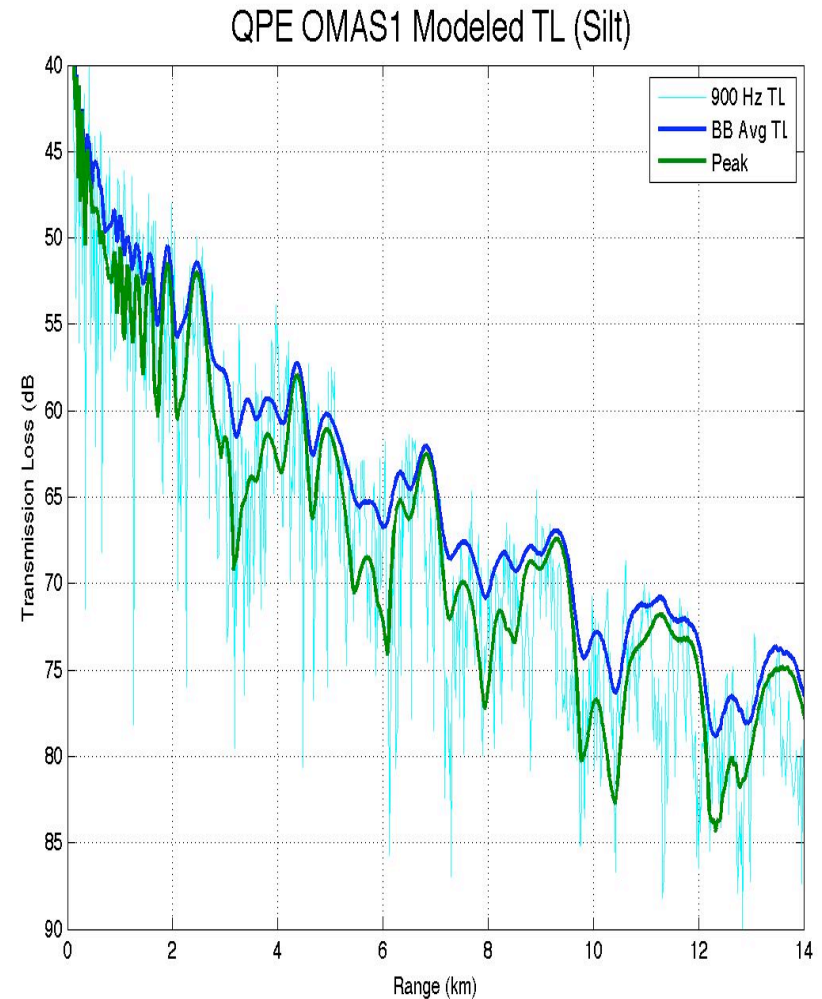
QPE08 TAIWAN, September 06, 2008 Smoothed Range vs Time



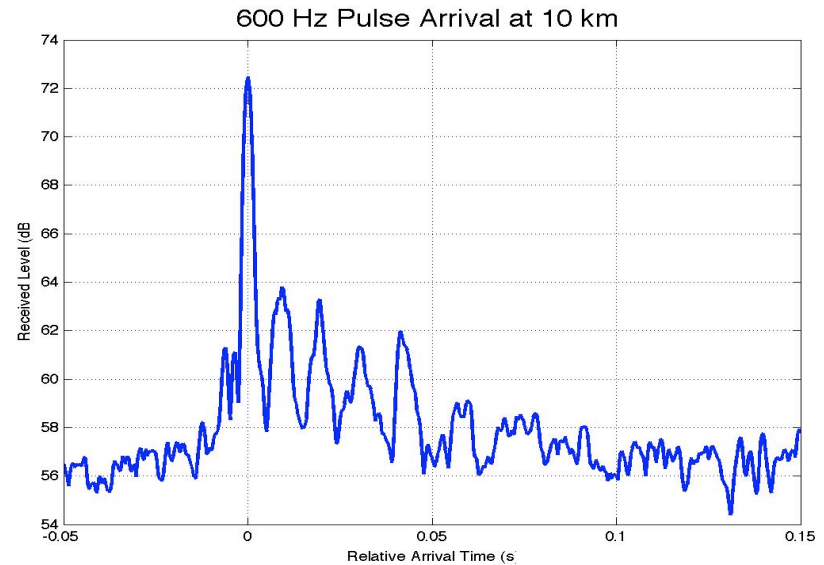
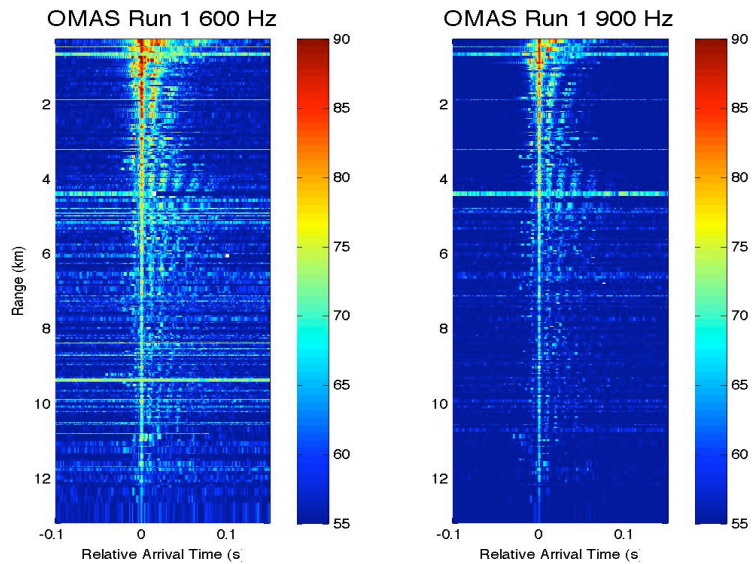
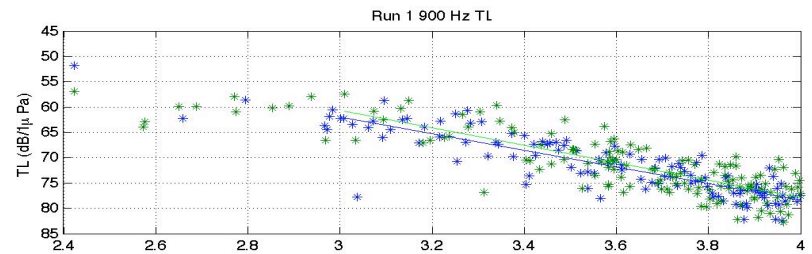
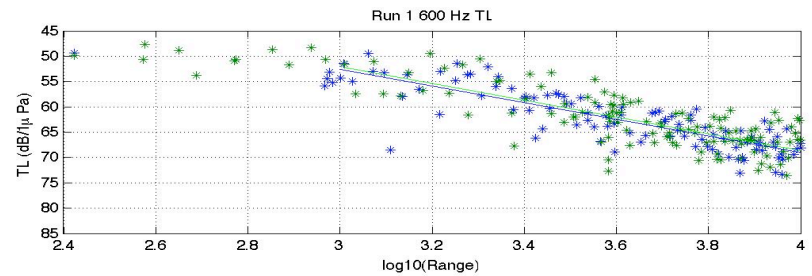
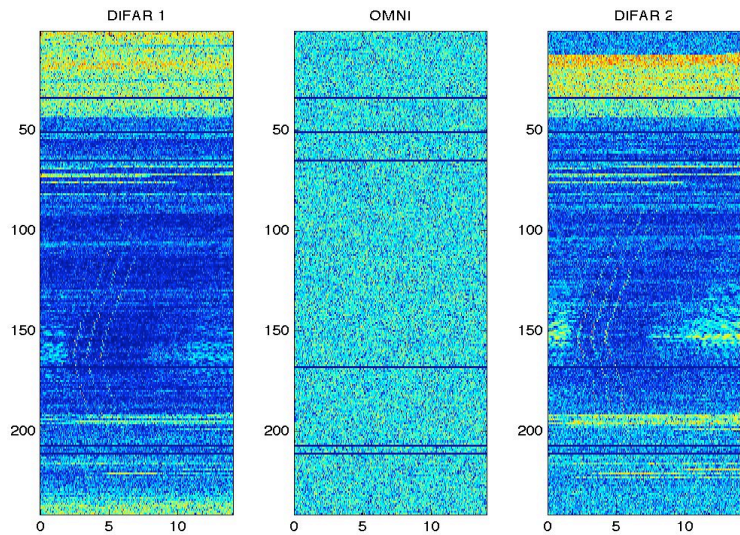


Model-Data Comparisons

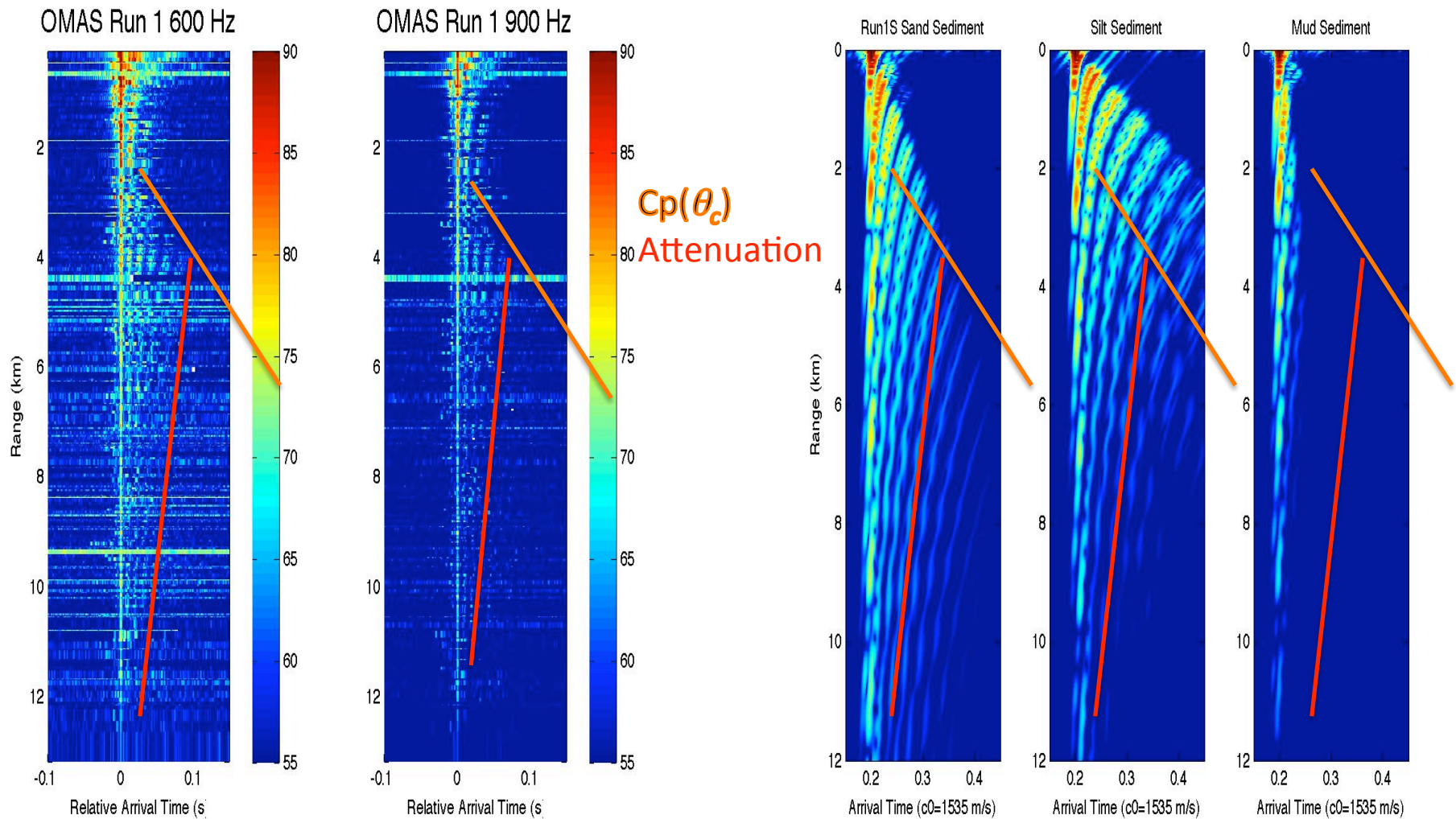
- Need to compare apples-to-apples
 - In order to increase SNR OMAS system transmits LFM and uses peak of the matched filter output as a proxy for TL
- In order to compare, we compute the BB PE field, FFT and pick the take the peak.



OMAS Broadband Measurements



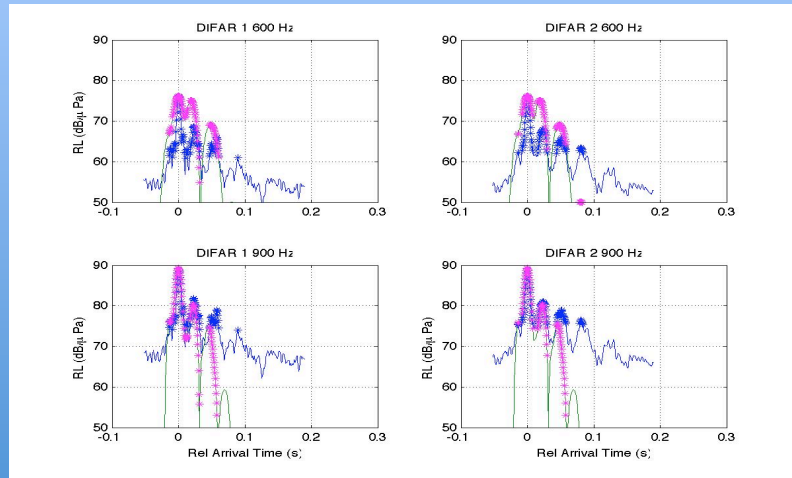
BB Signal vs. Range



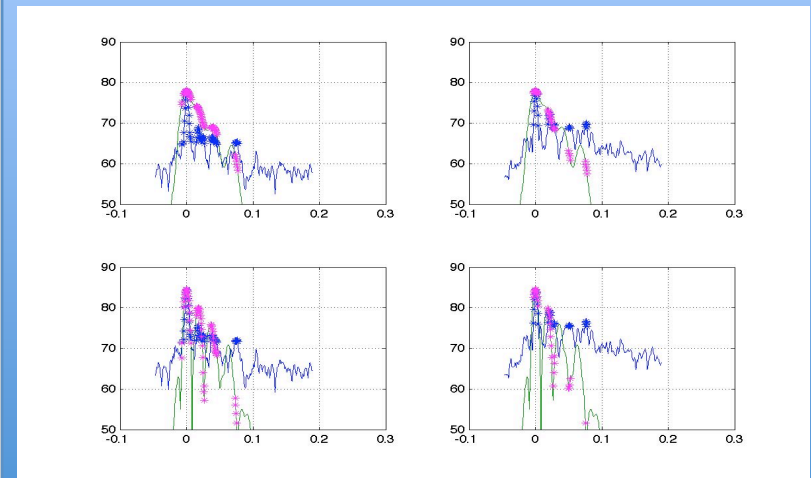
Pilot Data-Model Arrival Pattern Comparisons (*Normalized to peak*)

Using 1562 m/s 0.25 dB/ λ 1.8 g/cc

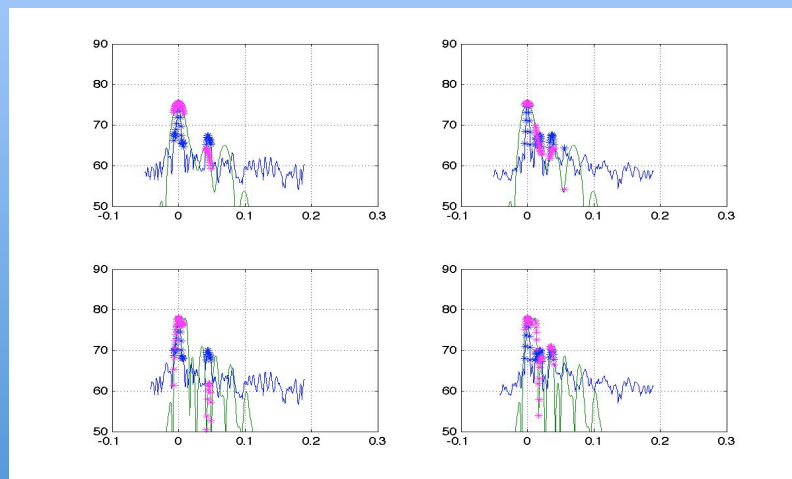
R = 4 km



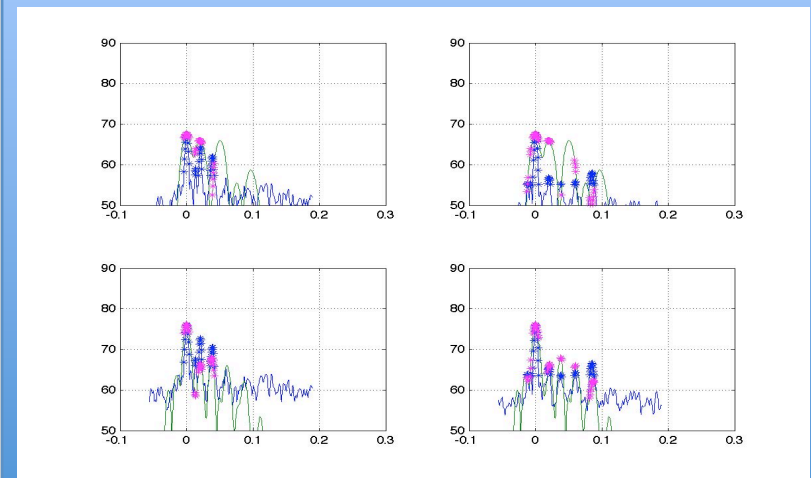
R = 5 km



R = 8 km

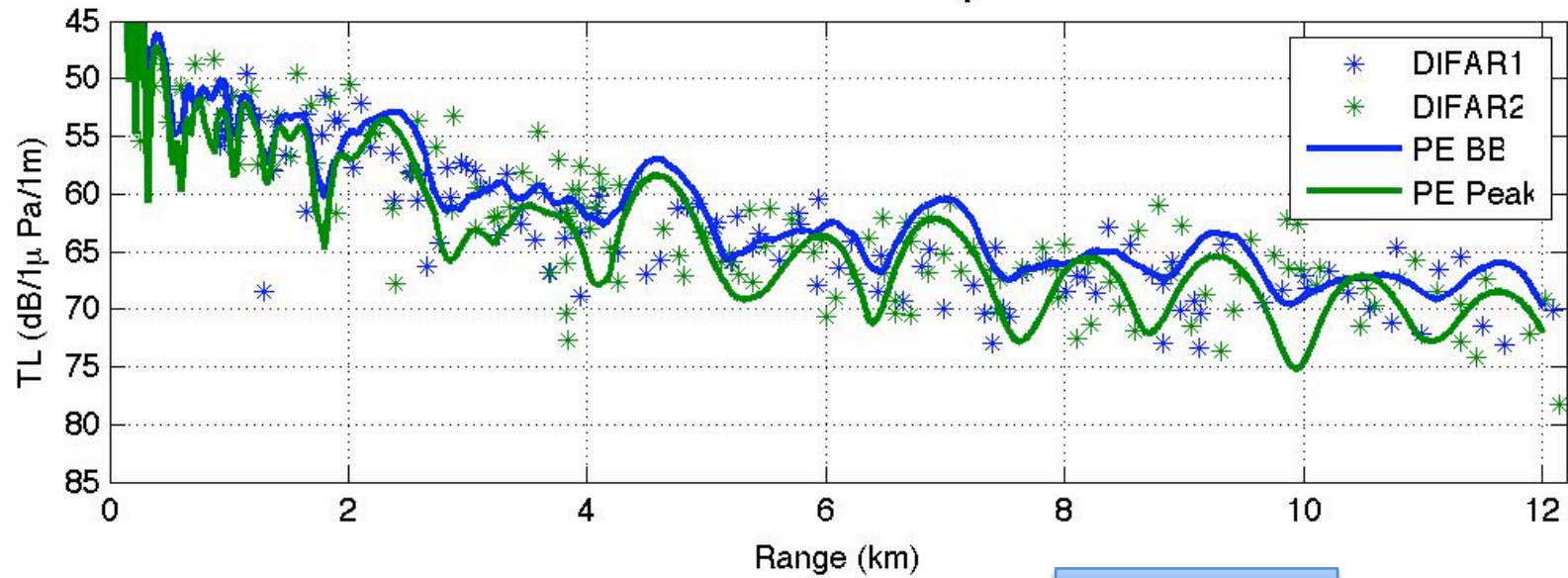


R = 10 km

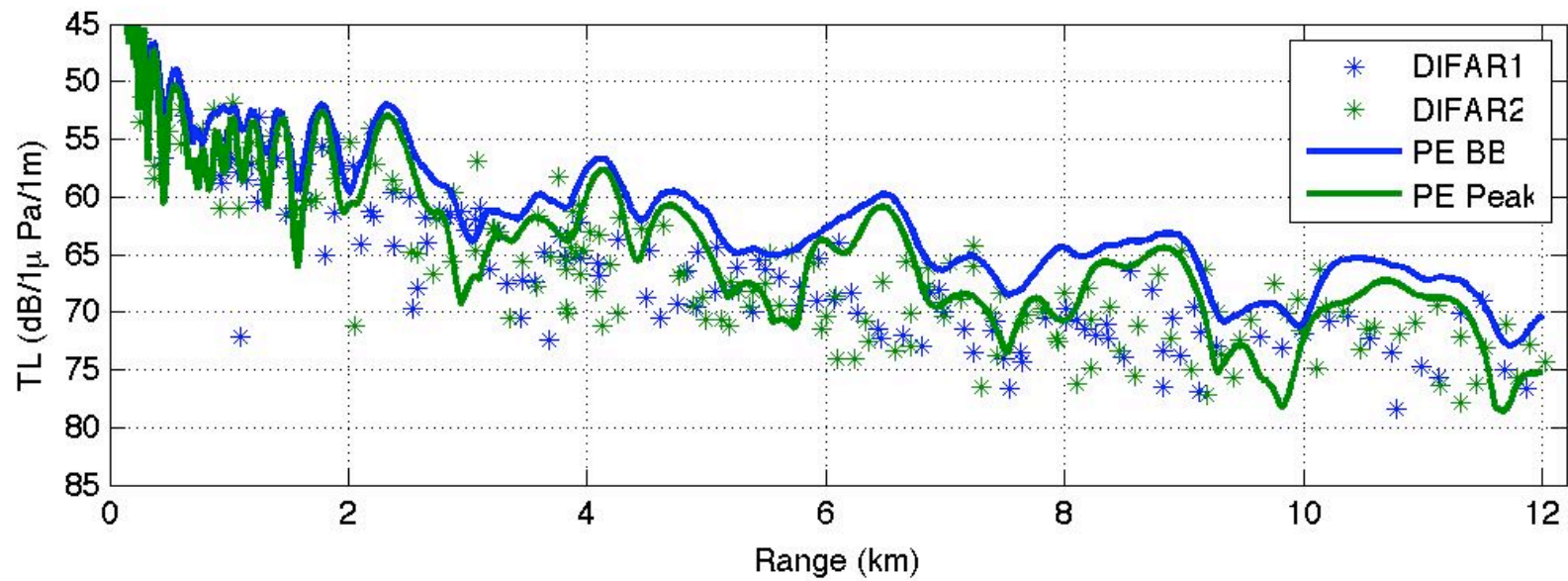


Model-Data TL Comparison

Run 1 600Hz TL alpha=0.2



Run 1 900Hz TL



QPE Pilot Acoustic Conclusions

- OMAS was successfully deployed (5 times) during night ops from RV-2
- Vessel noise does impact short range recordings
- Bathymetry (near shelf-break) strongly affects TL and must be accounted for in geometry planning
- OMAS MF-output can be used to determine signal evolution vs. range
- Signal waveform can be used to rapidly estimate a geo-acoustic Inversion
- DIFAR calibration issue needs to be resolved with local source

Objectives for 09 Test

- Primary Goal: Develop an integrated package for collecting and assimilating acoustic/ambient noise/oceanographic data to reduce acoustic uncertainty
- Apply near-real time (NRT) MF geo-acoustic inversion to signals
- Using updated geo-acoustics perform acoustic sensitivity computation
- Analyze ambient noise to improve SNR prediction and exploitation
- Generate NRT acoustic adaptive sampling runs for reducing oceanographic variability

Acoustic Adaptive Sampling

- Integrate acoustic signal processing (signal and noise) with dynamic ocean forecast (MIT/SIO)
- Integrate updated geo-acoustics (from pilot/in-situ measurements)
- Assimilate ambient noise measurements (compare with predictions)
- Generate real-time acoustic sensitivity (uncertainty) and coverage maps
- Generate optimal adaptive sampling runs to both reduce uncertainty and optimize SNR

Acoustic AS Priorities for QPE'09

- At most 2 sites (personal preference: 1 and 4)
- Prefer Linear Tracks (in addition to circular)
- Return to previous sites after sufficient collection and assimilation of data (+3 days?)
- Transmit subset of acoustic data to shore
 - TL vs. range
 - MF evolution vs. range
 - Ambient noise omni statistics (Directionality?)
- Perform a set of “adaptive sampling” runs for reduction and exploitation of uncertainty.