

MARPORT | PRO

**CATCH PRO
SENSORS**

2024

USER MANUAL



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Legal

History

V1	09/27/24	First release
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Copyright

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Disclaimer

Marport endeavors to ensure that all information in this document is correct and fairly stated, but does not accept liability for any errors or omissions.

The present user guide is applicable for the following versions:

- Mosa2: 02.13.x
- Scala2: 02.14.x

If you use other versions, the visual interface and options may vary.

Introduction and Presentation

Get a basic knowledge of the sensor.

Introduction

The **Catch Pro** and **Catch Explorer Pro** are part of Marport's latest generation of sensors, featuring significant upgrades from earlier models. These enhancements include compatibility with the latest Mosa2 and Scala2 software features, with the Dock smart charger, and higher-definition echogram images.

Marport's catch sensors tell you when your trawl starts to fill. Placed on the top of the trawl codend, they monitor the amount of catch that you have and warn you when the trawl is full. You can even use them to determine a precise amount of fish inside the trawl net. This way, you can monitor the contents of the codend as you are fishing, avoid problems of overfilling and increase fish survival rate inside the trawl net. It is recommended to install several sensors along the trawl to better follow the filling processes.


There are two types of catch sensors:

- **Catch Pro:** gives you the catch status of the trawl (empty or full), along with depth, water temperature and pitch and roll information. Catch sensors can emit on a single frequency of 40 kHz (Marport, Scanmar) or 70 kHz (Simrad, Wesmar), or on a dual frequency (40 kHz/70 kHz).
- **Catch Explorer Pro:** gives you the catch status of the trawl, with depth, water temperature and pitch and roll information. In addition, it provides an echogram image of the volume of catch inside the codend.

They are compatible with Marport Dock product, with which you can easily charge, monitor, configure and update the connected sensors (up to 4).



Safety Guidelines

 **Important:** To ensure proper and safe use of this equipment, carefully read and follow the instructions in this manual.


Basic good practices

When using the product, be careful: strong impacts can cause damage to the electronic components inside.


Never place the product in a hazardous and/or flammable atmosphere.

Product installation and use

Install and use this product in accordance with this user manual. Incorrect use of the product may cause damage to the components or void the warranty.

 **Notice:** Do not open the sensor bottle. Only qualified Marport technicians can do maintenance and repairs on internal components of the sensors.

Precautions

 **CAUTION:** In case of water ingress in the product, do not charge it: battery may vent or rupture, causing product or physical damage.

Applications

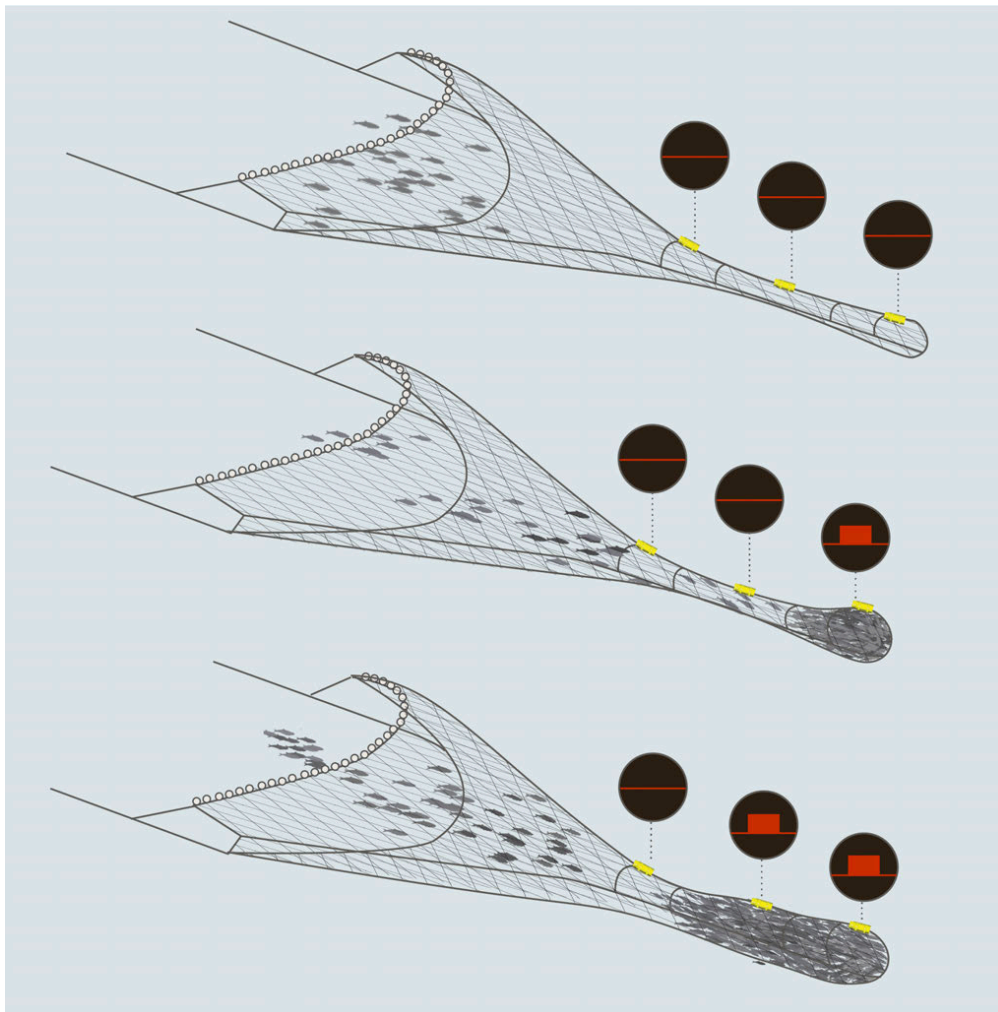
Here are some examples of data received from Catch Explorer and Catch sensors displayed in Scala2.

Catch Control System Installation

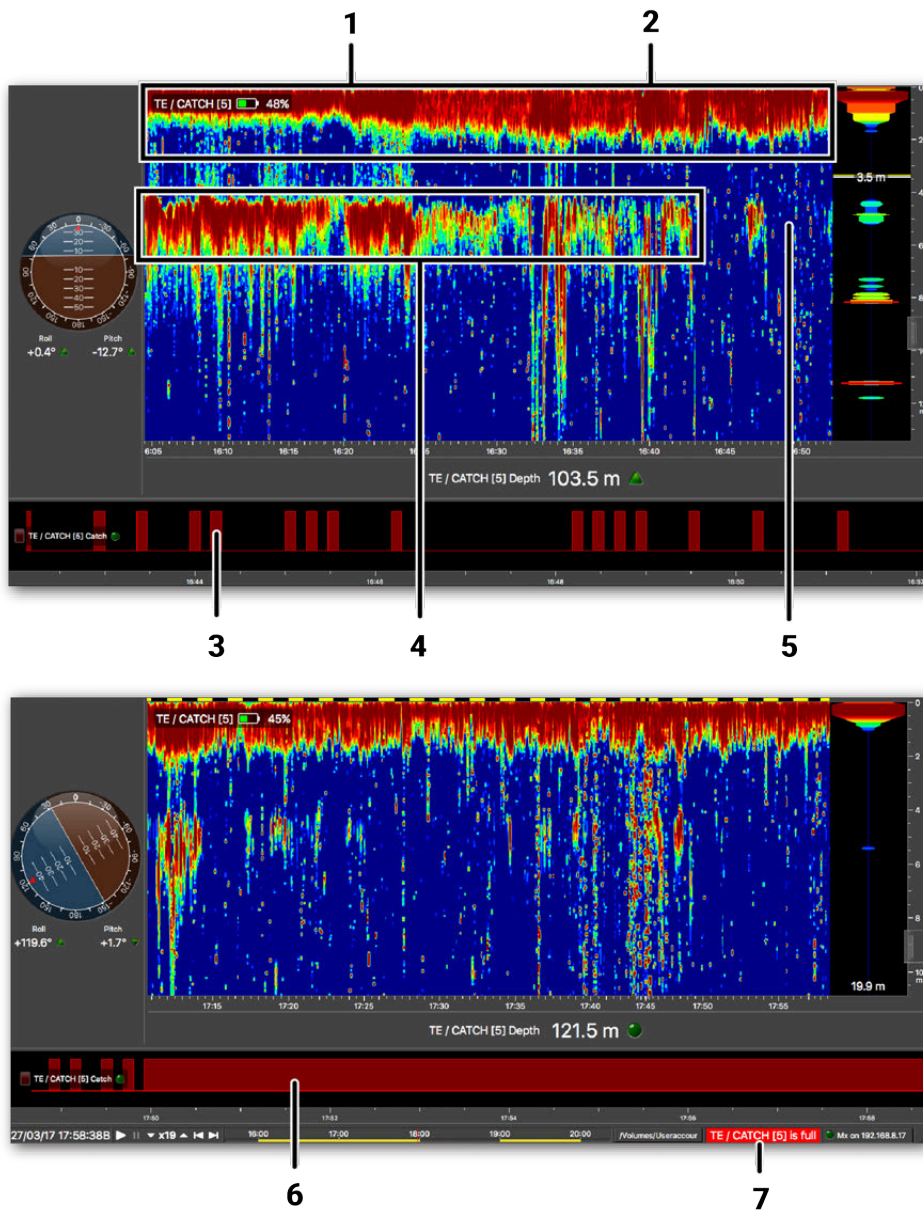
You can install several sensors on the codend to better follow the filling processes. It is very useful to determine the amount of fish inside the trawl net: you can prevent damage to fish and increase the security of crew and vessel.

For example, you can install three sensors on the codend. They will trigger one by one, according to the amount of fish inside the codend. After a few tows, you can estimate the

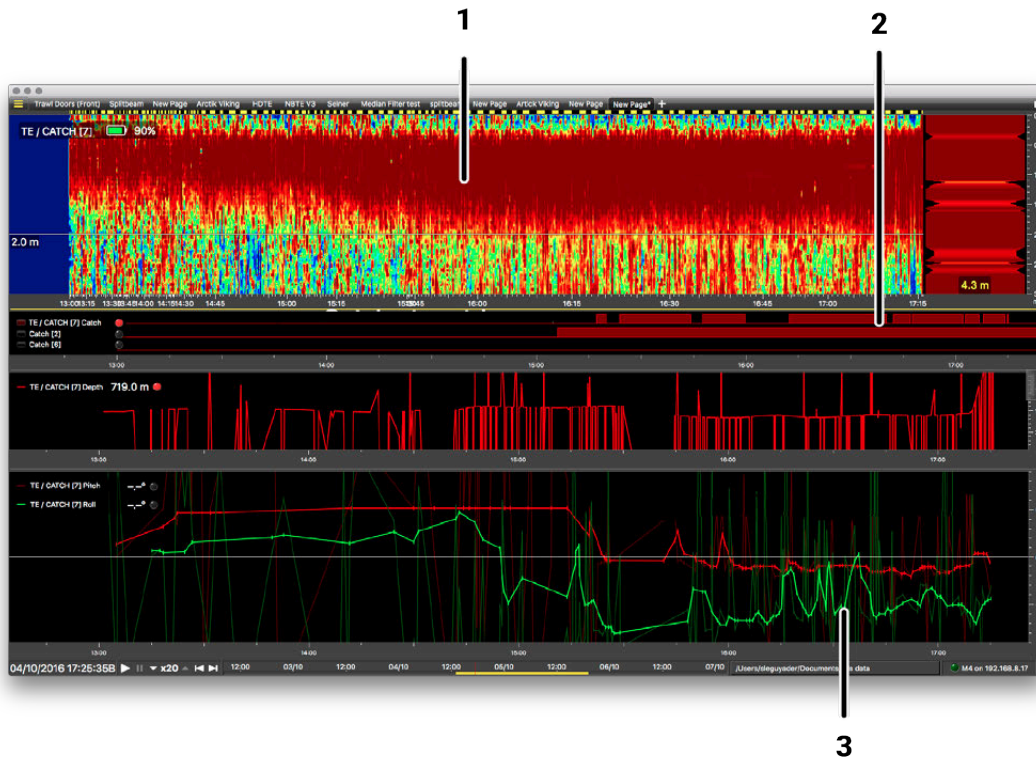
amount of tonnage of fish that you have depending on whether one, two or three sensors display a full status.



Catch Explorer display



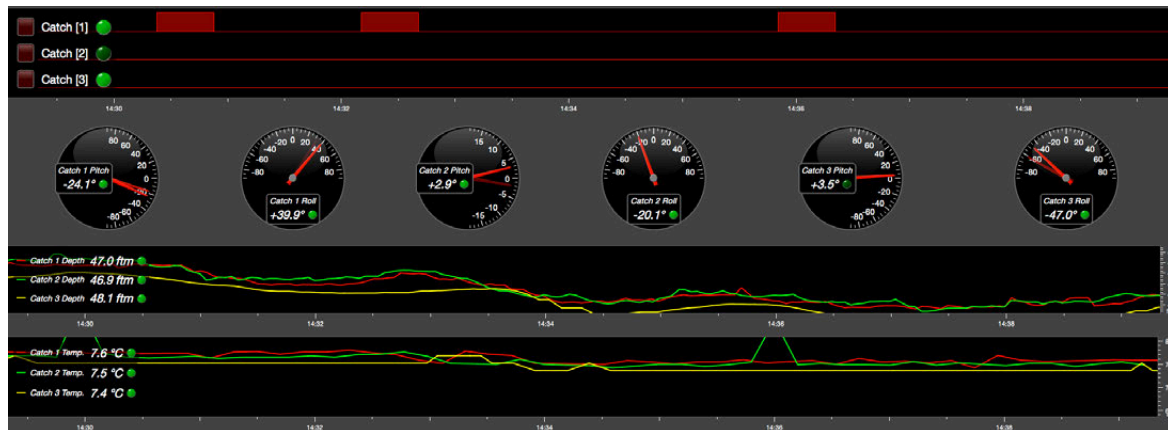
1. Codend
2. Echogram gets denser as the codend fills up and expand.
3. Codend is filling up.
4. Sea bottom
5. Bottom disappears because fish block the signal.
6. Codend is full.
7. Alerts that Catch is full.



1. High strength echogram level gets thicker with fish in the codend.
2. Catch pull cords trigger.
3. Pitch and roll begin to stabilize.

Catch sensors display

Examples of 3 catch sensors with depth, pitch and roll.



Description

System Compatibility

The Catch Pro sensors are compatible with the following versions of Marport's software and equipment.

Mosa2	02.13.03 or later
Scala2	02.14.00 or later
Mx receiver firmware	08.06.00 or later
Dock	01.02.00 or later

Technical Specifications

Catch Sensor

Uplink frequency	30 to 60 kHz
Range to vessel	up to 2500 m ¹
Depth range	up to 1800 m
Data update rate	Catch full: 20 sec. - Catch empty: 30 sec. - Depth: 3-8 sec. - Temp: 3-16 sec. - Pitch & roll: 5-14 sec.
Pitch angle	±90°
Roll angle	±90° (±180° for catch twister)
Pitch & roll accuracy	±0.1°
Depth resolution	0.1 m with 0.1% accuracy
Temp measurement range	-5° C to +25° C
Temp accuracy	±0.1° C
Typical battery life	Up to 740 hours ²
Charging time	6-8 hours ³
Battery type	Lithium-Ion
Weight in air	5 kg

Weight in water	0.9 kg
Warranty	2 years (Sensor & Battery) ⁴

Catch Explorer

Uplink frequency	30 to 60 kHz
Range to vessel	up to 2500 m ¹
Sounder broadband frequency	360 kHz
Sounder range	5 to 160 m
Data update rate	Depth, catch: 4 sec. - temp, pitch, roll, battery: 17 sec.
Echogram update rate	Up to 3 images/sec.
Pitch angle	±90°
Roll angle	±180°
Pitch & roll accuracy	±0.1°
Depth resolution	0.1 m with 0.1% accuracy
Temp measurement range	-5° C to +25° C
Temp accuracy	±0.1° C
Typical battery life	Up to 19 hours ²
Charging time	6-8 hours ³
Battery type	Lithium-Ion
Weight in air (with housing)	5 kg
Weight in water (with housing)	0.9 kg
Warranty	2 years (Sensor & Battery) ⁴

1. Reference only, depends on functions enabled. / 2. Depends on sensor uplink power and options. / 3. Based on average charging time. / 4. Marport Standard Marine Limited Warranty

Catch Explorer Beamwidths

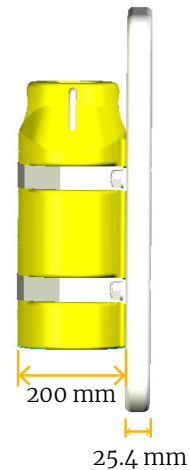
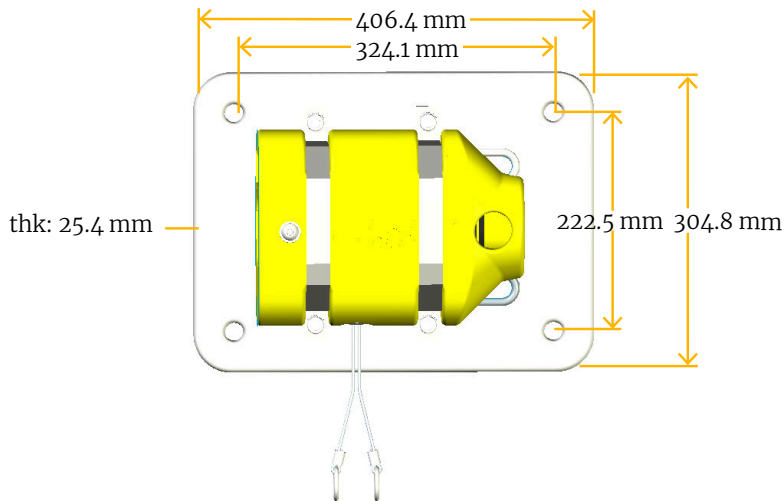
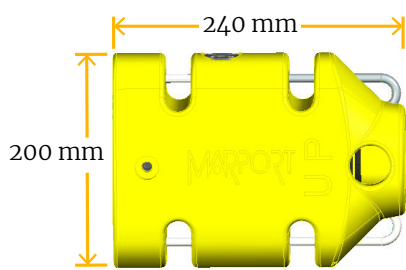
Beamwidths for Uplink pings

Beamwidth	@ 35 kHz	@ 50 kHz	@ 60 kHz
-3dB	46°	40°	30°

Beamwidths for Down pings

@ 360 kHz	
-3dB	13°

Dimensions



Firmware and Features

This section describes the firmware and features that must be configured on MASP to set up the sensor.

To be operational, the sensor needs to be configured with two files:

- a firmware file (*.A2F): it is the firmware of the sensor,
- an application file (*.A2A): it defines the sensor features and options.

These files are generated via MASP.

Firmware

The latest version of the firmware is available for download on MASP.

Compatibility: F450-02.03.01 and after

Features and Options

The features and options are configurable according to the type of hardware and customer's choices.

Catch Explorer

Features	<ul style="list-style-type: none"> • Product name: manually entered. • Application: Catch Explorer • Body: Small • Battery capacity (not configurable): 1-pack
Sounding Options	<ul style="list-style-type: none"> • Down (always activated) • Down2
Misc. options	<ul style="list-style-type: none"> • Memory Card Log: records a log of the sensor activity. This option is useful for troubleshooting support.
Measures	<ul style="list-style-type: none"> • Battery (always activated) • Catch (always activated) • Depth • Temperature • Pitch • Roll • Height

Catch sensor



Note: Compatible with Marport and Scanmar systems. Sensors emit at a frequency around 40kHz. Add Catch70 and/or CatchPI in **Misc. options** to make it compatible with other sensor manufacturers (see tables below).

Features	<ul style="list-style-type: none">• Product name: manually entered.• Application: Catch Sensor• Body: Small• Battery capacity (not configurable): 1-pack
Misc. options	Select to add compatibility with other catch sensor manufacturers. <ul style="list-style-type: none">• Catch70• CatchPI
Measures	<ul style="list-style-type: none">• Battery (always activated)• Catch (always activated)• Depth• Temperature• Pitch• Roll

Catch PI



Note: Compatible with Simrad PI. Add Catch70 in **Misc. options** to make it also compatible with Wesmar systems.

Features	<ul style="list-style-type: none">• Product name: manually entered.• Application: CatchPI• Body: Small• Battery capacity (not configurable): 1-pack
Misc. options	Select to add compatibility with other catch sensor manufacturers. <ul style="list-style-type: none">• Catch70
Measures	<ul style="list-style-type: none">• Catch (always activated)• Depth• Temperature

Catch 70

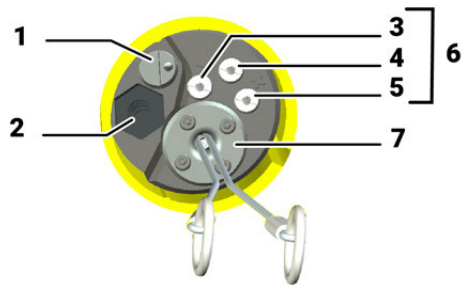


Note: Compatible with Simrad, Wesmar and Furuno systems.

Features	<ul style="list-style-type: none">• Product name: manually entered.• Application: Catch70• Body: Small• Battery capacity (not configurable): 1-pack
Measures	<ul style="list-style-type: none">• Catch (always activated)

Main Parts

External View



1. Pressure sensor
2. Temperature sensor
3. Negative charge
4. Water switch
5. Positive charge
6. Shoulder bolts
7. Pull cords (center-pull)



1. Transducer
2. End cap
3. Pull cords (side-pull)



CAUTION:





- Do not put foreign objects into pressure sensor opening or try to open it.
- Do not remove the shoulder bolts from the outside of the sensor.

It may damage the components.

Operational Mode Indicator

A LED on the sensor's transducer indicates the operational mode of the sensor.

State	Situation	LED
Starting	<ul style="list-style-type: none"> • Sensor has been switched on in water or with water switch. 	

State	Situation	LED
		<ul style="list-style-type: none"> • Startup sequence: LED blinks green/off/red/off/green/red. • Then, fixed green for 1 sec.
Running	<ul style="list-style-type: none"> • Sensor is in water. • Water switch is on. 	 <ul style="list-style-type: none"> • For 1 min.: LED blinks red at the beginning of each uplink communication cycle. • Or, LED blinks green / red if the product configuration is not valid.
Configuring	<ul style="list-style-type: none"> • Sensor is out of water. • User is testing and configuring using a Configuration Cable. • Sensor turns off after 10 min. without test or configuration operation. 	 <p>LED blinks green.</p>
Charging	<ul style="list-style-type: none"> • Charger plug is connected. • User is configuring at the same time via the Dock. 	 <ul style="list-style-type: none"> • LED blinks red. • LED is fixed red after 10 sec. if connected to a charger other than the Dock.
On deck	<ul style="list-style-type: none"> • Sensor has been hauled on deck. • The virtual water switch is on. • The sensor is locked in a low power state to not switch into running mode. 	 <p>LED blinks green every 4 sec.</p>


Sensor Configuration

Learn how to configure the sensor settings.



Note: This guide refers to the following versions of **Mosa2**: 02.13.x. If you use another version, the visual interface and options may vary.



Note: To configure the sensor on Mosa2: Press command + A or click **Menu**  and click **User Mode > Advanced**.

Connecting the Sensor to Mosa2

To configure the sensor, you need to connect it to Mosa2 application, using either the Dock or the Configuration Cable.

Using a Dock Charger Plug

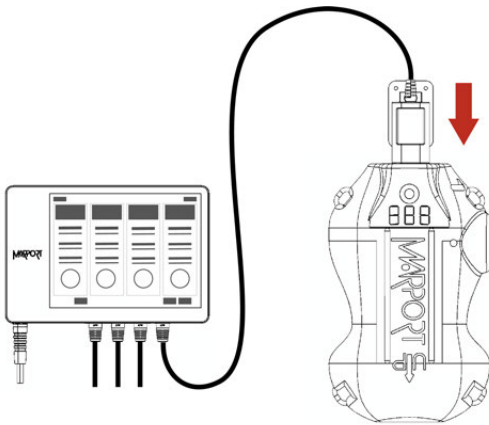
About this task



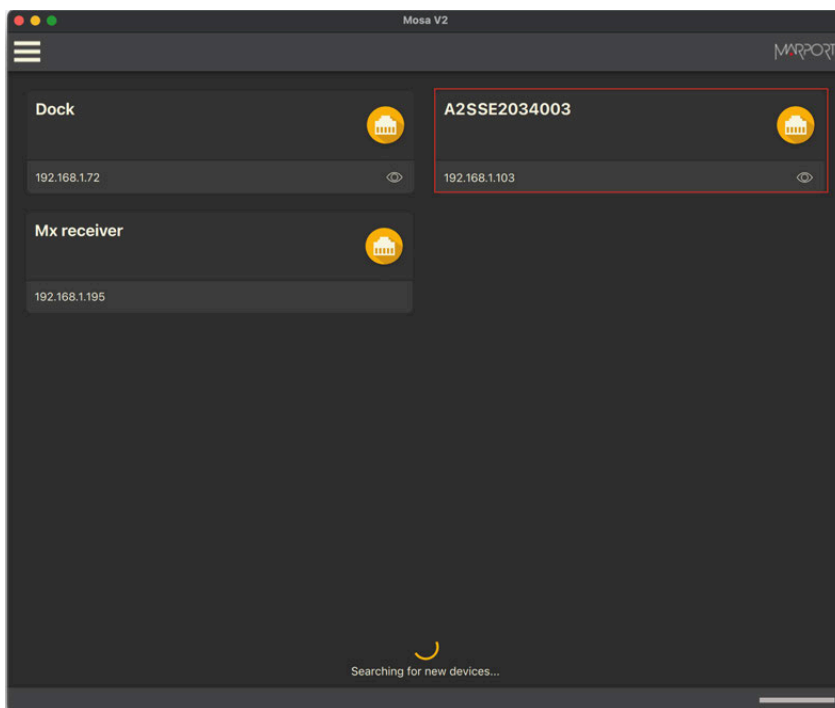
Tip: Refer to Dock user manual to have more details about the use of this product.



Procedure

1. Connect one Dock charging plug to the sensor's endcap.



2. Mosa2 discovery page opens. The sensor is displayed.




- Click  to open the sensor configuration page.
- Click  to show the deploy animation on the charger plug for 30 seconds.

Using the Configuration Cable

Connect the Configuration Cable from the computer to the sensor to display the sensor configuration page on Mosa2.

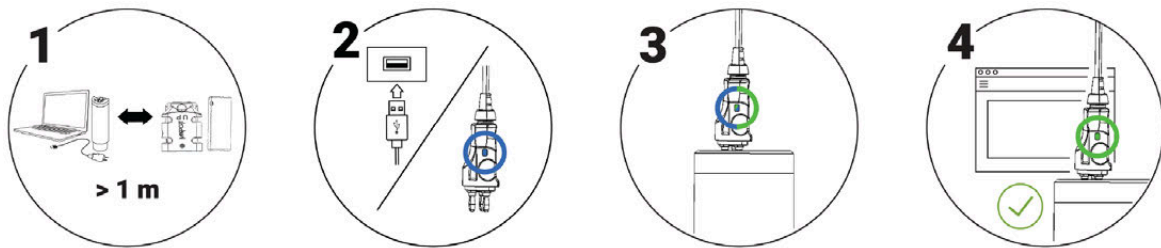
About this task

-  **Tip:** Refer to the Configuration Cable Quick Reference Guide available on our website for more details about the use of this product.

Procedure



1. Move other electrical devices minimum 1 m away from the computer.
2. Connect the USB connector directly to the computer.
Mosa2 opens automatically and the startup wizard is displayed. The LED on the plug is solid blue.
3. Connect the three-pin plug to the sensor.
The LED on the plug blinks alternatively blue and green.
4. Wait a few seconds. The configuration page of the sensor is displayed on Mosa2.
The LED on the plug is solid green.

Example



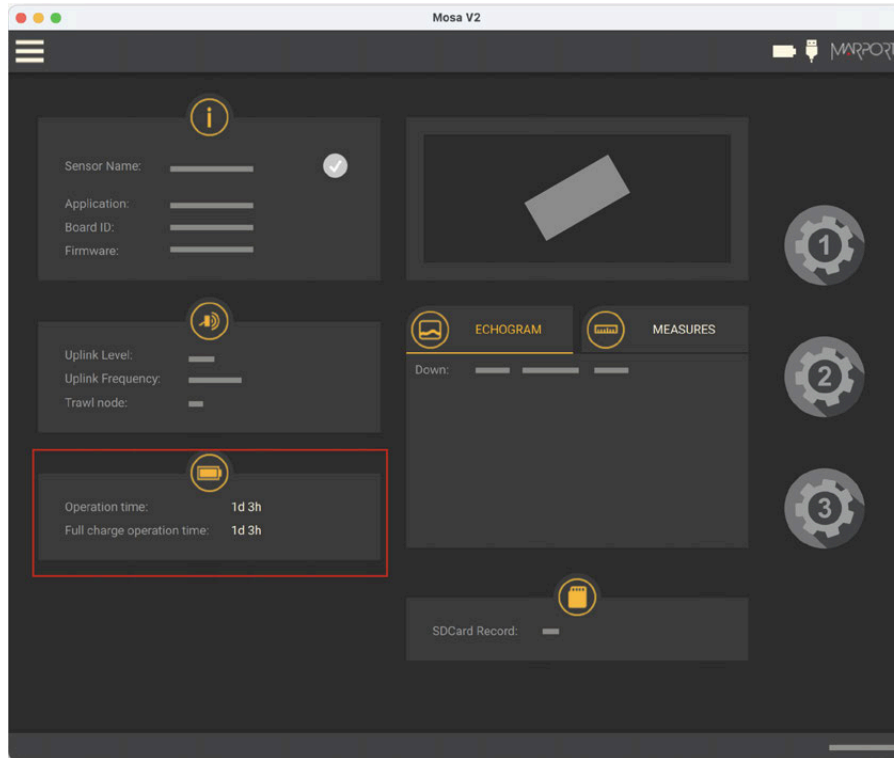
What to do next

You can now configure the sensor.

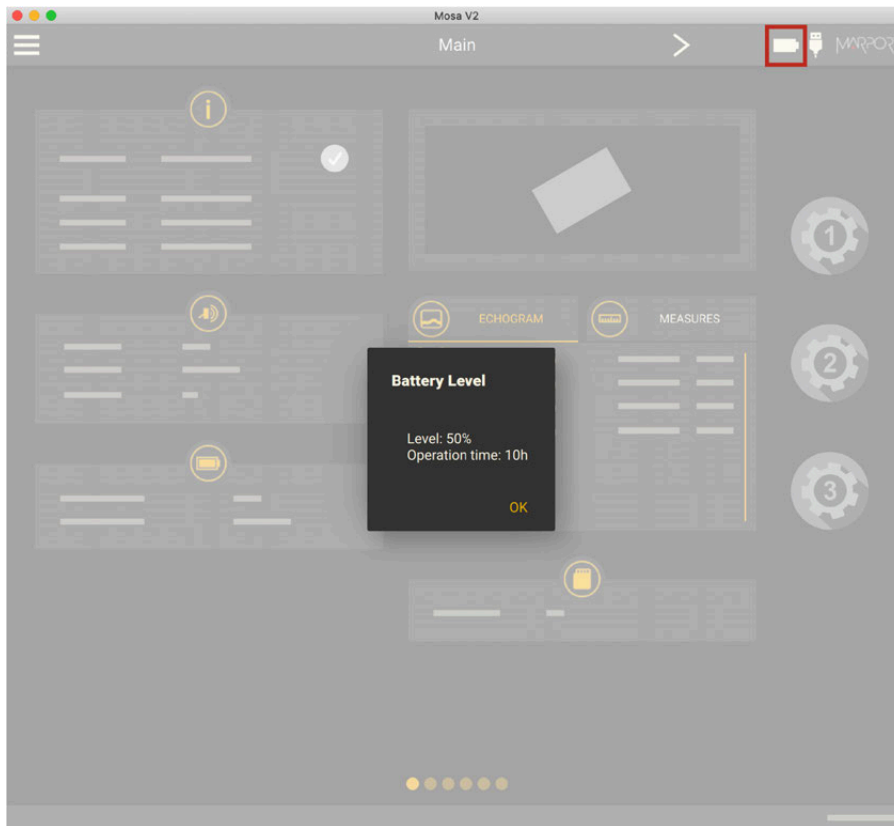
-  **Note:** You can keep the Configuration Cable continuously connected by USB, and virtually eject or connect it. When no sensor is connected to the Configuration Cable, click **Menu**  > **Eject Config Plug** or **Connect Config Plug**. When ejected, you come back to the discovery page. It stays disconnected until you virtually connect to it or manually disconnect then connect it.


Battery Information

The battery lifetime is displayed on the first page.




You can also check the battery level at anytime from the top bar:

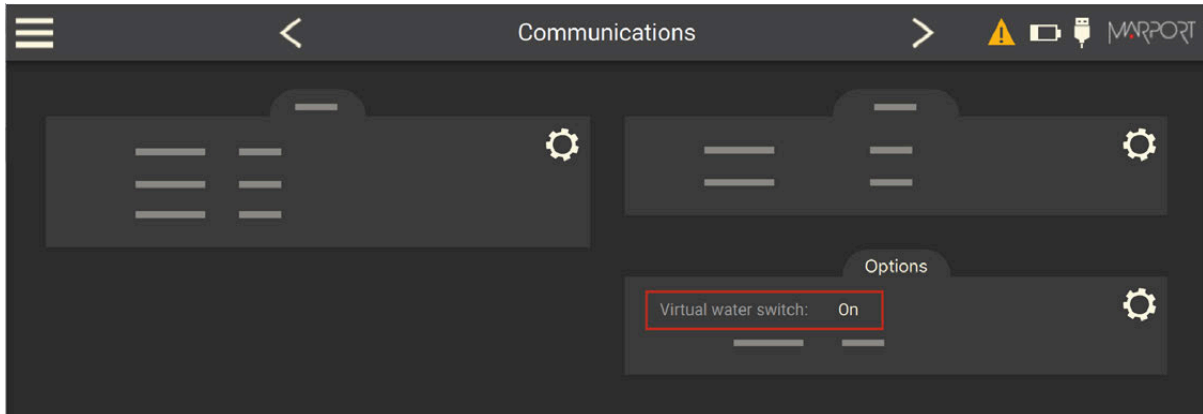


-  **Note:** When you change settings such as the uplink power or sounding range, it affects the battery consumption and remaining lifetime. The battery information will update after the sensor has been switched on and operating for 10 minutes.

About the Virtual Water Switch Option


Mosa2 has a virtual water switch option that changes the conditions under which the sensor is running.

 **Note:** The virtual water switch is available only for the **Pro** line of sensors (PCBA A2S Gen 2 and later, and all A2H versions). It is activated by default.



- When the virtual water switch is activated: the sensor runs when the depth is more than 2 meters and the water switch is in contact with water.

We recommend to activate it to prevent the sensor from running outside water. For example, if the sensor is hauled on deck and stays inside the net, the water switch remains wet and keeps emitting. This will significantly reduce the battery lifetime.

 **Note:** When activated, an orange warning icon is displayed in the top bar.



- When the virtual water switch is deactivated: the sensor runs only when the water switch is in contact with water. The depth is not taken into account.

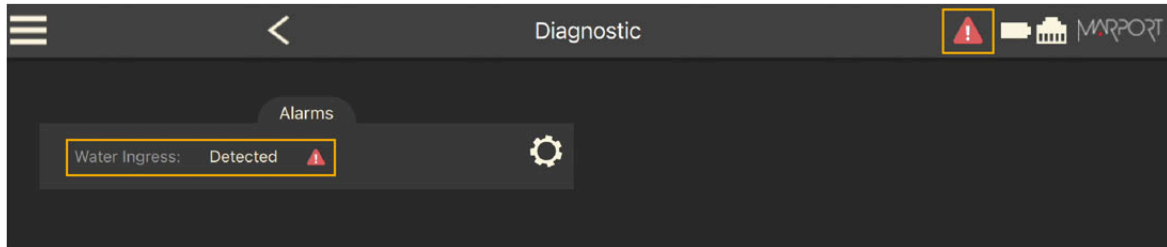
We recommend to deactivate it if the sensor is operating close to the surface or if you need to test the sensor in the office.

Diagnostic Information

Scala2 and Mosa2 applications warn the user in case of water ingress in the sensor.

In case of water ingress in the sensor, alarms are displayed in Scala2 Virtual Charger Room, in Mosa2 and on the charger plug when connected to the sensor.

In **Expert** mode, Mosa2 displays a dialog at the start of the application and warning icon in the toolbar and diagnostic page:



The charger plug displays a warning icon:



When the alarm appears, take the sensor out of water immediately and contact Marport support.

Warning: In case of water ingress in the product, do not charge it: battery may vent or rupture, causing product or physical damage.

Configuring the Trawl Node

You need to give a trawl node to the sensor. It is the number corresponding to the position of the sensor on the trawl.


About this task

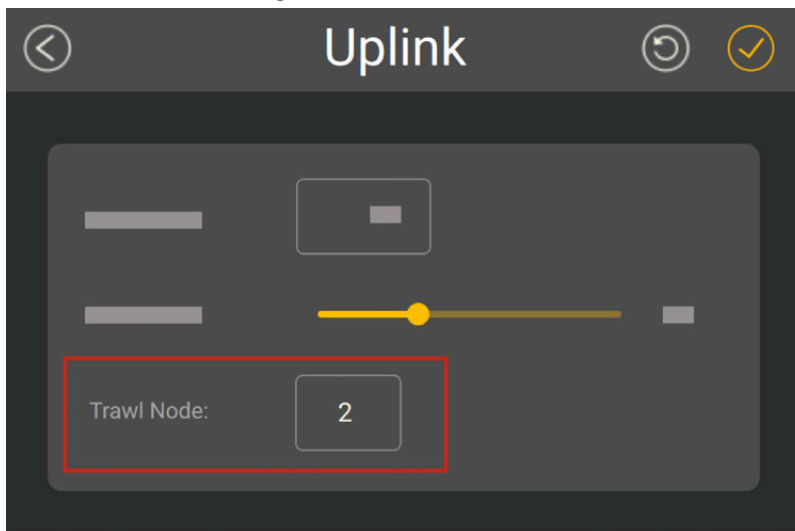
The trawl nodes corresponding to the positions on the codend are the following:


Trawl number	Node numbers
Trawl 1	1 to 6
Trawl 2	101 to 106
Trawl 3	201 to 206

Trawl number	Node numbers
Trawl 4	301 to 306
Trawl 5	601 to 606

Procedure

1. Go to the **Communications** page, then click  in **Uplink**.
2. Enter a node according to the position of the sensor on the trawl.



 **Important:** Make sure to put the same number when **adding the sensor to Scala2 receiver page (on page 45)**. If not, change it accordingly.

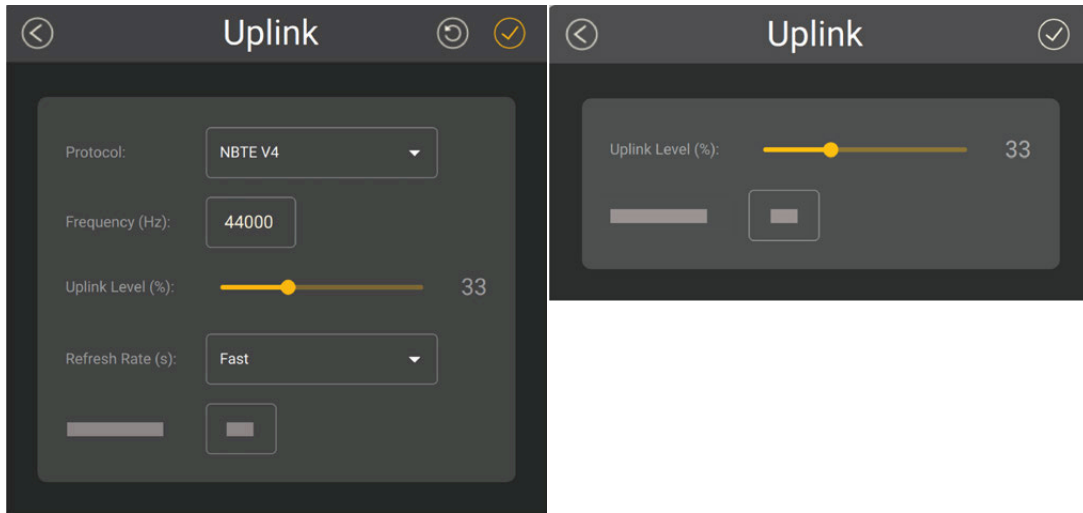
3. Click .

Configuring the Uplink Signal

Configure the settings of the communication link between the sensor and the vessel.

Procedure


1. Go to the **Communications** page, then click  in **Uplink**.



Catch Explorer Pro

Catch Pro

2. Catch Explorer Pro only: Choose a communication protocol.
 - NBTE V4: latest protocol, for A2S sensors.
 - Select previous versions if the sensor needs to be compatible with versions of the Mx receiver earlier than 08.03.04.
3. Enter a frequency for the communication with the vessel. Default is 44,000 Hz.
4. Drag the slider to change the power of the uplink signal.

 **Note:** A higher level of uplink power reduces the battery lifetime.

Recommended uplink powers	Conditions
33%	Works for most conditions.
100%	<ul style="list-style-type: none"> ◦ Sensor is far from vessel - e.g. more than 800 m depending on conditions, high depth, placed on the codend. ◦ High level of interferences

Recommended uplink powers	Conditions
	<ul style="list-style-type: none"> ◦ Issues receiving data ◦ Low SNR

5. Catch Explorer Pro only: In **Refresh Rate**, leave **Fast** selected.

Configuring the Telegrams

You change the telegram assigned to each type of data.


About this task

Telegrams are used to define the acoustic communication between the sensor and the receiver. Data (e.g. temperature, depth) are recognized by the receiver according to the type of telegram defined (e.g. TL, CL). The telegram defines intervals between pulses emitted by the sensor, and one interval represents one value. For example, if the interval between 2 pulses of a TL temperature telegram is 12 s, the temperature is 6.5 °C.

The telegrams that are sent depend on the sensor's features and options.

! **Important:** Make sure there is a minimum distance of 100 Hz between PRP telegrams and a minimum distance of 400 Hz with the uplink frequency of NBTE sensors. See **Frequency Plan (on page 74)** for a full list of boat/channel codes.

Procedure

1. In **Communications** page, you can see the list of the telegrams sent by the sensor.
2. Click  in **Telegrams List**, then set a telegram.


Option	Telegram	Value and/or update rate
Catch	M1	Full status every 20 sec. / Empty status every 30 sec.
PI Catch	SLOW	Full status every 123 sec. / Empty status every 126 sec.
	NORMAL	Full status every 32 sec. / Empty status every 34 sec.
	FAST	Full status every 5 sec. / Empty status every 5.5 sec.
Depth	D1	100 m., every 1 to 2 sec.
	D2	150 m., every 3 to 8 sec.

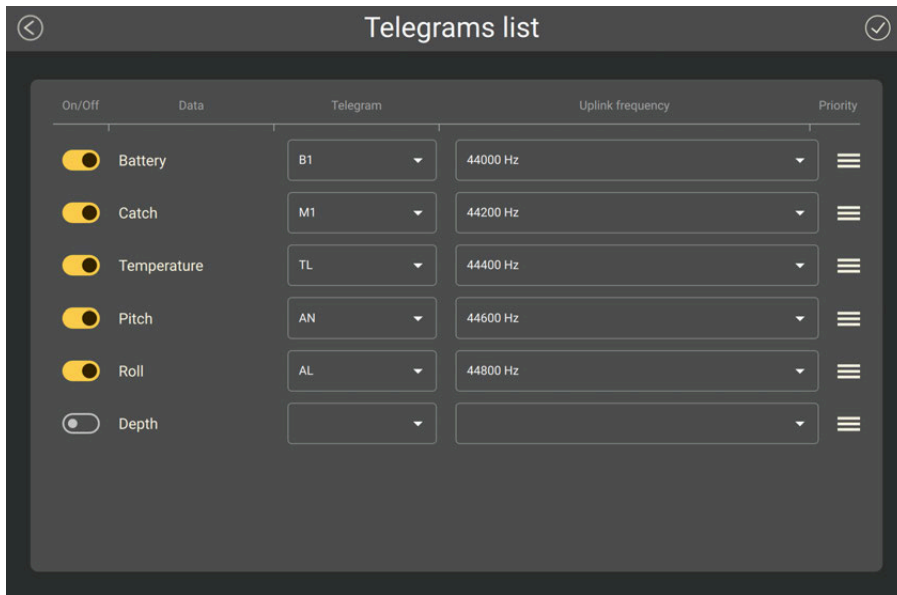
Option	Telegram	Value and/or update rate
	D3	300 m., every 3 to 8 sec.
	D3_MC	300 m., every 4 to 8 sec.
	D6	600 m., every 3 to 8 sec.
	D12	1200 m., every 3 to 8 sec.
	D18	1800 m., every 3 to 8 sec.
Temperature	TL	Every 11 to 16 sec.
	TL_MC	Every 8 to 11 sec.
	TN	Every 3 to 11 sec.
Pitch and Roll	CL	Every 11 to 14 sec.
	VQ	Every 5 to 7 sec.
Pitch only	D6	Every 3 to 4 sec.
	AN	Every 3 to 6 sec.
	VSH	Every 2 to 4 sec.
Roll only	D3	Every 3 to 8 sec.
	D6	Every 3 to 4 sec.
	AL	Every 11 to 15 sec.
	VRH	Every 2 to 4 sec.
Battery	B1	Every 60 to 70 sec.



Note: Using telegrams that send data more often reduces the battery life.

- To configure a Catch Twister ($\pm 180^\circ$ roll), set the roll telegram to **D6**.

4. Set a frequency for each data, either manually or using a boat/channel code.
5. Click  and drag it to change the order in which data are sent.



Catch Explorer Pro Specific Settings


Configure the settings of the Catch Explorer Pro echo sounder.

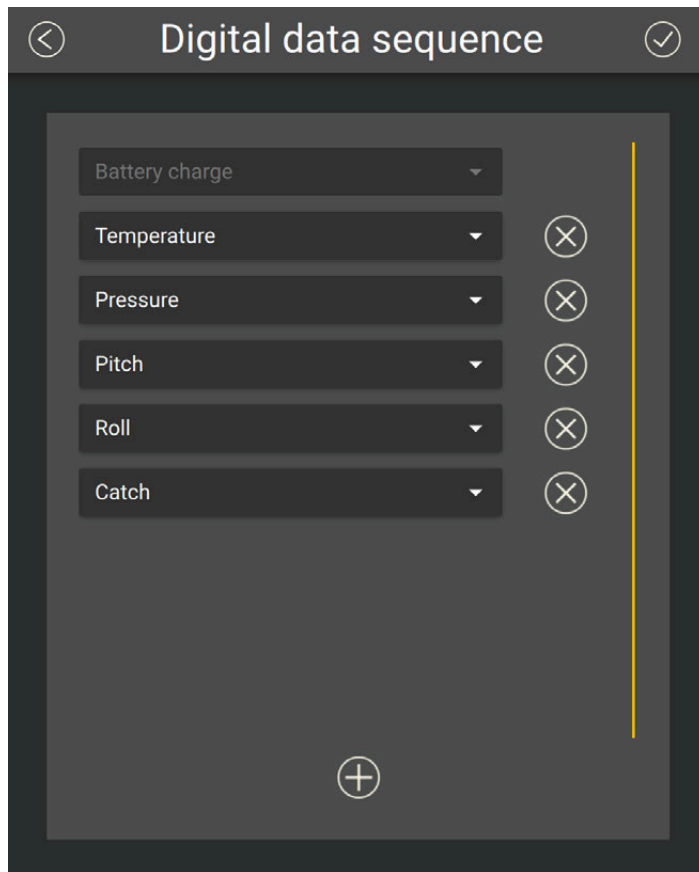
Configuring Data Sending Sequence


You can configure the order and types of measurements (e.g. temperature, pitch, roll...) sent to the receiver.

Procedure

1. Press command + A or click **Menu**  and click **User Mode > Advanced**.
2. In **Communications** page, click  in **Data Sequence**.

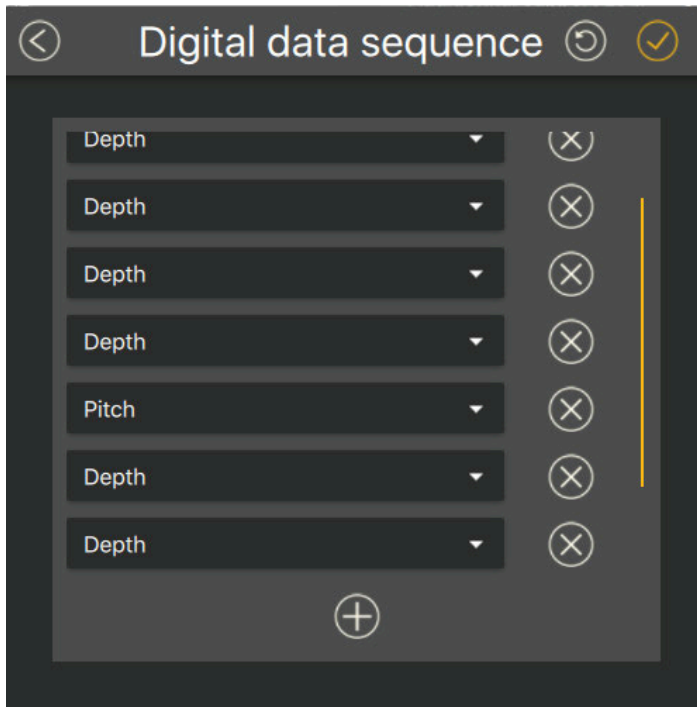
3. To add data, click  then select data in the drop-down menu. The sequence begins by the top.



 **Trouble:** If you do not see some data, it means it is not activated on the sensor (application file).

4. To delete data, click  in front of data.

5. To activate True mode display, enter a sequence corresponding to the following order: 4 x Depth / 1 x any data / 4 x Depth / 1 x any data, etc.





6. Click .

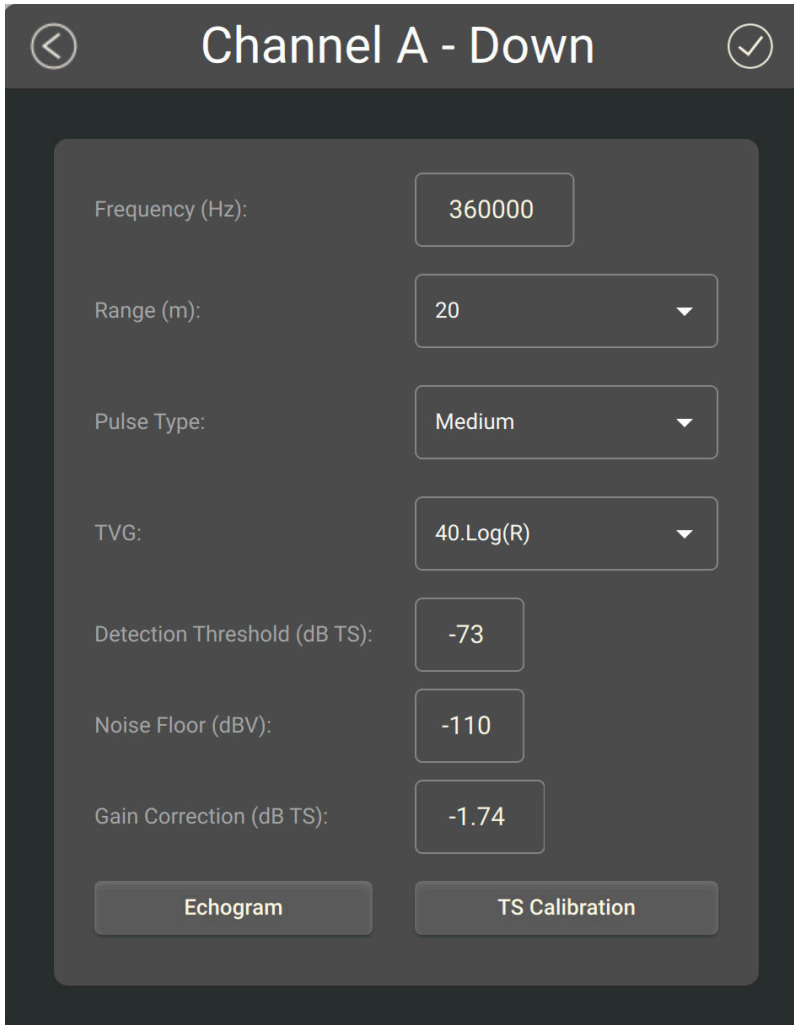
Configuring the Echo Sounder



Configure the echo sounder settings of the Catch.

Procedure

1. Go to the **Echo Sounder** page.
2. To select the direction of the sounding, click  in **Sounding Mode**, then choose a **Mode** between **Down only** or **Down + Down2** (choices depend on activated options). **Down + Down2** option allows you to compare two different settings on the down sounding (for example, 2 ping lengths or 2 frequencies). The sensor will send two consecutive pings toward down direction.


3. Go back to the page, then click  in front of the sounding direction, depending on the **Sounding Mode** that was configured.



4. Leave default **Frequency (Hz)** at 360,000 Hz.
5. Set the **Range (m)** of the sounding according to the maximum distance at which targets and bottom can be detected.
-  **Note:** We recommend to set the maximum range value when using the automatic range in order to see the sea bottom as soon as possible.
 -  **Note:** Range influences the display of echogram images. The smaller the range, the shorter the listening time and the better the quality of images. But if you set a bigger range, data arrives slower which results in poorer image quality.
6. If you want the range of the down sounding to automatically change to 20 m when the bottom is closer, see **About the Automatic Range Mode (on page 34)**.

7. Select a **Pulse Type** to have an appropriate length of pulse according to the distance to the bottom:

- **Short:** shallow waters (100 μ s)
- **Medium:** moderate depth (300 μ s)
- **Long:** deep waters (500 μ s)

 **Important:** Pulse length is an important setting for the calibration of the sensor. If you change the pulse length on a sensor calibrated for target strength, you need to calibrate the sensor again.

8. Select a **TVG** setting to compensate the signal loss in water and have targets or sea bottom displayed in the same color on the echogram, whatever the distance from the sensor:

- 20 log: focus on the bottom, footrope or a school of fish. (Recommended for this sensor.)
- 40 log: focus on individual targets.
- 30 log: compromise between the two others.

9. Set the **Detection Threshold (dB TS)** to -79 if you want to detect small targets. Otherwise, leave the default settings at -73 dB.

10. Do not change the other echo sounder settings.

About Time Variable Gain

TVG (Time Variable Gain) is a method that compensates signal loss in the water. Basically, the aim is to have targets or sea bottom displayed in the same color on the echogram, whatever the distance from the sensor.

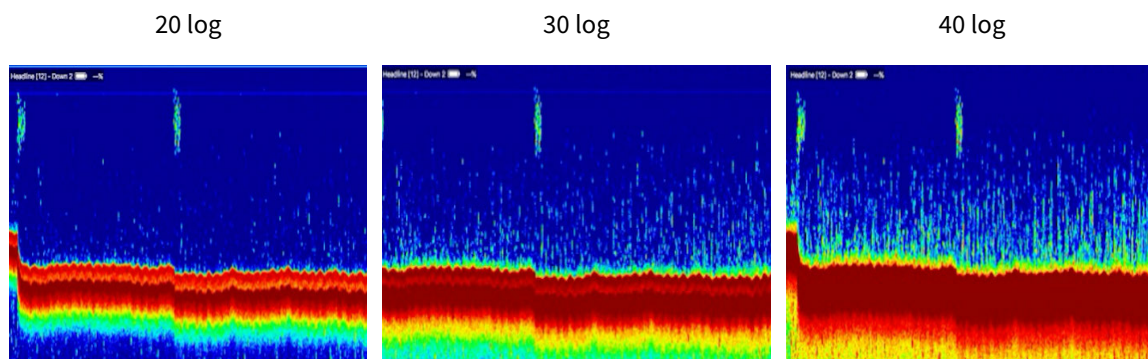
When the sounder sends pings, the deeper the target is, the more attenuated signals will be received and sent back. As a result, if the signal is too much attenuated, echoes (target strength) received from a target might not be as strong as they should be. TVG is here to compensate this effect. It uses a lower gain level when signals travel toward a target at a small distance and higher gain level when signals travel toward deeper targets. The end result is to compensate sounding attenuation and therefore to show a same target strength for a same target at different depths.

You can choose between three different TVG modes:

- 20 log: focus on the bottom, footrope or a school of fish.
- 40 log: focus on individual targets.
- 30 log: compromise between the two others.

For example, if you want a good view of the footrope, select a TVG mode at 20 or 30 log. You can see on the images below that the footrope is clearer at 20 and 30 log.

If you want a good view of individual targets, you can see that with 40 log, targets in the water column are clearer.



About the Automatic Range Mode

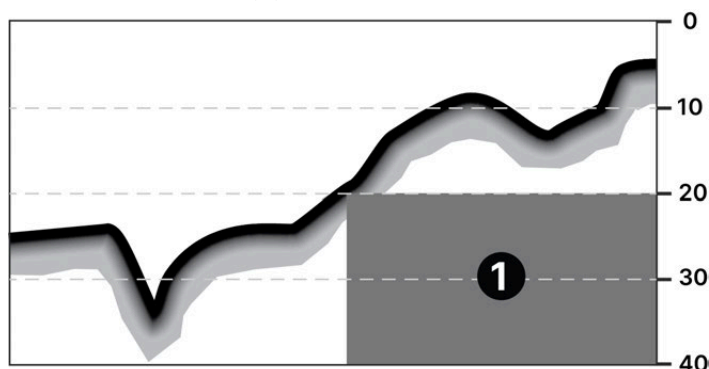
The sensor has an automatic range mode that is useful to get better quality echograms when the trawl is close to the bottom.

Principle


Range influences the display of echogram images. The smaller the range, the shorter the listening time and the better the quality of images. But if you set a bigger range, data arrives slower which results in poorer image quality.

You can activate the automatic range mode if you need to get better quality echograms when the trawl is close to the bottom. This mode is recommended when bottom trawling.

The echogram can automatically switch to a 20-meter range when the distance to the bottom is less than 20 meters (1).




The change of range depends on the settings configured on Mosa2.

 **Note:** The sensor requires pitch and roll angles within -25° to 25° for automatic range operation.

Mosa2 settings

The following **Sounding Mode** options must be set in Mosa2:

- The **Mode** must be set to **Down only**.
- The Down sounding **Range (m)** must be more than 20 meters.
- The **Refresh Rate** must be set to **Fast**.
- The **Trawl Opening** must be lower than 18.5 meters to be able to switch to a 20-meter range.
- **Automatic Range** must be activated.



 **Note:** The trawl opening value sets the minimum distance to see inside the trawl. As a result, if the trawl opening distance is equal or higher than 18.5, the sensor will not reduce the range to 20 meters.

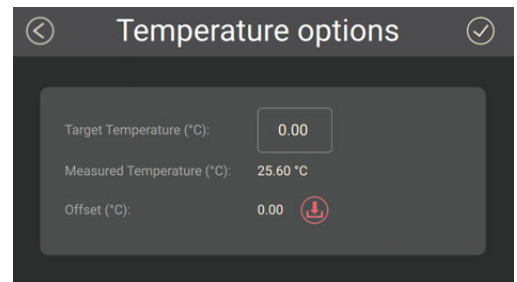
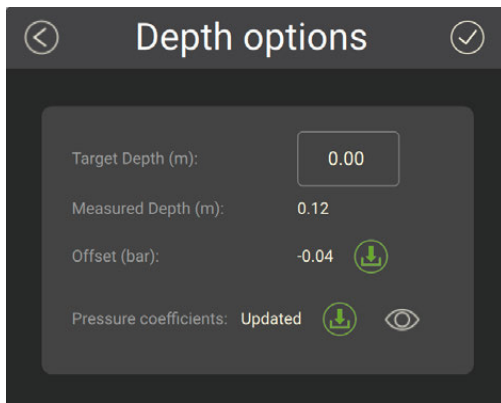
See **Configuring the Echo Sounder (on page 31)** for details about Mosa2 settings.


Applying Offsets to Measurements

You can apply offsets to temperature and depth measurements if the measured values do not correspond to the environment of the sensor.

Procedure

1. Go to **Measurements** page and click  next to depth or temperature to apply offsets.
 2. Enter a target value. Click .
- The measured value becomes the same as the target value. The value of the offset is displayed.



3. If you need to reuse offsets from a previous configuration, click  then select the configuration file (*.A2C).
4. About the pressure coefficients: you do not need to upload this file, the coefficients are directly included in the application file downloaded from MASP. Note that if you replace the pressure sensor, you need to change the sensor in MASP and upload the application file again.

Testing Measures

You can test the measures taken by the sensor (e.g. battery level, temperature, depth) to check that there are no faults.

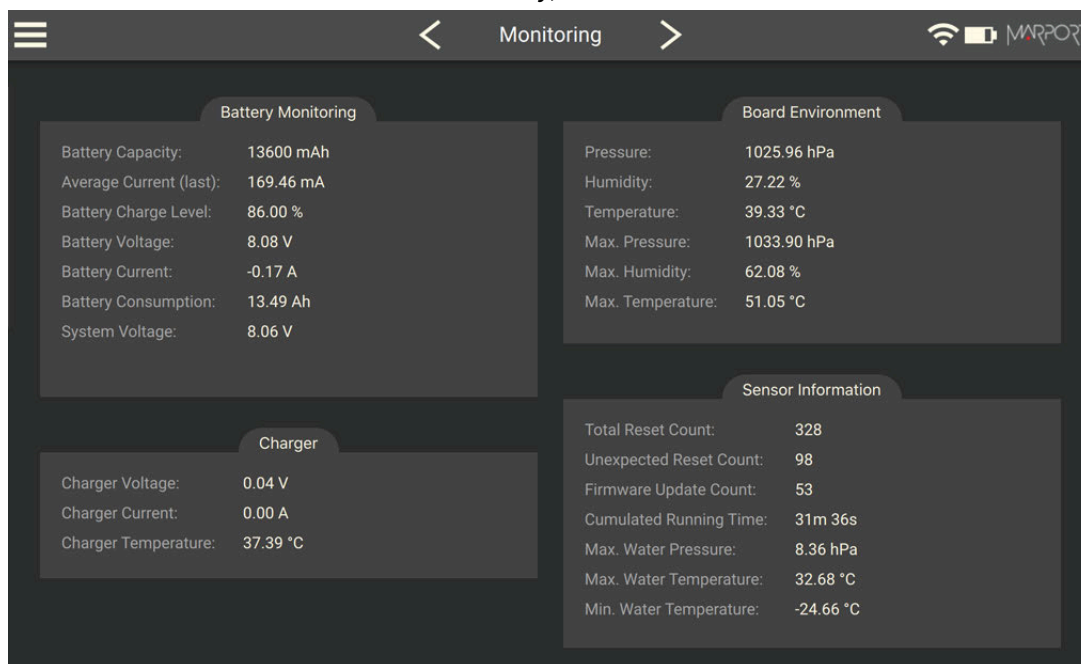
About this task

You can test the sensor in water or in air. In air, the following measures will be wrong: height, conductivity.

Procedure

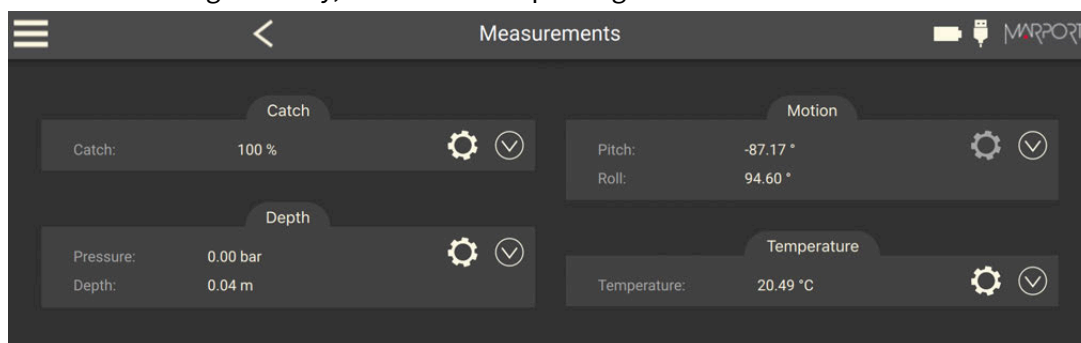
1. Press command + A or click **Menu**  and click **User Mode > Advanced**.
2. Go to the **Monitoring** page.


You can check information about the battery, board and sensor.



3. Go to the **Measurements** page.

You can see the values of the activated measures, such as depth, temperature. If the sensor is working correctly, measures are updating.



4. Click  to check and, if necessary, adjust data measured by the sensor:

- **Depth:** place your sensor on a desk or on the ground and enter 0 in **Target Depth**.
- **Temperature:** enter the estimated temperature of your environment.
- **Catch:** Set options for catch measures and calibrate the sensor.

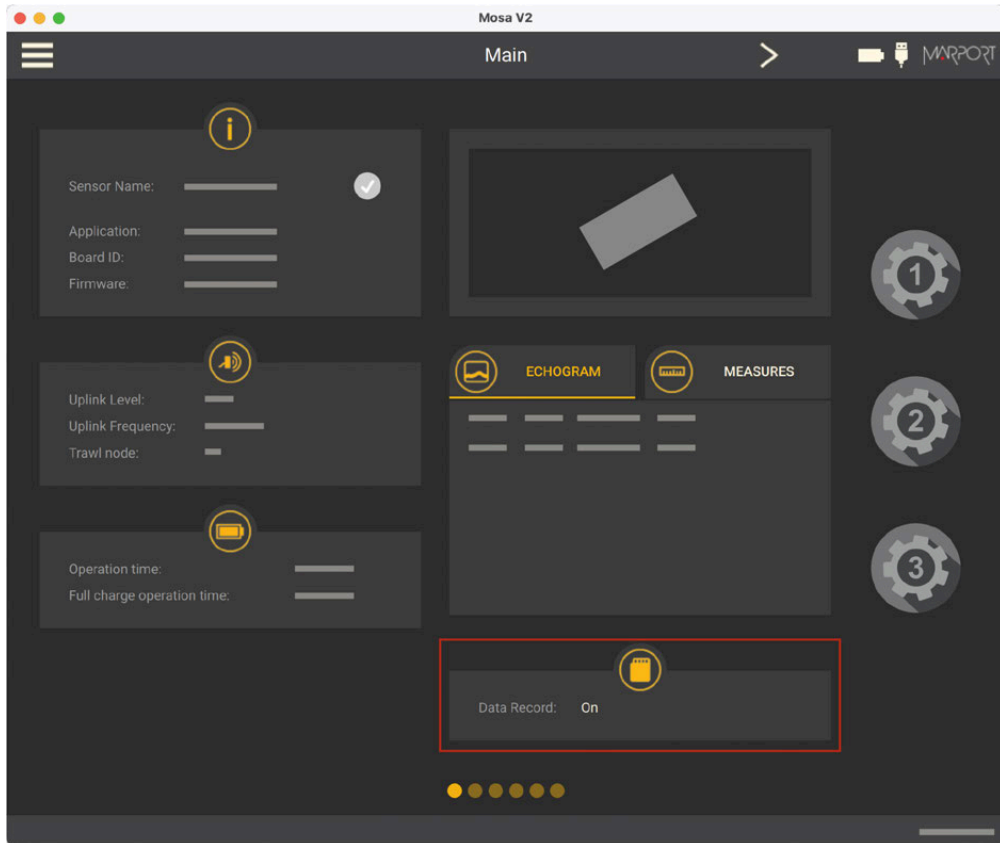
Memory Card Recording

This topic explains the memory card recording feature (this feature is optional).

Overview


Data recorded on the sensor memory card are in higher resolution, with a higher refreshing rate. For sensors with echograms, you can see target strength values without uplink sound transmission loss.

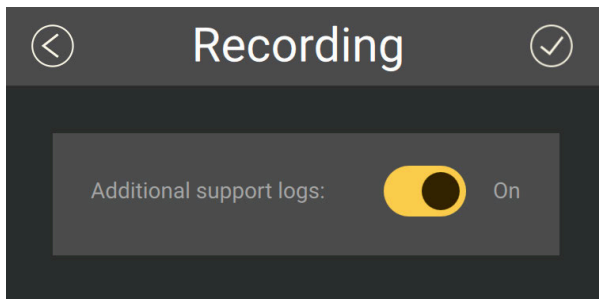
You can see on Mosa2 main page if the memory card recording feature is activated:



Additional settings

We recommend to activate the support logs to help support teams for error diagnosis.



1. Go to the **Communications** page, then click  in **Recording**.
2. Activate **Additional support Log**.




Getting data from the memory card

The last 99 recorded sensor data files and last 99 battery files are displayed. Two types of files are on the memory card:

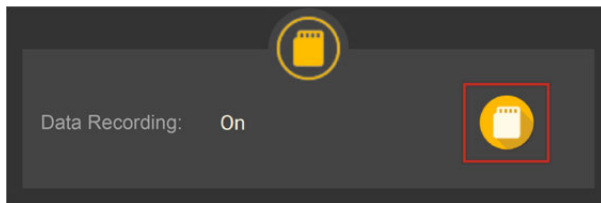
- Files containing measures recorded by the sensor. Their name begins by "450". These data are more precise and recorded more often than data received on the receiver. One file corresponds to a tow (time between entering and leaving water). The recording date displayed in the second column is synchronized with your computer time.
- BATT = Files created when the sensor is charging (1 file per charging cycle). They are useful for support teams for troubleshooting.

 **Note:** The first time the sensor connects to Mosa2 or if the sensor desynchronizes, a clock with a warning icon  is displayed in the top toolbar. Click it to synchronize the time of the memory card with the computer's time.

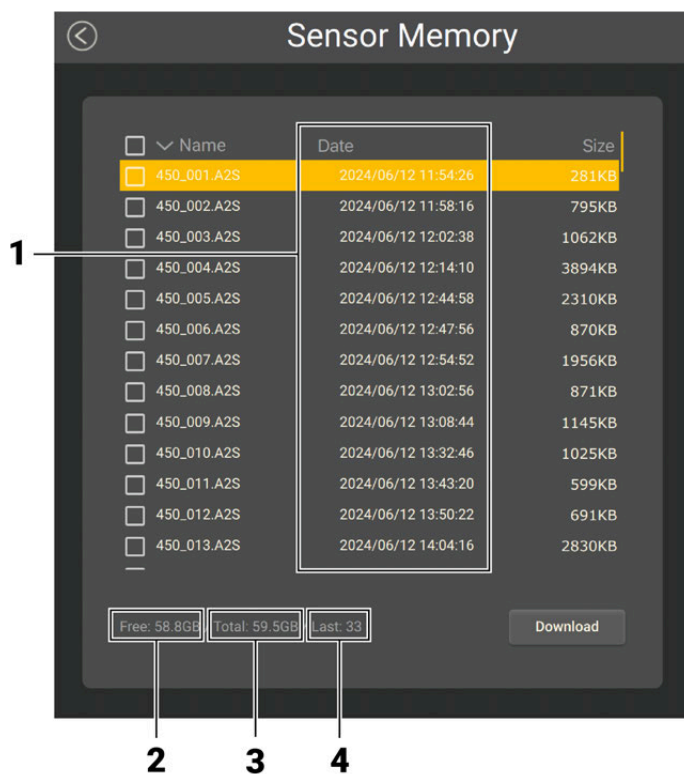
 **Note:** When downloading the files, we recommend to connect the sensor to Mosa2 using the Dock or the Configuration Cable for a better transfer of data.

1. Press command + E or click **Menu**  and click **User Mode > Expert**.

2. On the first page, click  in **Data Recording**.



Recorded files are displayed. Click the title of the columns to sort them by their name, date or size.



1. Time of end of towing
2. Free memory
3. Total memory size
4. Index of the last file written

See **Replaying Data Recorded on a Memory Card (on page 55)** to learn how to replay these data in Scala2.

Saving a Configuration on Mosa2

You can save different configurations of the sensor to be able to quickly change the configuration when you change your fishing method.

Before you begin



- You have finished configuring the sensor.

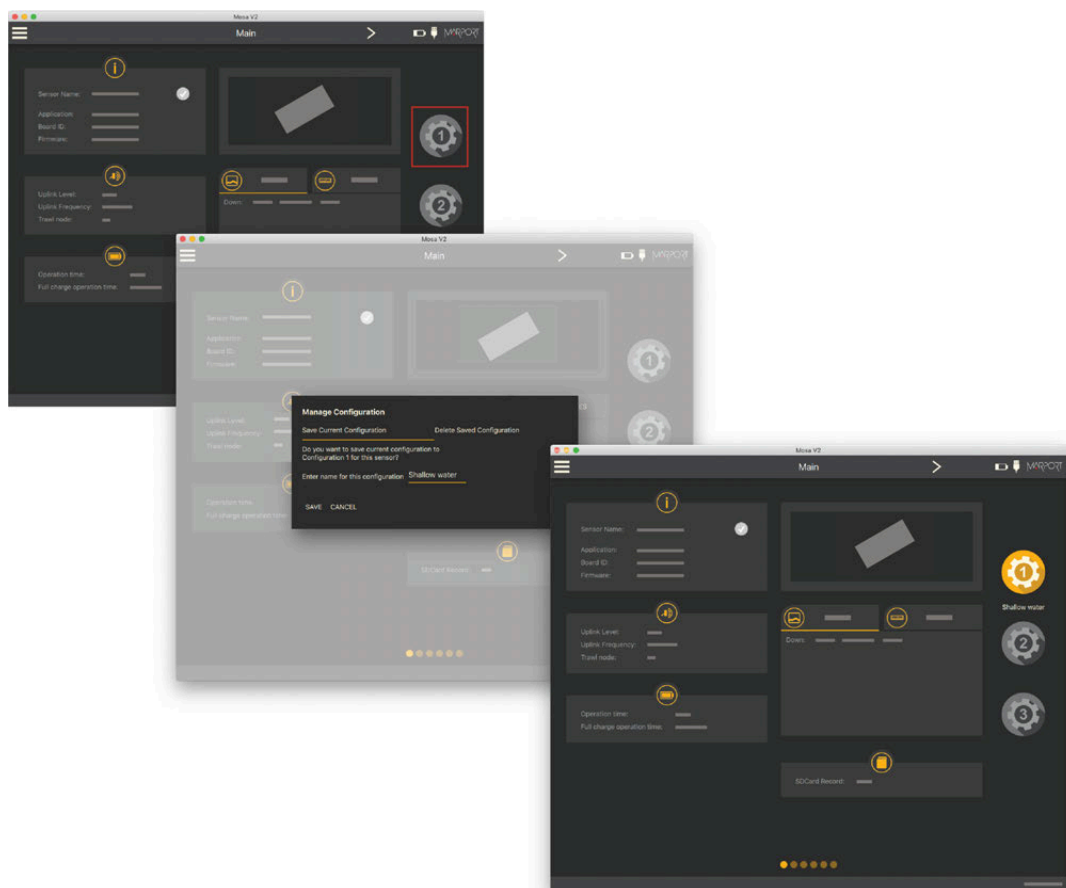
About this task

You can have up to three different configurations for the sensor. When you change your fishing method, you can apply a corresponding configuration in one click. For example:

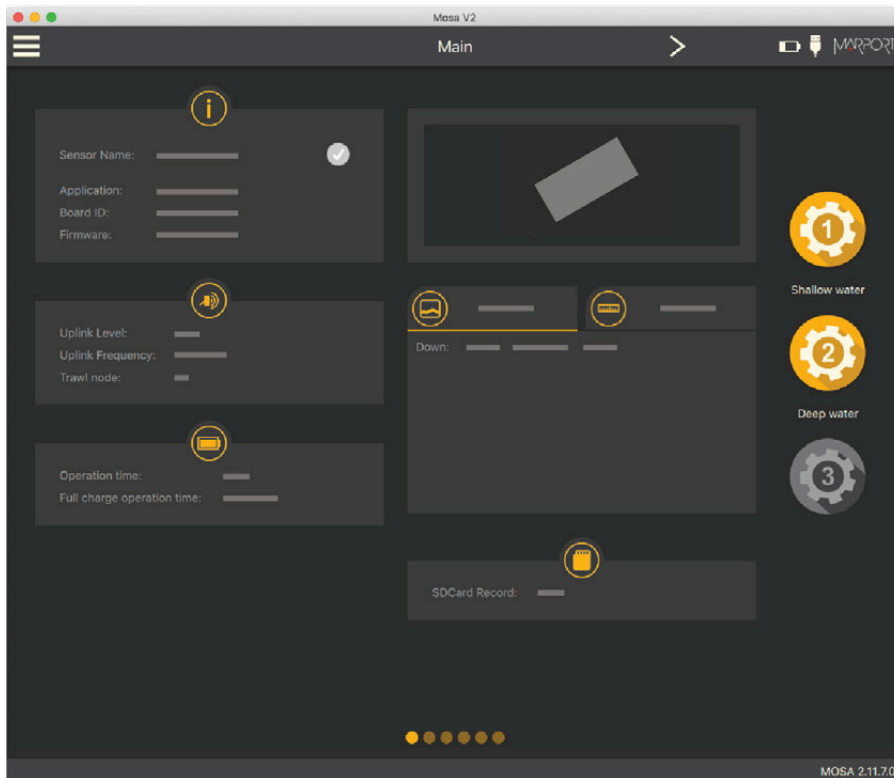
- If fishing in shallow water, you can use a configuration with an uplink level of 33%, a short pulse and a short range.
- If fishing in greater depths, you can change for a configuration with an uplink level of 100%, a long pulse and a long range.

Procedure

1. When you are finished configuring the sensor, for example to use the sensor in shallow water, click one of the wheel icon  on the first page of Mosa2.
water, click one of the wheel icon  on the first page of Mosa2.
2. In the window that appears, enter a name for the configuration and save it.
The wheel icon becomes orange and the name of the configuration is displayed underneath.



3. To create another configuration, for example this time to use the sensor in deep waters, change the settings of the sensor on Mosa2.
4. When you are finished, click the second wheel icon and save the configuration.



5. If you need to change the sensor configuration back to the first configuration (shallow water), click the corresponding wheel.
The configuration is applied.
6. If you need to make changes to a configuration:
 - a. Change settings.
 - b. Maintain the click on the corresponding wheel until the **Manage Configuration** window appears.
 - c. Click **OK** in **Save Current Configuration**.
7. To delete a configuration:
 - a. Maintain the click on the corresponding wheel until the **Manage Configuration** window appears.
 - b. Click **OK** in **Delete Saved Configuration**.

Exporting Sensor Configuration

You can export the sensor settings you configured on Mosa2 on a file. You can afterward use this file when configuring a similar sensor.

Before you begin

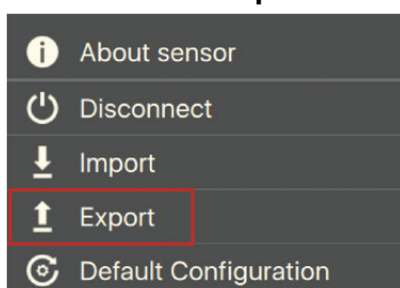
- You are finished configuring the sensor.

About this task

If you have issues with your sensor, send this file to support teams.

Procedure

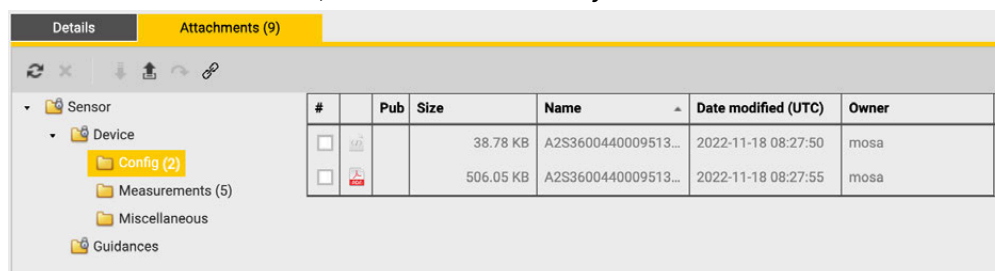
1. Click **Menu**  > **Export**.



2. From the window that appears, choose a folder on your computer to save the file and click **Open**.

Results

The configuration file is exported and saved on your computer as an A2C file. If you are connected to the internet, it is also automatically sent to MASP in XML and PDF files.



Importing a Sensor Configuration

You can apply to a sensor a configuration that has already been made on another sensor.

Before you begin

- You have exported a configuration (see **Exporting Sensor Configuration (on page 42)**) and have the *.A2C or XML configuration file.

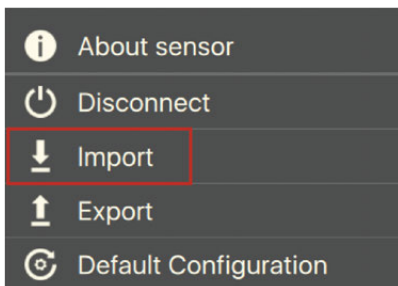
About this task

Only the following settings are imported: trawl node, recording settings (SD card, support logs), communication options (virtual water switch, simulation mode), uplink level and frequency, echo sounder settings.

- ! **Important:** If the new configuration changes the echo sounder settings, you must recalibrate the sensor for target strength value.

Procedure

1. Press command + A or click **Menu**  and click **User Mode > Advanced**
2. Click **Menu**  > **Import**.




3. From the window that appears, select the *.A2C or XML configuration file.

Results

The configuration is loaded into the sensor.

System Configuration and Display

Learn how to configure the receiver to be able to receive and display Catch data.

 **Note:** This guide refers to the following version of Scala2: 02.14.x. If you use another version, the visual interface and options may vary.

Adding the Sensor to the Receiver


You need to add the sensors to the receiver in order to display their data on Scala2.

For compatibility details, see **System Compatibility (on page 10)**.


Adding the Sensor to the Receiver

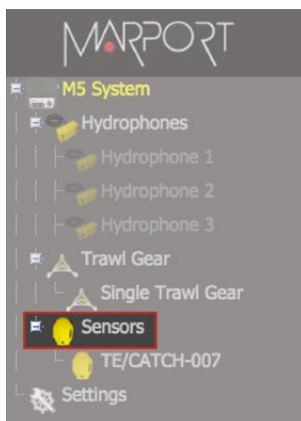
You need to add the sensors to the receiver using the system web page.

About this task

 **Important:** To be able to add your sensor to the receiver, make sure your receiver version is compatible. Check **System Compatibility (on page 10)**.


Procedure

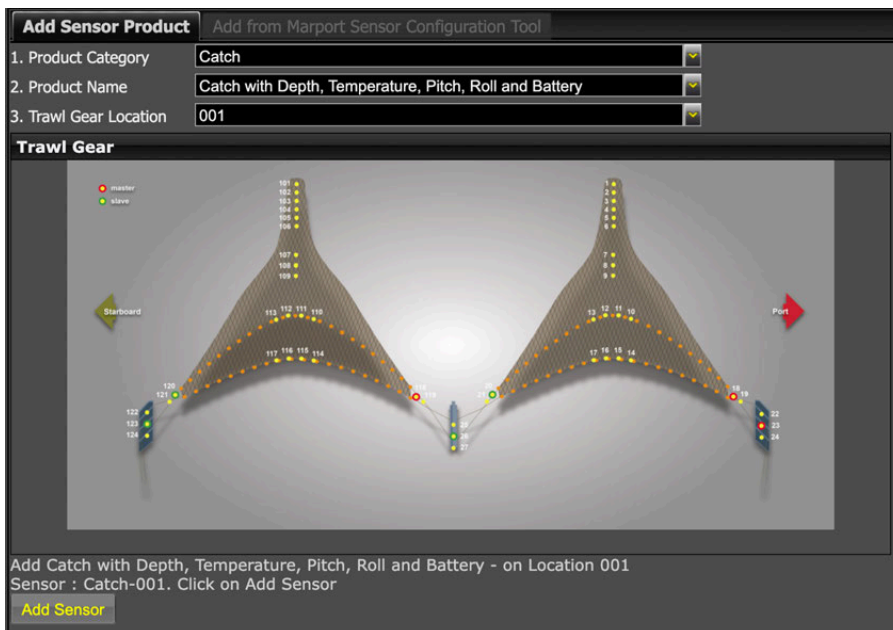
1. From Scala2, click **Menu**  > **Expert Mode** and enter the password `copernic`.
2. Right-click the IP address of the receiver at the bottom of the page, then click **Configure Receiver**.
3. From the left side of the receiver page, click **Sensors**.



4. From the page **Add Sensor Product**, select the options corresponding to your type of sensor:

Type of sensor	Product category	Product Name	Trawl Gear Location
Catch Explorer	TE/Catch	TE/Catch (V4) with...*	Same as defined in Mosa2 (see Configuring the Trawl Node (on page 24))).
Catch	Catch	Catch with...* / Catch Twister with...*	
Catch hybrid PI	PI Sensor	PI Catch	

 **Note:** *Choose the **Product Name** according to the sensor features chosen in MASP.




5. Click **Add Sensor**.

The sensor is added to the receiver and displayed on the left side of the screen. The configuration page is displayed.

Configuring Sensor Settings

You need to complete communication settings when you add the sensor to the receiver.

 **Important:** Make sure the settings you enter here are the same as in Mosa2.

Catch Pro



CATCH-002

Sensor Name
 Sensor Name: CATCH-002
 Sensor Product: Catch with Depth, Temperature, Pitch, Roll and Battery

Sensor Options
Sensor Processing
 Detection: Detection and 2D Sensitivity: Medium

Catch
 Frequency (Hz): 44200 Telegram: M1 Filter: Configure...

Depth
 Frequency (Hz): 44900 Telegram: D1 Filter: Configure...

Temperature
 Frequency (Hz): 44400 Telegram: TL Filter: Configure...

Roll
 Frequency (Hz): 44800 Telegram: AL Filter: Configure...

Pitch
 Frequency (Hz): 44600 Telegram: AN Filter: Configure...

Battery
 Frequency (Hz): 44000 Telegram: B1 Filter: Configure...

Apply

4

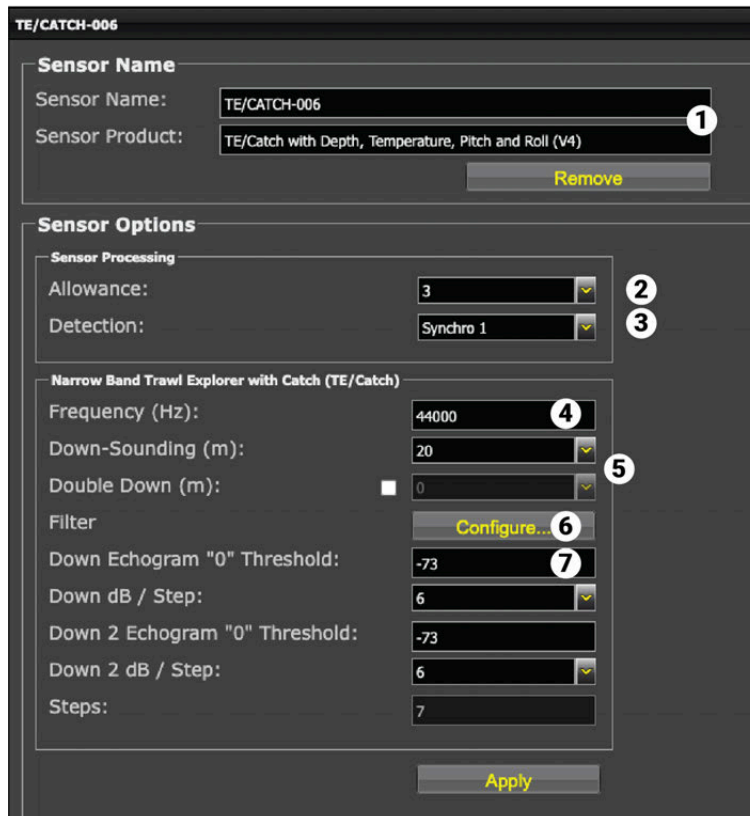
Telegrams list

On/Off	Data	Telegram	Uplink Frequency	Priority
<input checked="" type="checkbox"/>	Battery	B1	44000 Hz	
<input checked="" type="checkbox"/>	Catch	M1	44200 Hz	
<input checked="" type="checkbox"/>	Temperature	TL	44400 Hz	
<input checked="" type="checkbox"/>	Pitch	AN	44600 Hz	
<input checked="" type="checkbox"/>	Roll	AL	44800 Hz	
<input type="checkbox"/>	Depth			



1	Sensor name displayed in Scala2 and its features.
2	<p>This setting helps detecting the signal of the sensor among other sensor or echosounder signals. Change only if you have issues receiving data.</p> <ul style="list-style-type: none"> • Detection and 2D: default value. This setting helps distinguishing the sensor signals when there are a lot of interferences (e.g. echosounders). It selects the correct signals according to very selective criteria. • Detection: If you do not receive data, it may be because the Detection and 2D setting is too selective with the signal. Detection is less selective and allows more signals to be received. • Detection for Seiner: no need for this sensor
3	<ul style="list-style-type: none"> • Low: if the signal of the sensor is high = the trawl is close to the vessel (SNR min. 18 dB). • Medium: Default setting. Compromise between the two other settings (SNR min. 12 dB). • High: if the signal of the sensor is low = the trawl is far from the vessel (SNR min. 6 dB).
4	For each option, enter the same frequencies and telegrams as those entered in Mosa2.
5	Click Configure to change filters applied on incoming data.

Click **Apply** when you have finished.

Catch Explorer Pro



1	Sensor name displayed in Scala2 and its features. The version of the communication protocol must correspond to what was set in Mosa2.
2	This setting helps detecting the signal of the sensor among other sensor or echosounder signals. Change default setting only if you have issues receiving data. <ul style="list-style-type: none"> • Choose between 0 and 2 only if no interferences on the vessel (not recommended). • 3 is default setting. • Choose between 4 and 6 if you have issues receiving data. It allows you to receive more data, but be aware they might be wrong data.
3	This setting also helps detecting the sensor signal. Leave default setting at Synchro 1.
4	Enter the same frequency as the one entered for the uplink frequency in Mosa2.
5	Select the same sounding direction and range as those set in Mosa2.

6	<p>Click Configure to change filters applied on incoming data. Filters are particularly useful to reduce interferences on the echogram data.</p> <p> Note: Filters should not be necessary with a Digital spread sensor. However, if you notice interference, you can apply filters such as Some Smoothing, More Smoothing or Rate of Change.</p> <p> Tip: Please refer to Scala2 user guide for more information about the filters.</p>
7	Enter the same detection threshold as set in Mosa2.

Click **Apply** when you have finished.

What to do next

Configure the positioning settings if the sensor has the positioning option.

Configuring Data Display

In Scala2, you can display measurements taken by the sensors (e.g. catch status, depth, pitch and roll...).


About this task

Sensor measurements are displayed in the control panels, in **Mx** tab. Data title should be:

- **TE/CATCH** for a Catch Explorer
- **CATCH** for Catch sensors
- **PI-CATCH** for Catch hybrid PI sensors.

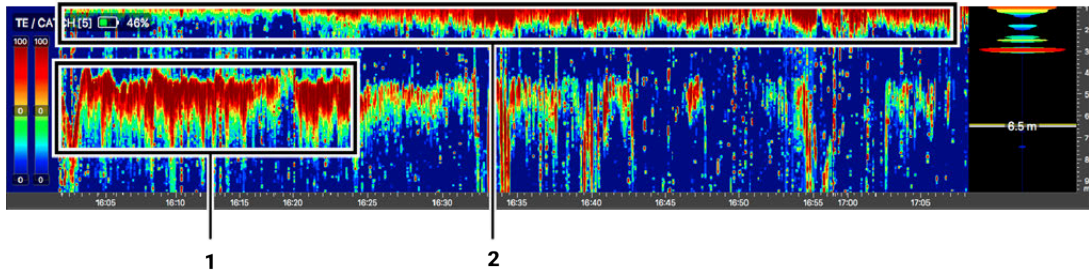
The title is followed by the node where the sensor was placed when added to the system. Data displayed (e.g. pitch & roll, temperature) depends on the firmware installed.

Procedure

1. From the top left corner of the screen, click **Menu**  > **Customize**.
2. To display echogram images of a Catch Explorer: from **TE/CATCH** in **Mx**, click + hold **Sonar Data** and drag it to the page display.



Below is an example of an echogram image.



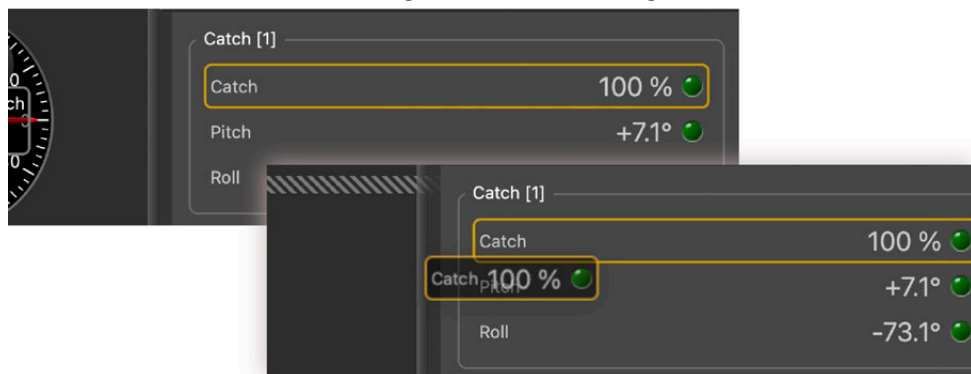
When the codend is not totally full, you can see the bottom of the sea (**1**). When the codend is filling up, you can see at the top that the echogram gets denser (**2**) and the sea bottom disappears. It is because fish can block the signal.

Note: When the trawl is empty, the codend moves a lot, as well as the sensors attached to it. You may not have correct echogram images at the beginning of a tow because the sensors are not correctly oriented toward the vessel. The codend and sensor become stable when the trawl begins to fill. The codend can move again when it is full.

Note: We recommend you to deactivate **Draw Bottom Line** option. Right-click the echogram to check if it is activated.

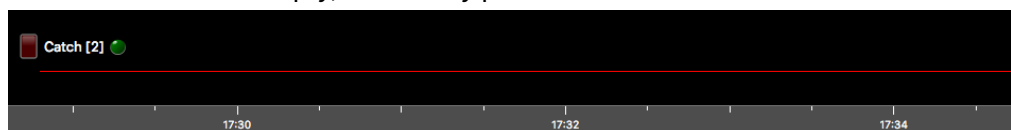
3. To know if the trawl is empty or full:

a. Open the control panels and drag **Catch** data to a page.

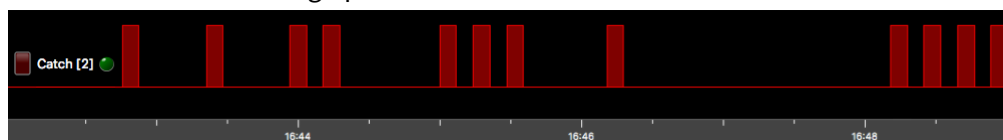


b. In the **Choose type of display** dialog box, select **History Plot**.

When the codend is empty, the history plot looks like this:



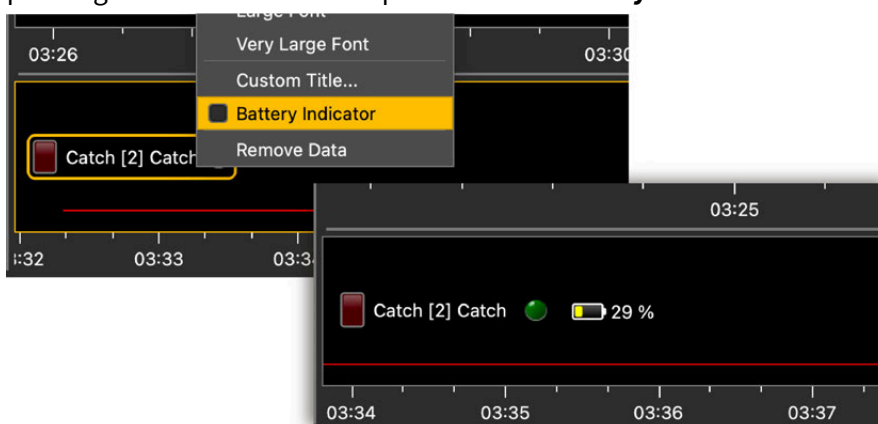
When the codend is filling up:




When the codend is full:




4. If you have a firmware version 08.03 and above, you can display the battery level on the plot. Right-click the title of the plot and click **Battery Indicator**.

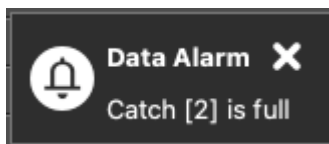


5. To be alerted when the trawl is full:
 - a. From the top left corner of the screen, click **Menu**  > **Settings**.
 - b. From the **Settings** dialog box, go to the **Alarms** tab.

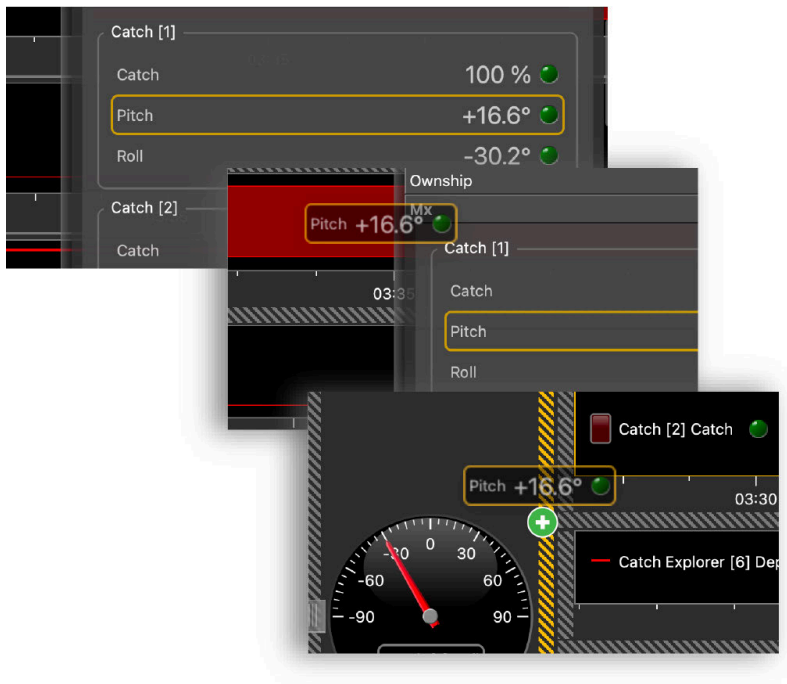
- c. Click **Add**.
- d. In **Alarm Data** and **Alarm Conditions**, enter the following settings:

 **Note:** If you have several Catch sensors, you can select other sensors from **Sensor / Trawl Part**.

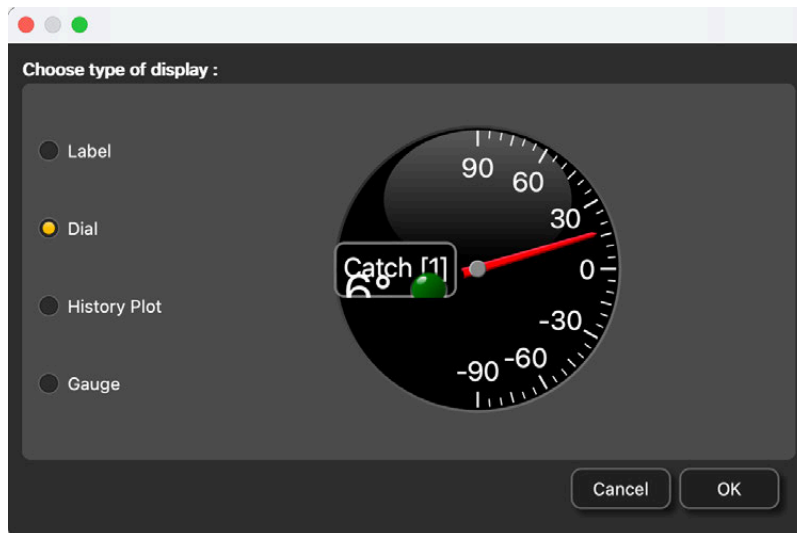
- a. In **Alarm Notifications**, choose if you want to display a visual and sound notification:



6. To display pitch and roll data, click + hold data and drag it to the page display.

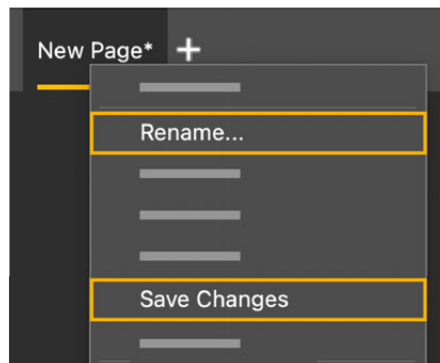



From **Choose type of display** dialog box, select the type of display.



7. To save the changes you made:

- a. To rename the page, right-click the name of the page and click **Rename**.
- b. To save the page, right-click the name of the page and click **Save Changes**.




8. Deactivate the Customize mode when you have finished customizing pages: click **Menu**  > **Customize** again.

Replaying Data Recorded on a Memory Card

In Scala2, you can replay data that has been recorded in high definition on the sensor memory card.

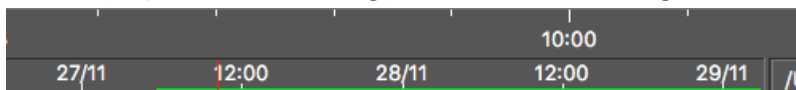
About this task

-  **Note:** Data in high definition is available only when downloading it from the sensor memory (A2S files). Data received in Scala2 will have a lower definition (SDS files).

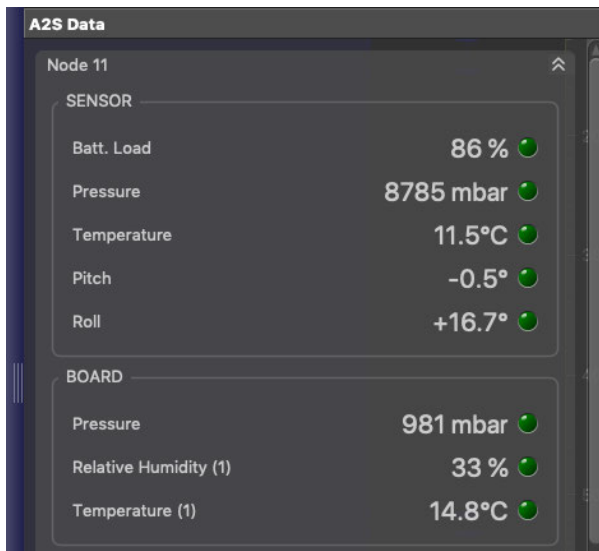
Procedure

1. Download from Mosa2 the files recorded on the sensor memory.
2. Right-click the timeline and click **Change Directory** to choose the source directory where the files are stored.

In the replay bar, the recording period of the files in high definition is displayed in green.



In the control panels, data that was received in live is displayed in the **Mx** panel and data recorded on the SD card is displayed in the **A2S Data** panel.



3. Go to the control panels, then click and drag data from the **A2S Data** panel to a page.

Installation

Learn how to install the sensor on the trawl gear.

Installing the Catch Sensors

You can install one or several Catch and Catch Explorer sensors on the codend of the trawl.

About this task

Sensors can be installed with the pull cords on the side or on the center of the sensor.

Pull cords are attached to the net. When the net fills up and the meshes expand, cords are pulled and this triggers the catch sensor.

You can install a stabilization board for Catch Explorer sensors.

Procedure

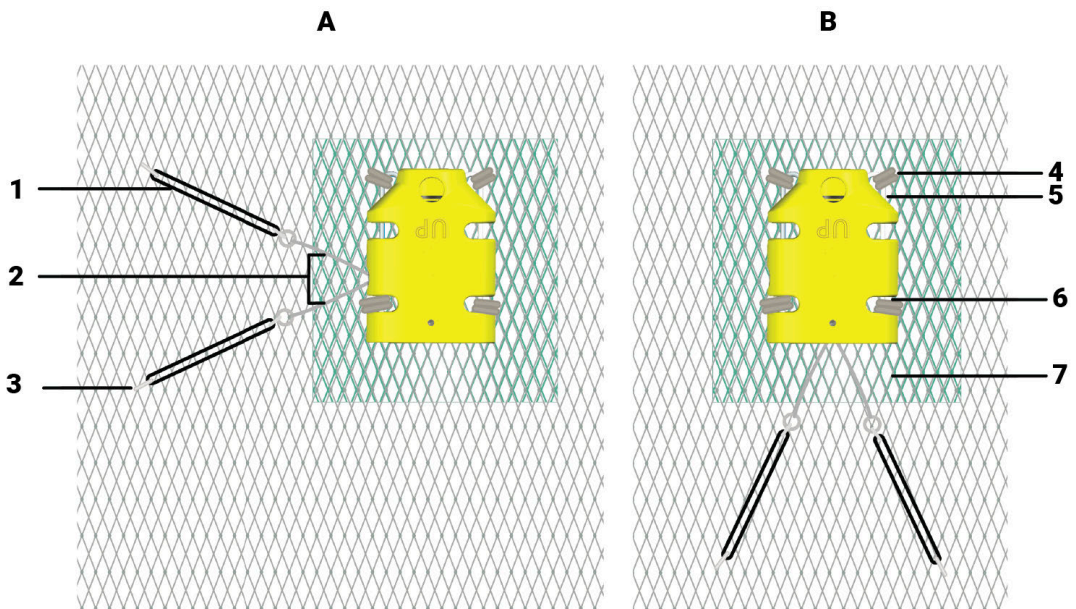
1. Install the sensor on the top of the codend with the **UP** side of the housing oriented toward the vessel. You can install a double-mesh piece of netting to stabilize the sensor. Make sure there is nothing in front of it that would block its signal.



Tip: If the meshes of the net obstruct the Catch Explorer Pro signal, you can install the sensor inside the codend.

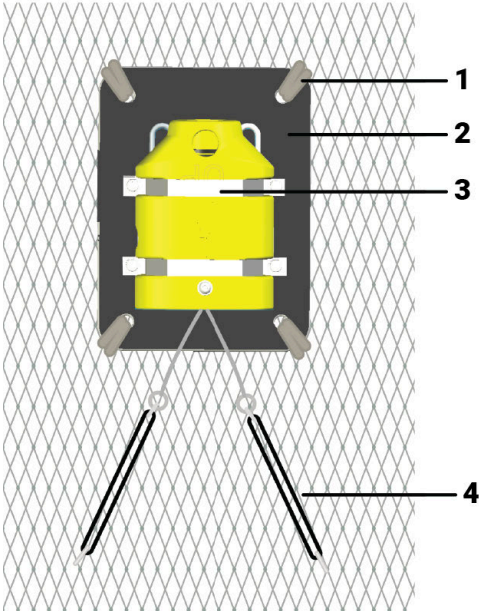
2. Securely attach the sensor to the net by its front and back attachment lugs:
 - a. We recommend to attach the front and back attachment lugs with rope. This prevents metal to metal contact and extends the life of the housing.
 - b. When you attach the sensor, stretch the net codend at the point where you need the catch status to become full.
 - c. Once installed, make sure that when the net is fully stretched out it does not cause stress on the attachments points.
3. If you use a stabilization board:
 - a. Put the mounting straps through the lugs on the sides.
 - b. Attach the stabilization board with rope to prevent rapid wear on the board.

4. Attach one end of each rubber strap to the pull cords of the sensor, and the other ends to the net. Make sure the pull cords are taut enough to trigger when the net is full, but loose enough not to trigger when the net is empty.



- | | | | |
|---------------------|---|-----------------------|---|
| A. Side-pull | <ul style="list-style-type: none"> 1. Rubber strap 2. Pull cords 3. Snap hook | B. Center-pull | <ul style="list-style-type: none"> 4. Knot with rope 5. Front attachment lug 6. Back attachment lug 7. Double-mesh piece of netting for stabilization |
|---------------------|---|-----------------------|---|

Catch Explorer:

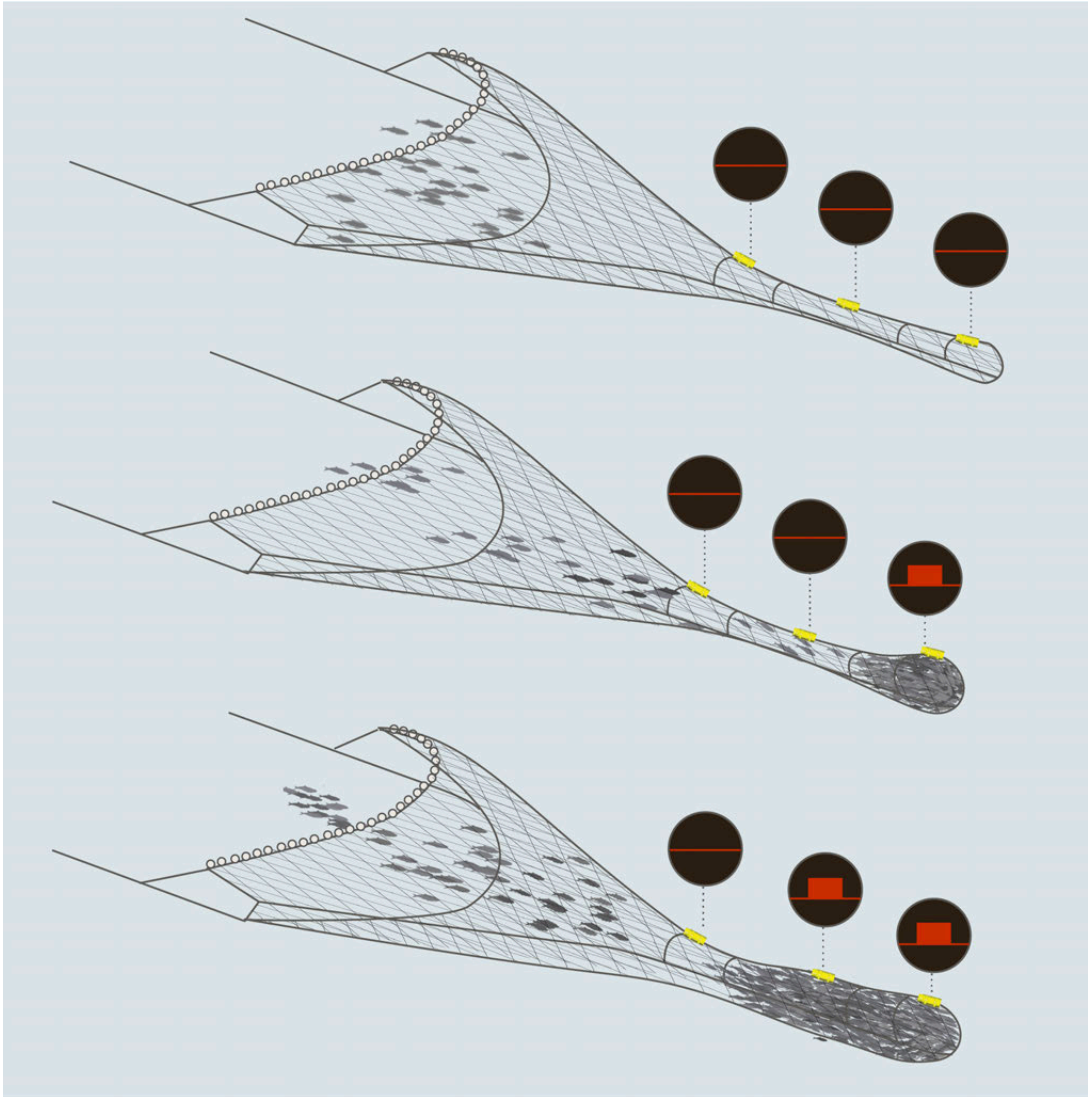


- 1. Knot with rope
- 2. Stabilization board
- 3. Mounting strap
- 4. Rubber strap

Example of installation.




5. Install several sensors on the codend to better follow the filling processes. The sensors will trigger one by one, according to the amount of fish inside the codend. After a few tows, you can estimate the amount of tonnage of fish that you have depending on whether one, two or three sensors display a full status.



Maintenance and Troubleshooting

Read this section for troubleshooting and maintenance information.

-  **Important:** Only an approved Marport dealer can access the internal unit. Warranty will become void if anyone other than an approved dealer tries to do internal maintenance duties on the product.




Charging the Sensor with the Dock

Connect a sensor to one of the 4 charging connectors of the Dock to display its level of charge.


Before you begin

- Make sure the Dock is connected to a power supply and turned on.

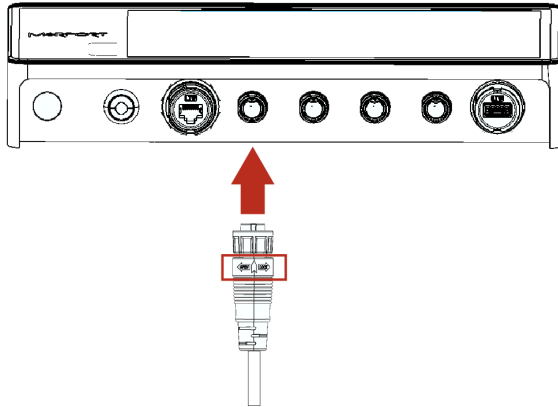
About this task

-  **Warning:** In case of water ingress in the product, do not charge it: battery may vent or rupture, causing product or physical damage.
-  **Note:** For Dock products with serial number before DOC2400000: Do not leave the sensors connected on a charger that is switched off. If the charger is not connected to the mains voltage, the sensor switches on and this will drain the battery.
-  **Note:** Avoid full discharges and charge the battery whenever possible, at any battery level. Lithium-ion batteries do not have a charge memory, so they do not need full discharge cycles.

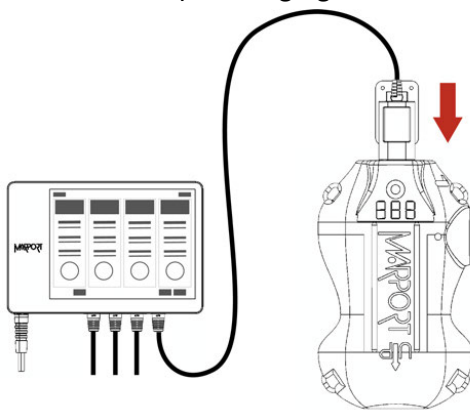
Procedure

1. Before charging the sensor: wash with fresh water and dry the sensor. This prevents corrosion of the charging pins.
 -  **Important:** Check that the charging pins are not damaged. If they are, contact you local Marport dealer for replacement.

2. Connect the charger plug to one of the 4 charging ports.



3. Connect the 3-pin charging connector to the sensor charging pins.



Results

The Dock screen and Virtual Charger Room display the state of charge of the sensor.


Cleaning the Sensor


You need to regularly clean the sensor for proper performance.

Wash the sensor with fresh water and dry it before you charge or store it.

Regularly check that the sensor is clean. If not:

- Wash away mud or debris with warm water.
- Use Isopropyl alcohol to clean the end cap and transducer. Use a steel wool pencil to clean the shoulder bolts, and very fine sandpaper (180 grit) to clean between them.

 **Notice:** Do not use highly abrasive materials or jet wash.

 **Notice:** Special care should be taken with sensors and components sensitive to mechanical shock or contamination.

Maintenance Checklist

We recommend you to follow this maintenance schedule for better performance and to avoid any trouble with the equipment.

Before use	<ul style="list-style-type: none">• Check that all attachment equipment are not worn or torn. Replace when appropriate.• Check that the sensor is clean. See Cleaning the Sensor (on page 62) for cleaning procedures.• Check the battery level 24 hours before use and recharge if necessary.
After use	Wash the sensor with fresh water.
Between uses	When the sensor is not in use, store in a dry area, without humidity, at a temperature between -10° and 70 °C (14 to 158 °F).
Not used for more than 3 months	<ul style="list-style-type: none">• Do not leave the batteries at full charge or discharged for a long period of time or they will wear out.• Every 6 months, put the sensor in charge for less than an hour.
Every 2 years	The sensor must be returned to an approved Marport dealer for inspection and maintenance.

If the sensor has not been not used for more than 3 months, we highly recommend to check the following points before using it:


- Make sure the sensors on the end cap are in good condition and clean.
- Connect the sensor to a charger and check the charging status.

- Switch on the sensor by activating the water-switch, then listen for a ping noise and check if you see the LED switched on.
- Test the sensor measures with Mosa2: depth, temperature, pitch, roll, and if applicable: spread distance, echogram, catch status, speed measures (using the EM log tester).
- If you have a test hydrophone, check the reception in the wheelhouse with Scala2.


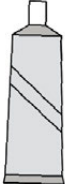
Replacing the Pull Cords

You can replace the catch pull cords when they are worn out or damaged.

Before you begin

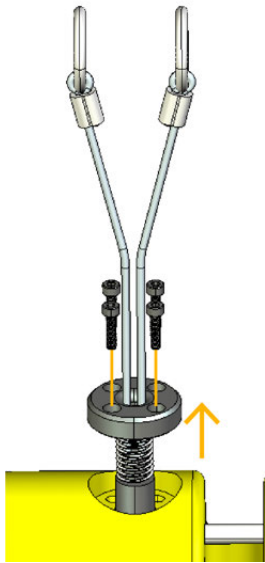
 **Note:** Only qualified Marport technicians can do this task.

For this task you need the following tools:

	
9/64" Allen key	Anti-seize

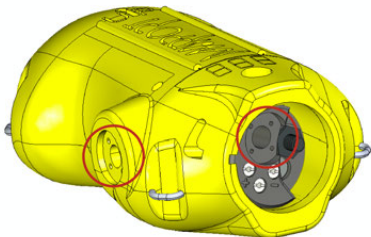
Procedure

1. Remove the old pull cords.



- a. Remove the four screws on the pull cord assembly with a 9/64 size Allen key.
- b. Remove the cords, spring and magnet from the hole.

2. Install the new pull cords.




- a. Install the new pull-cord assembly on the side or on the end cap of the sensor.
- b. Apply anti-seize on the four screw threads, then tighten the screws with the 9/64 size Allen key.


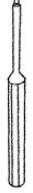
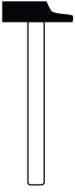

Replacing the Catch Magnet

You can replace the magnet that is part of the pull cord assembly when the magnet is broken.

Before you begin

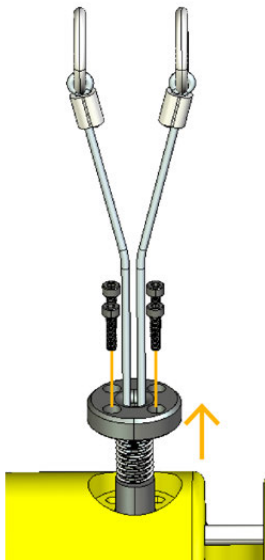
 **Note:** Only qualified Marport technicians can do this task.

For this task you need the following tools:

			
9/64" Allen key	Drift punch / pliers	Arbor press / hammer	Anti-seize

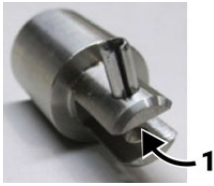
Procedure

1. Remove the old pull cords.



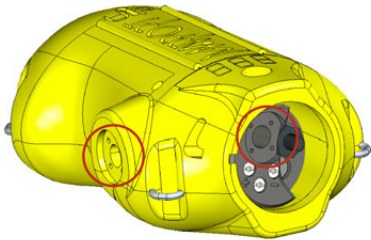
- a. Remove the four screws on the pull cord assembly with a 9/64 size Allen key.
- b. Remove the cords, spring and magnet from the hole.

2. If the pull-cords are in good condition, only replace the magnet.



- a. To remove the old magnet, remove the pin between the arms of the magnet using a drift punch or pliers.
- b. Slide the rope end between the arms of the new magnet with the pin facing up **(1)**.
- c. Install the pin down through housing arms to secure rope in place. You can use an arbor press or hammer.
- d. Check that the rope is not pinched between the pin and housing arms and that the pin does not interfere with the spring.

3. Install the new pull-cord assembly.



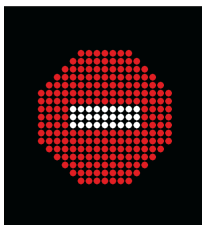
- a. Put the new pull-cord assembly in the hole on the side or end cap of the sensor.
- b. Apply anti-seize on the four screw threads, then tighten the screws with the 9/64 size Allen key.

Troubleshooting

Learn how to solve common problems.

Warning icon on the Dock charger plug

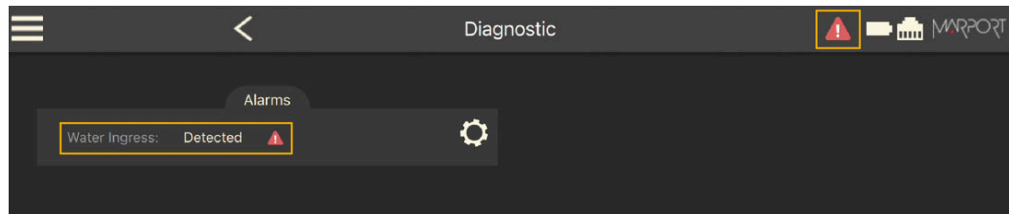
The sensor is not detected by the Dock and there is a warning icon on the Dock charger plug.



- The shoulder bolts are dirty or damaged.
 - Clean them using a swab or Q-tip with Isopropyl alcohol.
 - Fully clean the surface from debris and inspect the surface for burrs or pitting.
 - If not taken care of, there is a risk of short circuit.

- If you have inspected the shoulder bolts and the problem persists, it means water may have leaked into the sensor.

- Connect the sensor to Mosa2 to check if there is a diagnostic alarm:
 1. Connect the sensor to a Dock charger plug or connect a Configuration Cable from the computer to the sensor, and open Mosa2.
 2. From Mosa2, go to the **Diagnostic** page and check the alarms.



- If there is an alarm or if the sensor is not detected by Mosa2, disconnect it from the Dock and do not charge it until it is inspected by a technician.
- Send the sensor back for servicing to a Marport office.

! **Important:** Only Marport technicians can open the sensor to access the internal components.

! **CAUTION:** In case of water ingress into the sensor, battery may vent or rupture, causing product or physical damage.

Mosa2 does not open due to error message


Mosa2 displays an error message saying it cannot be opened.

→ Your Mac security preferences do not allow you to open applications not downloaded from the App Store.

1. From the upper left corner of the screen, click **Apple menu > System Preferences > Security & Privacy**.
2. Click the lock icon and enter the password, if applicable.
3. At **Allow apps downloaded from**, select **Anywhere**, then close the dialog box.
4. **macOS Sierra or later:** **Anywhere** option is not displayed by default. To display **Anywhere**:
 - a. Click the magnifying glass from the top right corner of your screen and type `Terminal`.
 - b. Click **Terminal** from the results.
 - c. Enter in the terminal: `sudo spctl --master-disable`.
 - d. Press Enter.

Anywhere option is now displayed in **Security & Privacy** preferences.

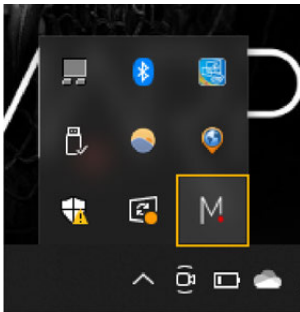
Sensor does not connect correctly with Mosa2 when using the Configuration Cable


 **Remember:** If the sensor does not connect correctly with Mosa2, always:

- Disconnect both USB connector and three-pin plug.
- Connect again the Configuration Cable.
- Make sure the three pins are fully inserted inside the sensor.

→ Mosa2 does not automatically open when connecting the Configuration Cable.

- Check that you see Marport Captain icon in the desktop taskbar. If you do not see it: close, then open Mosa2. The icon should appear in the taskbar.



 **Note:** Marport Captain is a program running in the background. It allows Mosa2 automatic opening and displays shortcuts to Mosa2 and Scala2 applications installed on the computer. It should not be closed.

- If the problem persists, install Mosa2 again.

→ At the end of step 2 of the startup wizard, the sensor does not respond. Mosa2 displays a red cross and the Configuration Cable LED is red.

- Check that no other instance of Mosa2 application is already running on the computer. If this is the case, close both applications, then open only one.
- Or else, connect the sensor to a charger and wait until it is fully charged.

→ The sensor has been disconnected from Mosa2.

- Check that the Configuration Cable is not connected to a USB hub. The Configuration Cable must be connected directly to the computer.
- If the computer goes to sleep mode, the sensor may be disconnected. Change the settings on your computer to increase the time before sleep mode.
- If the problem persists, connect the sensor to a charger and wait until it is fully charged. Then try again to connect.

→ Mosa2 displays a critical error message.

- Disconnect both USB connector and three-pin plug. Then, connect again the Configuration Cable. If the message is still displayed, it means there is an issue with the sensor's components. Contact Marport support.

The sensor is not running when testing out of water

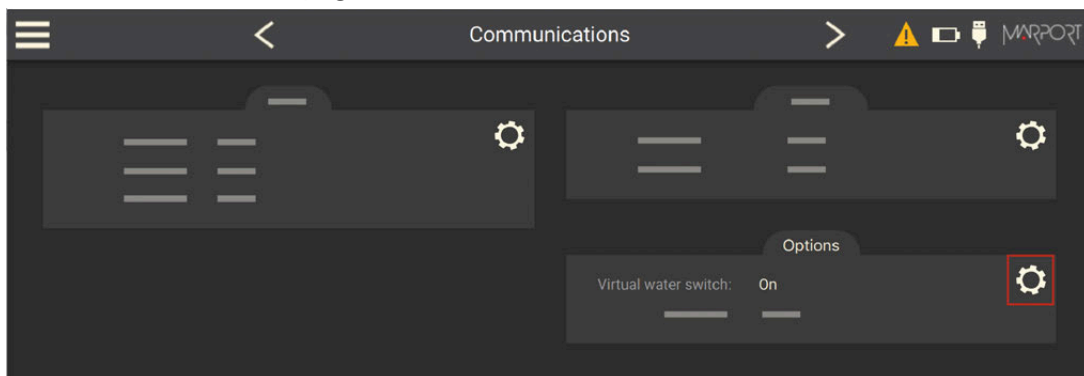
You activated the sensor water switch outside water or in a low level of water (for example for testing purpose) but it does not switch to running mode and does not emit any data.

→ The virtual water switch option may be activated in Mosa2. When this option is activated, the sensor runs only at a depth more than 2 meters. For more details, read **About the Virtual Water Switch Option (on page 23)**.

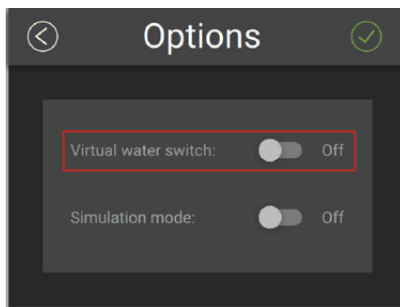
1. Connect the sensor to Mosa2 and check if there is an orange warning sign at the top of the window. If yes, it means the virtual water switch is on.



2. Go to **Communications** page, then in **Options**, click .



3. Deactivate the **Virtual water switch** option.



Support Contact

You can contact your local dealer if you need maintenance on your Marport products. You can also ask us at the following contact details:

FRANCE

Marport France SAS
8, rue Maurice Le Léon
56100 Lorient, France
supportfrance@marport.com

ICELAND

Marport EHF
Tónahvarf 7
203 Kopavogur, Iceland
supporticeland@marport.com

NORWAY

Marport Norge A/S
Breivika Industrivei 69
6018 Ålesund, Norway
supportnorge@marport.com

SOUTH AFRICA

Marport South Africa
Cape Town, Western Cape
11 Paarden Eiland Road
Paarden Eiland, 7405
csanter@marport.com

SPAIN

Marport Spain SRL
Camino Chouzo 1
36208 Vigo (Pontevedra), Spain
supportspain@marport.com

UNITED KINGDOM

Marport UK Ltd
32 Wilson Street
Peterhead, AB42 1UD, United Kingdom
gyoungson@marport.com

USA

Marport Americas Inc.
12123 Harbour Reach Drive, Suite 100
Mukilteo, WA 98275, USA
supportusa@marport.com

Appendix

Frequency Plan

It is important to carefully plan the setup of your sensors before adding them to the system. You can create a table with a list of frequencies and complete it when you add sensors.

Boat & Channel Codes

This list shows the standard frequencies for PRP telegrams. When you configure boat codes, make sure to respect the correct interval between frequencies (see table above).

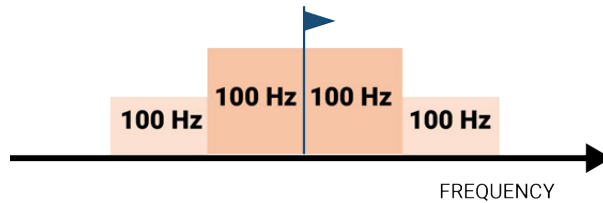
Codes		
BC/CH	Frequency	FID (Scanmar)
C-1/CH1	42833	45
C-1/CH2	41548	32
C-1/CH3	41852	35
C-1/CH4	40810	25
C-1/CH5	42500	42
C-1/CH6	43200	49
C-2/CH1	42631	43
C-2/CH2	41417	31
C-2/CH3	41690	33
C-2/CH4	40886	26
C-2/CH5	42300	40
C-2/CH6	43100	48
C-3/CH1	42429	41
C-3/CH2	41285	30
C-3/CH3	41548	32
C-3/CH4	40970	27
C-3/CH5	42100	38

C-3/CH6	43000	47
C-4/CH1	42226	39
C-4/CH2	41852	35
C-4/CH3	41417	31
C-4/CH4	41160	29
C-4/CH5	42700	44
C-4/CH6	43300	50
C-5/CH1	42024	37
C-5/CH2	41690	33
C-5/CH3	41285	30
C-5/CH4	41060	28
C-5/CH5	42900	46
C-5/CH6	43400	51
C-6/CH1	39062	3
C-6/CH2	39375	7
C-6/CH3	39688	11
C-6/CH4	40000	15
C-6/CH5	40312	19
C-6/CH6	40625	23
C-7/CH1	38906	1
C-7/CH2	39219	5
C-7/CH3	39531	9
C-7/CH4	39844	13
C-7/CH5	40156	17
C-7/CH6	40469	21

Frequencies and intervals

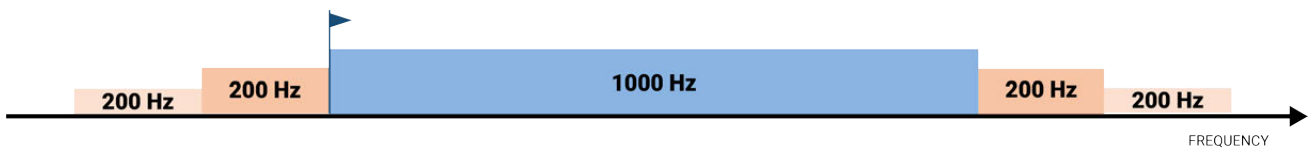
The diagrams below show the bandwidth of the different types of Marport sensors and intervals you must respect when adding other sensors.

PRP sensors (e.g. Catch sensor, Trawl Speed, Spread sensor...)



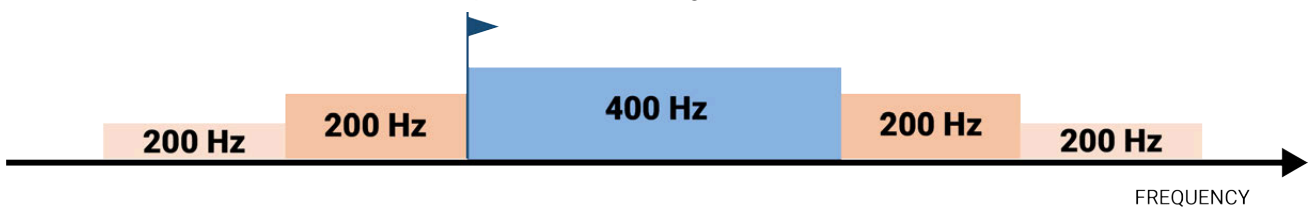
Example: If the frequency of the sensor is 40kHz, there should be no sensors between 39.9 and 40.1kHz.

Marport Pro sensors (e.g. Trident, Door Explorer, all Navigator range except Catch)



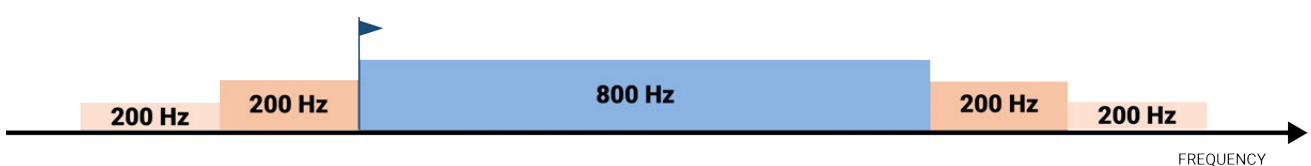
Example: If the frequency of the sensor is 40kHz, there should be no sensors between 39.8 and 41.2kHz.

NBTE sensors (e.g. Speed Explorer, Trawl Explorer, Catch Explorer, Catch Navigator, Door Sounder)

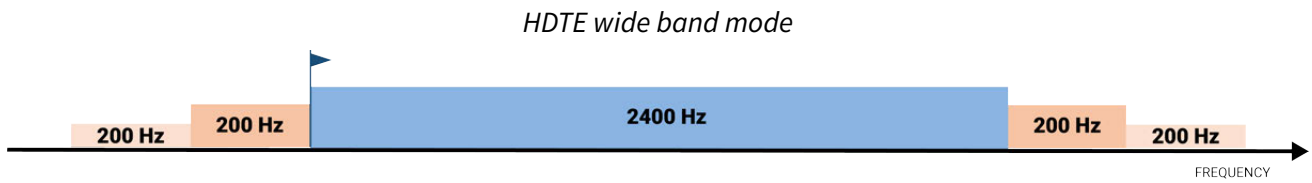


Example: If the frequency of the sensor is 40kHz, there should be no sensors between 39.8kHz and 40.6kHz.

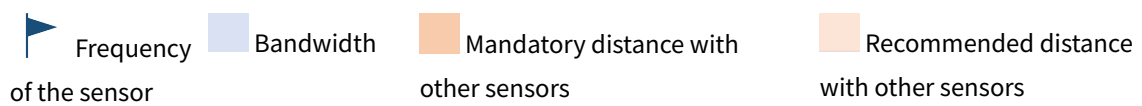
HDTE narrow band mode



Example: If the frequency of the sensor is 40kHz, there should be no sensors between 39.8kHz and 41kHz.



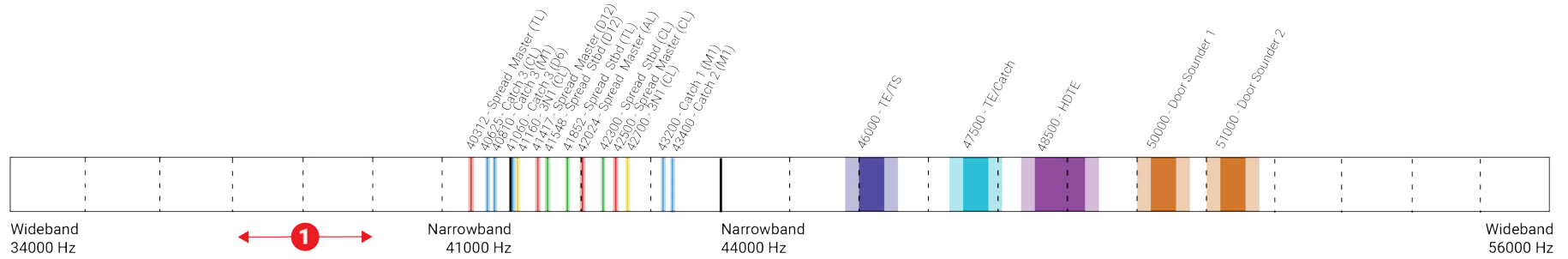
Example: If the frequency of the sensor is 40kHz, there should be no sensors between 39.8kHz and 42.6kHz.



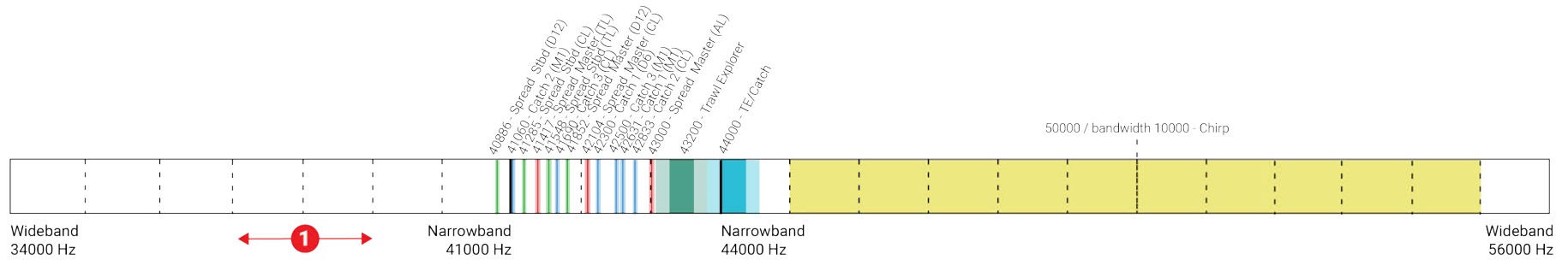
Examples of frequency allocations

- We recommend to allocate frequencies between 34 and 56 kHz for wideband hydrophones and between 41 kHz and 44 kHz for narrowband hydrophones.
- Echosounders are usually placed around 38 kHz, make sure to allow enough distance with them.

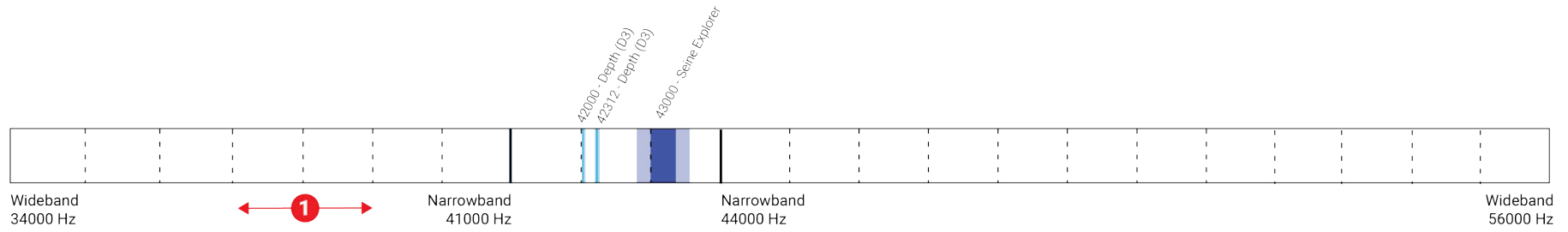
Example of a system with Spread, Catch, Trawl Speed sensors and Speed Explorer, Catch Explorer, HDTE and Door Sounder.




Example of a system with Spread sensors with positioning, Catch sensors, Trawl Explorer and Catch Explorer.



Example of a system for purse seining, with a Seine Explorer and depth Seine sensors.



 Bandwidth

 Mandatory distance with other sensors

1 Avoid allocating frequencies between 37 and 39 kHz because this range is generally used by echosounders.

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