

MARPORT | PRO

**SPEED PRO
SENSORS**

2024

USER MANUAL



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Legal

History

| | | |
|----|----------|---------------|
| V1 | 09/27/24 | First release |
|----|----------|---------------|

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:

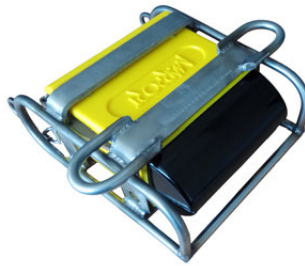
- Mosa2: 02.13.x
- Scala2: 02.14.x

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

Introduction and Presentation

Get a basic knowledge of the sensor.

Introduction



The **Speed Pro** sensors 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 speed sensor family includes two categories of sensors:

- The **Flow sensors**, that include the **Trawl Speed** sensor and **Grid** sensor.
- The **Speed Explorer Pro**.

They all track pitch and roll data. Each of them has different functions and purposes.

The Grid sensor is placed on the grid of a trawl. It tells you if the grid does its job: selecting out the unwanted catch while target species enter the codend. It monitors the angle of the grid and the flow of water passing through it. This way, you know if the grid is twisted or blocked and you can fix the problem before losing significant catches.


The Trawl Speed sensor can be placed on the headrope. It measures water flow in two axis: the flow along the direction of the trawl and across it. You can control if the trawl is moving at the right speed and with the right geometry. It measures along speed up to 6 knots and cross currents speed up to 3 knots.

Finally, the Speed Explorer has the functions of a Trawl Speed sensor and a Trawl Explorer sensor combined. Placed on the headrope or tunnel, it measures water flow along the direction of the trawl (up to 10 knots) and across it (up to 3 knots) and displays an echogram. This way, you can see fish passing through the trawl and have an overview of the trawl opening and the

effects of the currents around it. It also tracks pitch & roll, depth and temperature data. Data is received more often than with the other speed sensors.

Speed Pro sensors are compatible with Scantrol software.

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

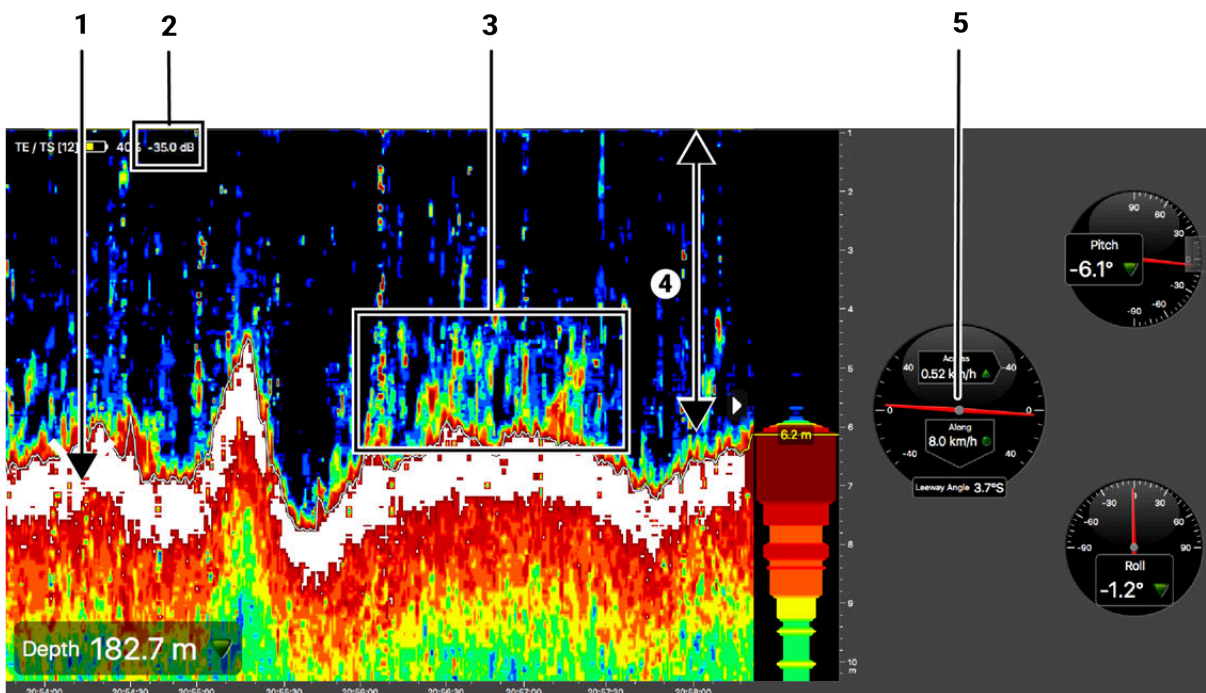
Here are some examples of data received from Grid, Trawl Speed and Speed Explorer sensors and displayed in Scala2.

Grid sensor display



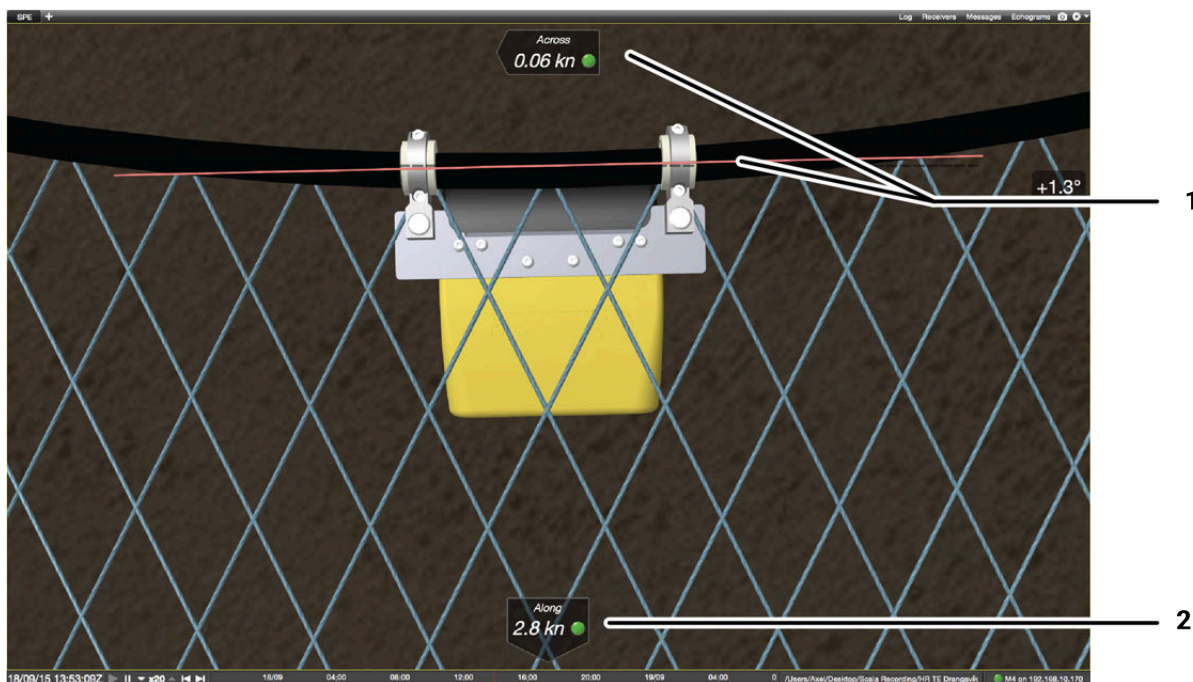
1. Control the angle of the grid (45°).
2. Check the water flow to know if the grid is blocked.

Speed Explorer display



1. Seabed / 2. Target strength (only for V3 version of sensors) / 3. Haddockes / 4. Trawl opening / 5. Trawl Speed dial: displays water across and along speeds.

Trawl Speed 3D view



1. Control if the trawl opening has the correct angle. Across speed needs to be around 0.
2. Control the speed of the water along the trawl, and adjust your speed according to the currents.

Description

System Compatibility

The Speed 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

Trawl Speed & Grid Sensors

| | |
|---|--|
| Uplink frequency | 30 to 60 kHz |
| Range to vessel | up to 2500 m ¹ |
| Data update rate | Along/across speed: trawl speed and grid max. every 14 sec. - Pitch&Roll: 8 to 15 sec. (depends on settings) |
| Depth range | up to 1800 m |
| Depth resolution | 0.1m with 0.1% accuracy |
| Pitch angle | ±90° |
| Roll angle | ±180° |
| Pitch & roll accuracy | ±0.1° |
| Temp measurement range | -5° C to +25° C |
| Temp accuracy | ±0.1° C |
| Across speed range | Up to ± 3 knots |
| Along speed range | Up to ± 6 knots |
| Speed resolution | 0.1 knot |
| Across and along speed accuracy | ±0.1 knot |
| Typical battery life | Up to 80 hours ² |
| Charging time | 4 hours ³ |
| Battery type | Lithium-Ion |
| Weight of Trawl Speed (sensor + protection cage) in air | 22.4 kg |
| Weight of Trawl Speed (sensor + protection cage) in water | 13 kg |
| Weight of Grid sensor and protection cage in air | 19 kg |
| Weight of Grid sensor and protection cage in water | 11.3 kg |
| Warranty | 2 years (Sensor & Battery) ⁴ |

Speed Explorer

| | |
|---|---|
| Uplink frequency | 30 to 60 kHz |
| Range to vessel | up to 2500 m ¹ |
| Sounder broadband frequency | Configurable between 120-210 kHz |
| Sounder range | 5 to 160 m |
| Data update rate | Depth: 1-8 sec. - Temp/Battery/Altitude/Pitch&Roll: every 6 sec. - Along/Across speed: every 7 sec. |
| Echogram update rate | Up to 3 images per second |
| Pitch angle | ±90° |
| Roll angle | ±180° |
| Pitch & roll accuracy | ±0.1° |
| Depth resolution | 0.1m with 0.1% accuracy |
| Temp measurement range | -5° C to +25° C |
| Temp accuracy | ±0.1° C |
| Across speed range | Up to ± 3 knots |
| Along speed range | Up to ± 10 knots |
| Speed resolution | 0.1 knot |
| Across and along speed accuracy | ±0.1 knot |
| Typical battery life | Up to 50 hours ² |
| Charging time | 4 hours ³ |
| Battery type | Lithium-Ion |
| Weight of sensor + protection cage in air | 22.4 kg |
| Weight of sensor + protection cage in water | 13 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

Speed Explorer Beamwidths

Beamwidths for Uplink pings:

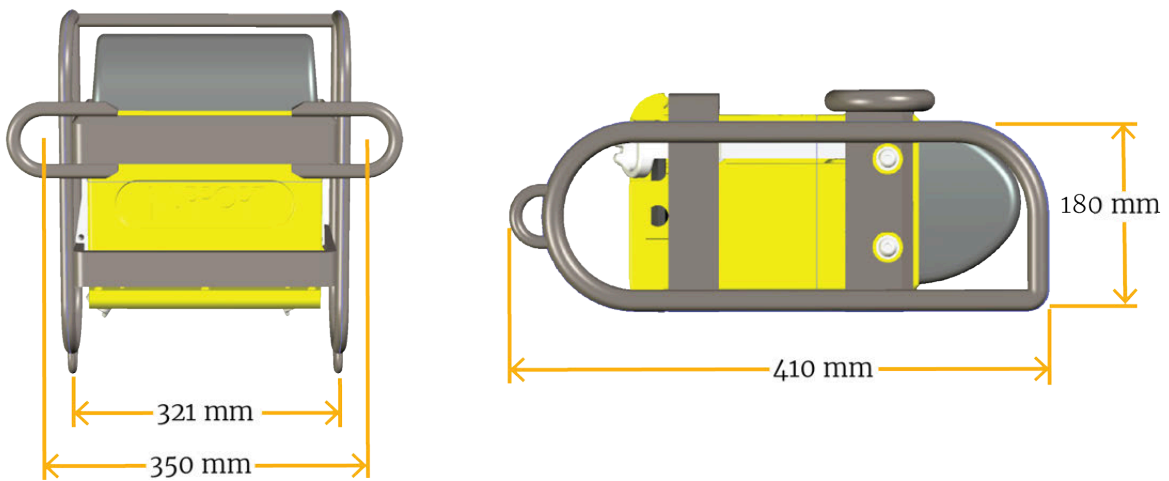
| Beamwidth | @ 35 kHz | @ 50 kHz | @ 60 kHz |
|-----------|----------|----------|----------|
| -3dB | 46° | 40° | 30° |

Beamwidths for Up and Down pings:

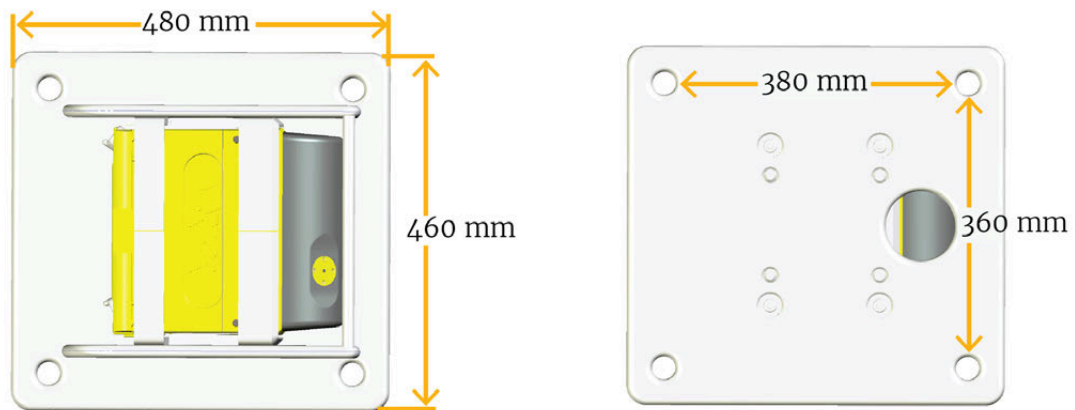
| Beamwidth | @ 125 kHz | @ 160 kHz | @ 200 kHz |
|-----------|-----------|-----------|-----------|
| -3dB | 26° | 24° | 22° |

Outline Dimensions

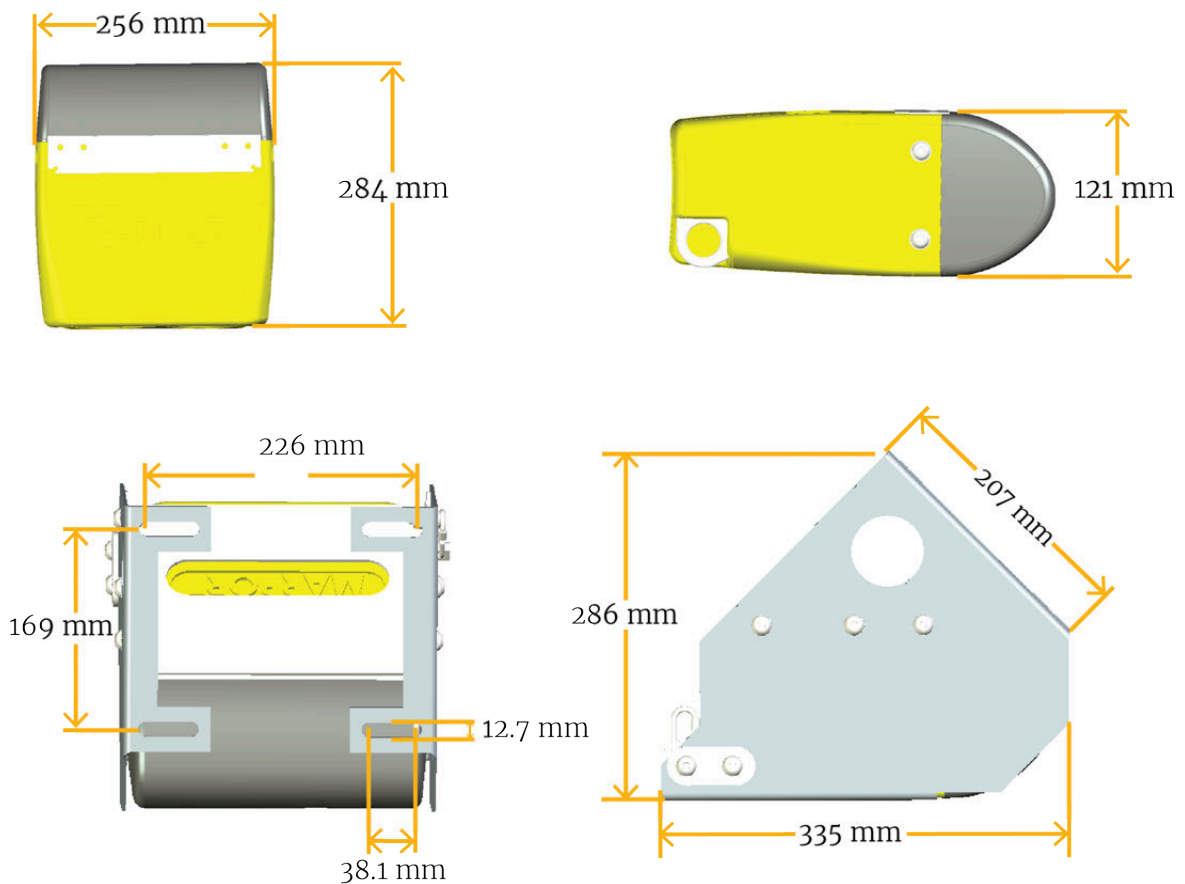
Trawl Speed and Speed Explorer sensors



Speed Explorer with a board for inverted installation



Grid sensor



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.

Speed Explorer

| | |
|-------------------------|---|
| Features | <ul style="list-style-type: none"> • Product name: manually entered. • Application: Trawl Speed Explorer / Trawl Speed Explorer Reversed • Body: Tets • Battery capacity (not configurable): 2-pack |
| Sounding Options | <ul style="list-style-type: none"> • Down (always activated) • Up • 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) • Pressure • Temperature • Pitch • Roll • Along Speed (always activated) • Across Speed (always activated) |

Trawl Speed

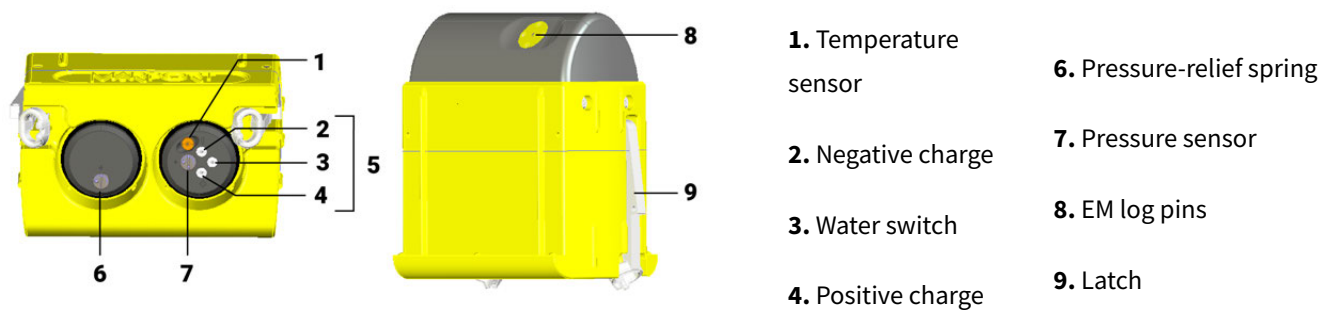
| | |
|-----------------|--|
| Features | <ul style="list-style-type: none"> • Product name: manually entered. • Application: Trawl Speed • Body: Tets • Battery capacity (not configurable): 2-pack |
| Measures | <ul style="list-style-type: none"> • Battery (always activated) • Pitch • Roll • Along Speed (always activated) • Across Speed (always activated) |

Grid Sensor

| | |
|-----------------|--|
| Features | <ul style="list-style-type: none"> • Product name: manually entered. • Application: Trawl Speed • Body: Tets • Battery capacity (not configurable): 2-pack |
| Measures | <ul style="list-style-type: none"> • Battery (always activated) • Pitch • Roll • Grid Angle (always activated) • Across Speed (always activated) |

Main Parts

External View



5. Shoulder bolts



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.


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

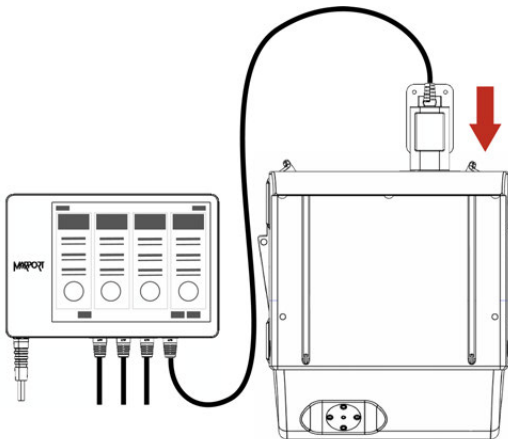
To configure the sensor, you need to connect it to Mosa2 application, using either the Dock or the Configuration Cable.

Using a Dock Charger Plug

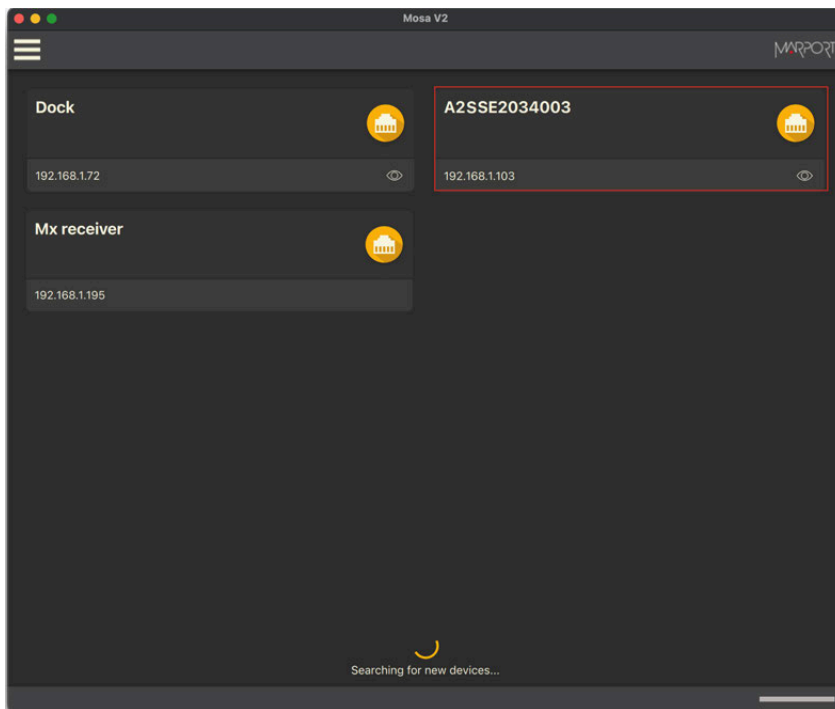




Tip: Refer to Dock user manual to have more details about the use of this product.

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.

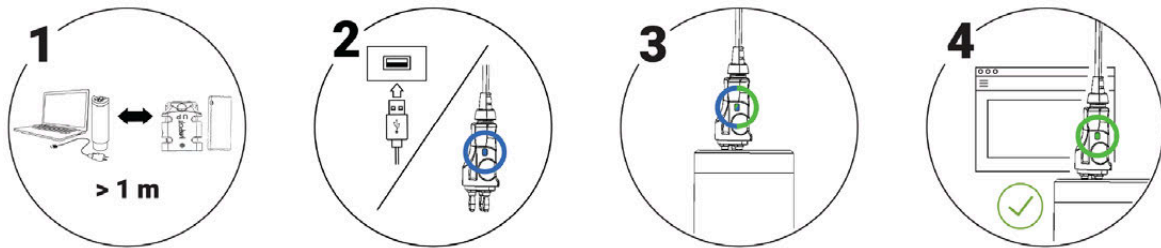
Using the Configuration Cable

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





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

1. Move other electrical devices minimum 1 m away from the computer.
Mosa2 opens automatically and the startup wizard is displayed. The LED on the plug is solid blue.
2. Connect the USB connector directly to the computer.
The LED on the plug blinks alternatively blue and green.
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.

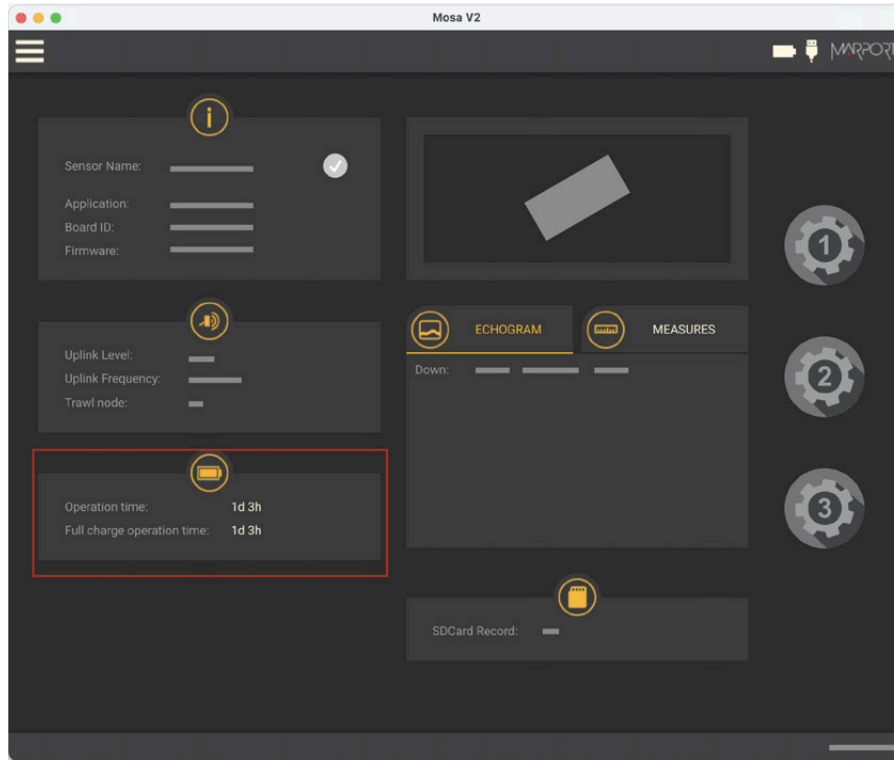


You can now configure the sensor.

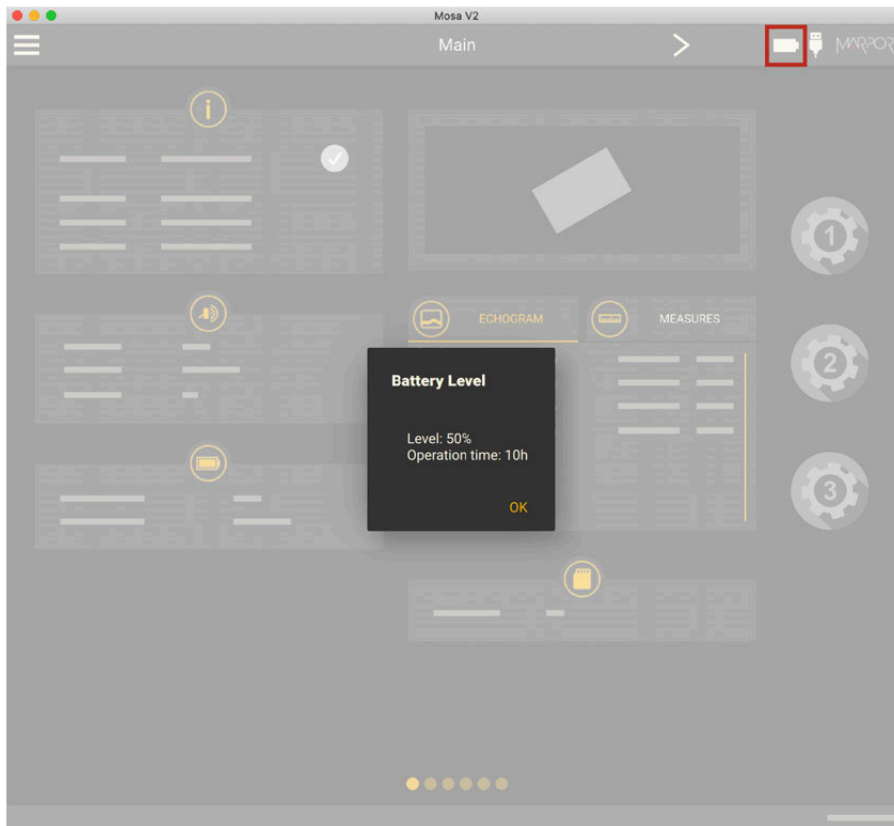
-  **Note:** You can keep the Configuration Cable continuously connected by USB, and virtually eject or connect it. When no sensor is connected to the Configuration Cable, click **Menu**  > **Eject Config Plug** or **Connect Config Plug**. When ejected, you come back to the discovery page. It stays disconnected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

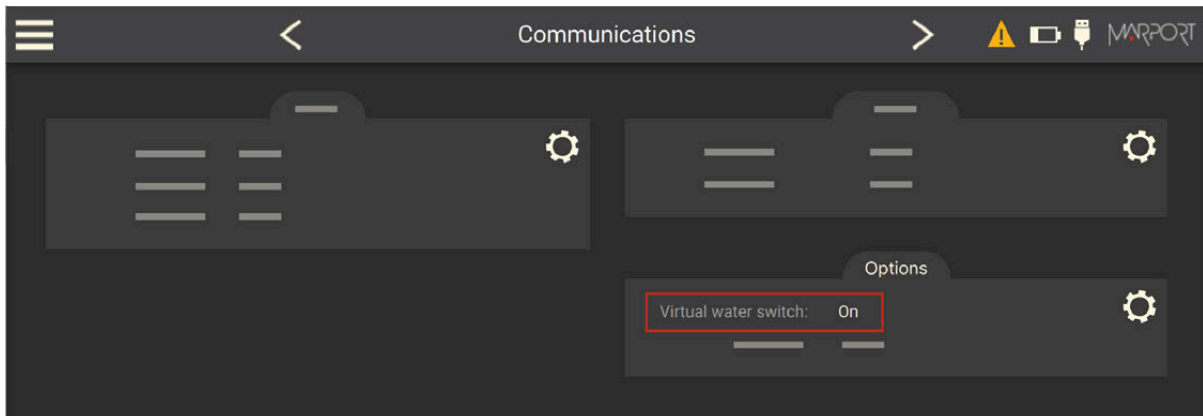


-  **Note:** When you change settings such as the uplink power or sounding range, it affects the battery consumption and remaining lifetime. The battery information will update after the sensor has been switched on and operating for 10 minutes.

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.

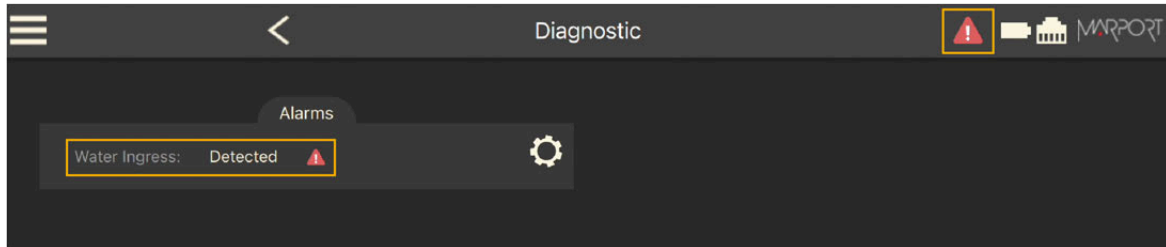
We recommend to deactivate it if the sensor is operating close to the surface or if you need to test the sensor in the office.

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

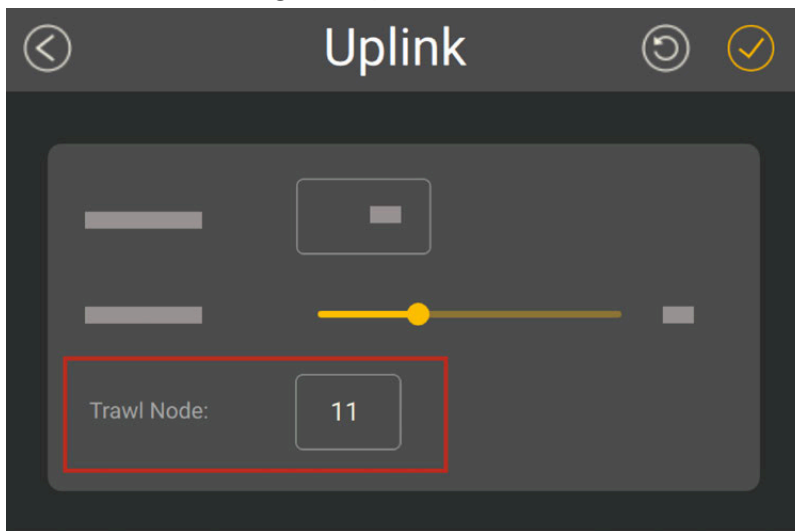
You need to give a trawl node to the sensor. It is the number corresponding to the position of the sensor on the trawl.


The trawl nodes corresponding to the positions on the headline (Speed Explorer, Trawl Speed), tunnel (Speed Explorer) and back of the trawl (Grid sensor) are the following:

| Type of sensor | Node numbers (trawl 1 / 2 / 3 / 4 / 5) |
|----------------|--|
| Speed Explorer | <ul style="list-style-type: none">• Headrope: 10, 11, 12, 13 / 110, 111, 112, 113 / 210, 211, 212, 213 / 310, 311, 312, 313 / 610, 611, 612, 613• Tunnel: 7, 8, 9 / 107, 108, 109 / 207, 208, 209 / 307, 308, 309 / 607, 608, 609 |

| Type of sensor | Node numbers (trawl 1 / 2 / 3 / 4 / 5) |
|----------------|---|
| Trawl Speed | • Headrope: 10, 13 / 110, 113 / 210, 213 / 310, 313 / 610, 613 |
| Grid | • Back of trawl: 5, 6, 7, 8 / 105, 106, 107, 108 / 205, 206, 207, 208 / 305, 306, 307, 308 / 605, 606, 607, 608 |

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



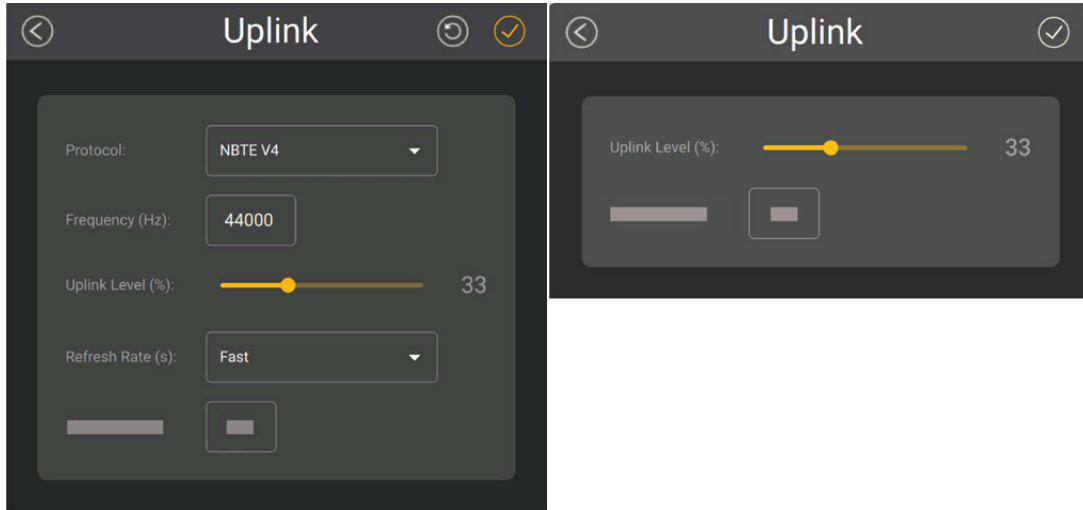
 **Important:** Make sure to put the same number when **adding the sensor to Scala2 receiver page (on page 44)**. If not, change it accordingly.

3. Click .

Configuring the Uplink Signal

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


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



Speed Explorer Pro

Speed Pro

2. Speed 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 ◦ High level of interferences |

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


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


Configuring the Telegrams

You change the telegram assigned to each type of data.

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 68)** for a full list of boat/channel codes.

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 |
|----------------------------|----------|---------------------------|
| Along Speed & Across Speed | CL | Every 11 to 12 sec. |
| | CL2 | Every 11 to 12 sec. |
| Grid angle | GL | Every 11 to 12 sec. |
| Depth | D1 | 100 m., every 1 to 2 sec. |
| | D2 | 150 m., every 3 to 8 sec. |
| | D3 | 300 m., every 3 to 8 sec. |
| | D3_MC | 300 m., every 4 to 8 sec. |

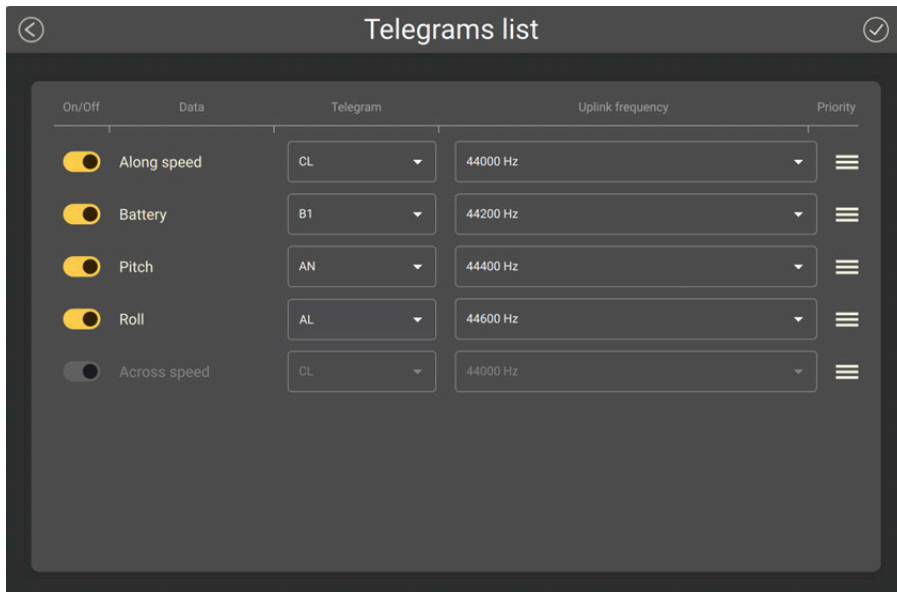
| Option | Telegram | Value and/or update rate |
|----------------|----------|----------------------------|
| | D6 | 600 m., every 3 to 8 sec. |
| | D12 | 1200 m., every 3 to 8 sec. |
| | D18 | 1800 m., every 3 to 8 sec. |
| Temperature | TL | Every 11 to 16 sec. |
| | TL_MC | Every 8 to 11 sec. |
| | 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.



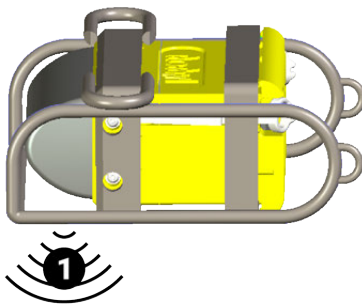
Speed Explorer Pro Specific Settings

Configure the settings of the Speed Explorer Pro echo sounder.

Sounding Modes

The sensor can send pings according to three different sounding modes.

Down 1

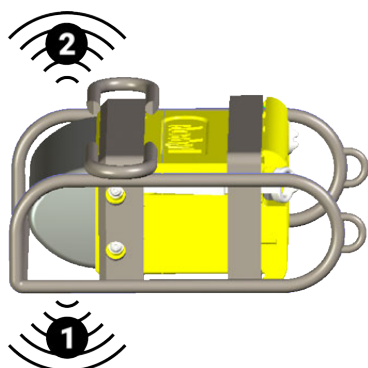


Sensor sends pings towards down direction (**1**) only.

You can see fish going into the trawl.

Pings are sent quicker than with the other modes, so more data is received, which enables a better horizontal resolution. This mode is recommended for better quality echogram images.

Down 1 + Up

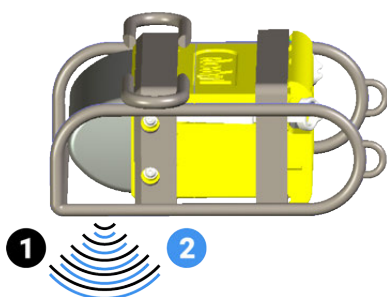


Sensor sends pings towards down (1) and up (2) directions.

With the down sounding, you can see fish going into the trawl. With the up sounding you can see if fish are missing the trawl and passing above the headrope. This way, you can correct the trawl position.

Fewer pings are sent because they are distributed between the 2 directions. As a result, data arrives slower to the receiver and echograms are of lesser quality.

Down 1 + Down 2



Sensor sends 2 consecutive pings towards down direction (1 and 2).


This mode is useful if you need to send two different pings towards the down direction. For example, sending one short and one long ping, or sending one low frequency and one higher frequency ping.

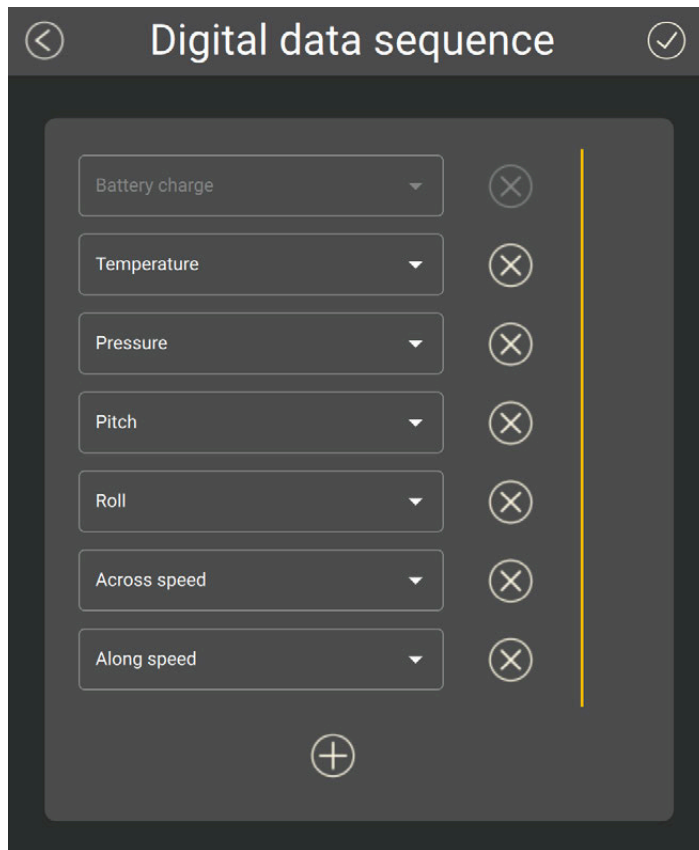
Like down + up mode, fewer pings are sent because they are distributed between the two different down soundings. As a result, data arrives slower to the receiver and echograms are of lesser quality.


Configuring Data Sending Sequence

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

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

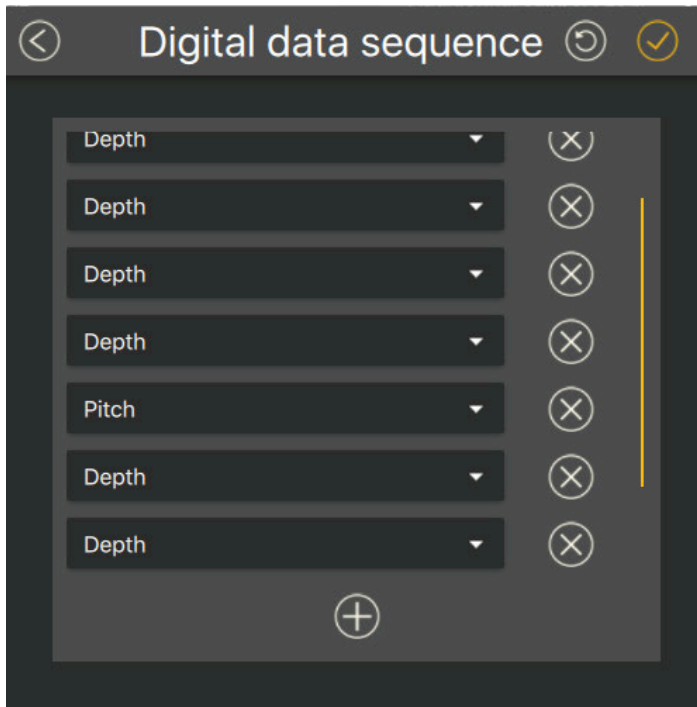
3. To add data, click  then select data in the drop-down menu. The sequence begins by the top.



 **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.




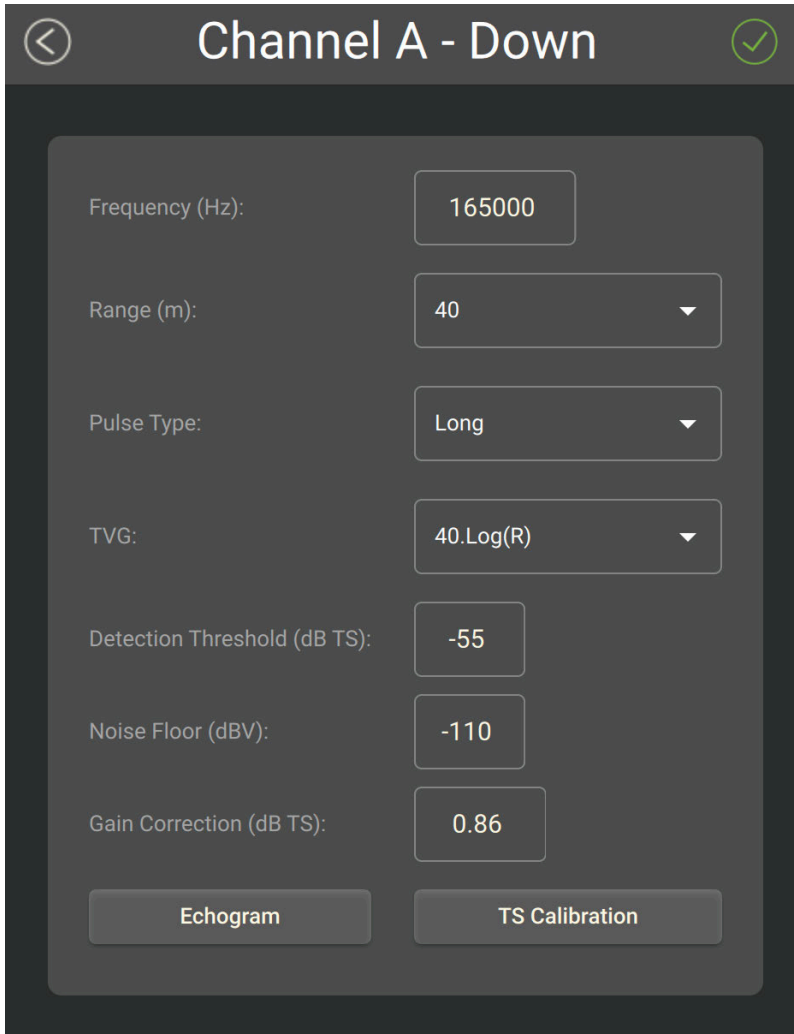
6. Click .

Configuring the Echo Sounder

Configure the echo sounder settings of the Speed sensor.

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**, **Up** 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.



Channel A - Down

Frequency (Hz): 165000

Range (m): 40

Pulse Type: Long

TVG: 40.Log(R)

Detection Threshold (dB TS): -55

Noise Floor (dBV): -110

Gain Correction (dB TS): 0.86

Echogram TS Calibration

4. Leave default **Frequency (Hz)** at 165,000 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 33)**.

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.
- 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.

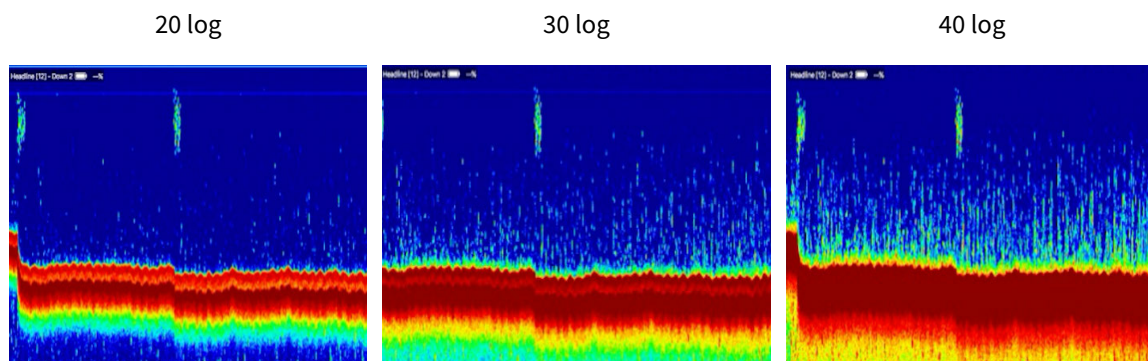
When the sounder sends pings, the deeper the target is, the more attenuated signals will be received and sent back. As a result, if the signal is too much attenuated, echoes (target strength) received from a target might not be as strong as they should be. TVG is here to compensate this effect. It uses 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

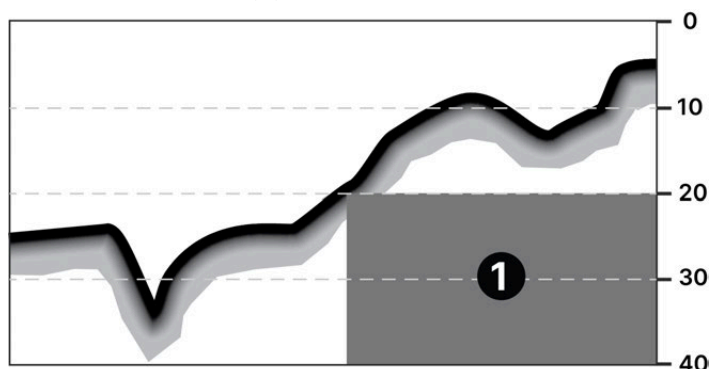
The sensor has an automatic range mode that is useful to get better quality echograms when the trawl is close to the bottom.

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.

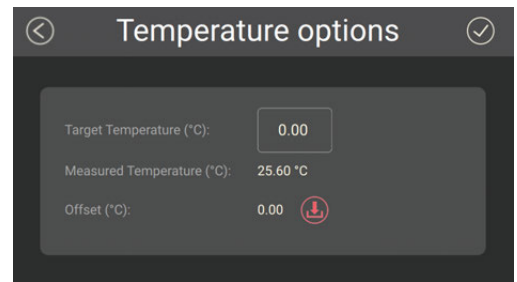
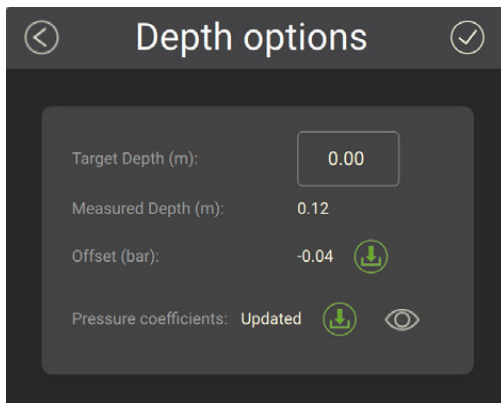
 **Note:** The trawl opening value sets the minimum distance to see inside the trawl. As a result, if the trawl opening distance is equal or higher than 18.5, the sensor will not reduce the range to 20 meters.


See **Configuring the Echo Sounder (on page 30)** 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.

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.

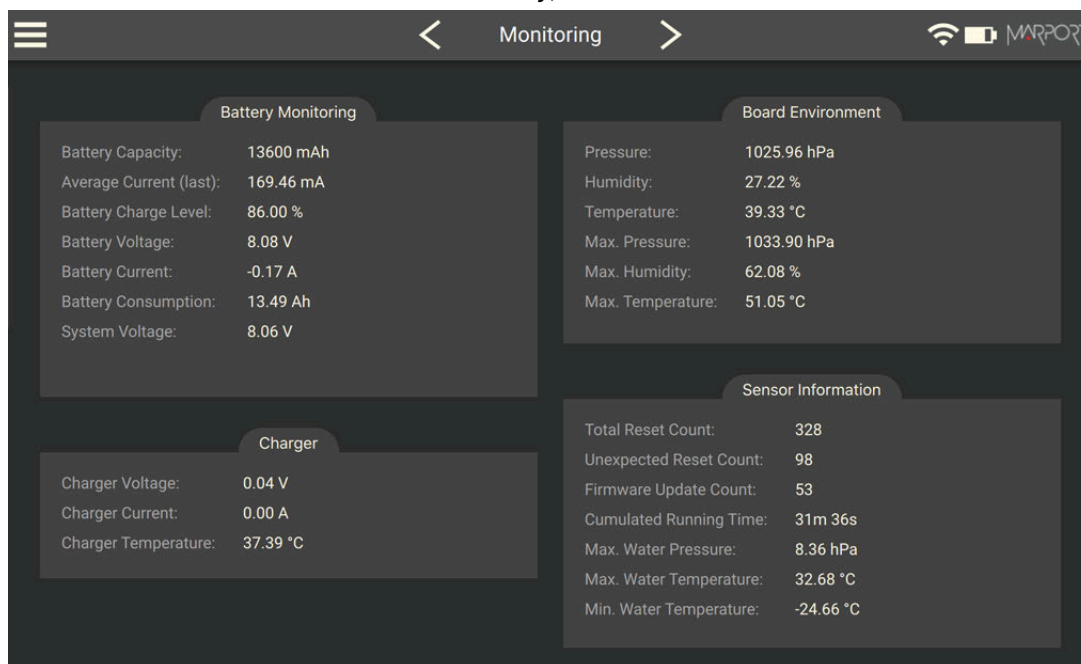
Testing Measures

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

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

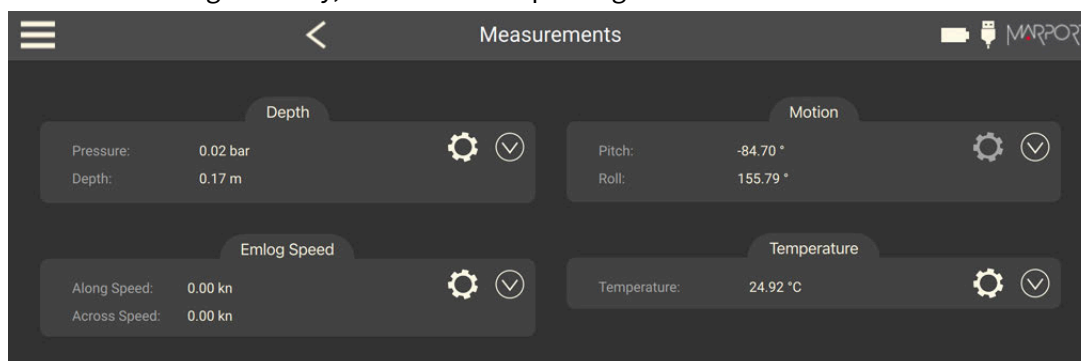
1. Press command + A or click **Menu**  and click **User Mode > Advanced**.
2. Go to the **Monitoring** page.


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.
- **Emlog Speed:** calibrate the speed measurements.

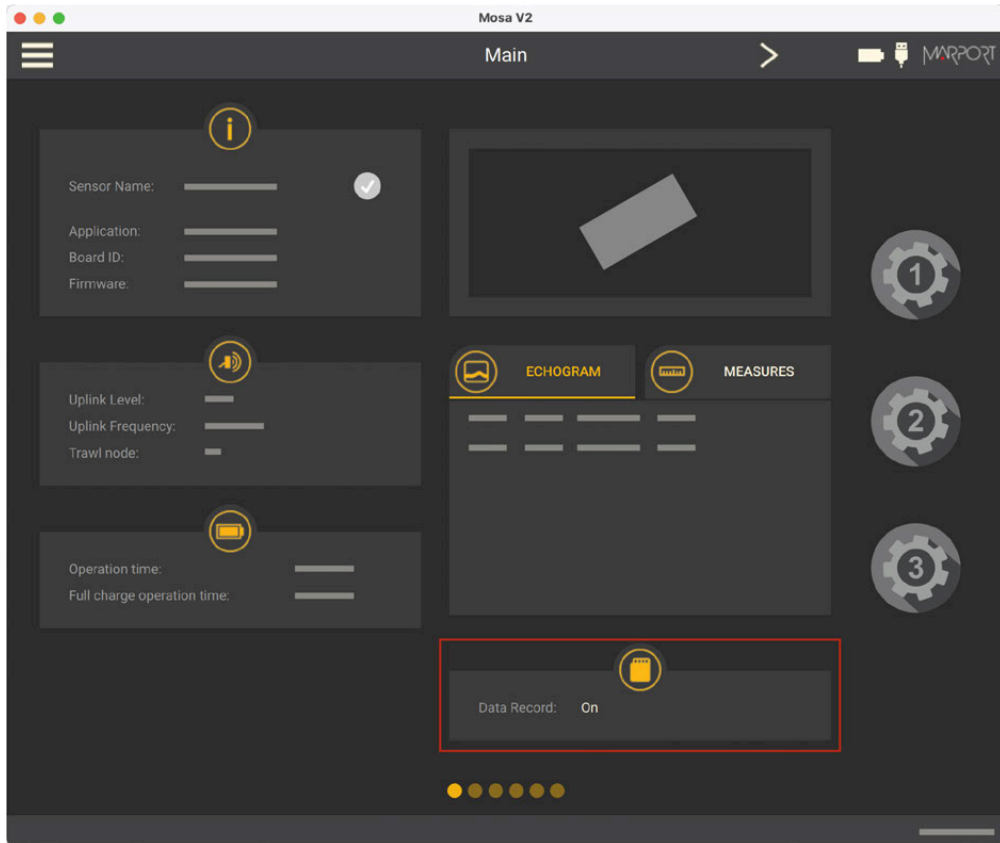
Memory Card Recording

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.

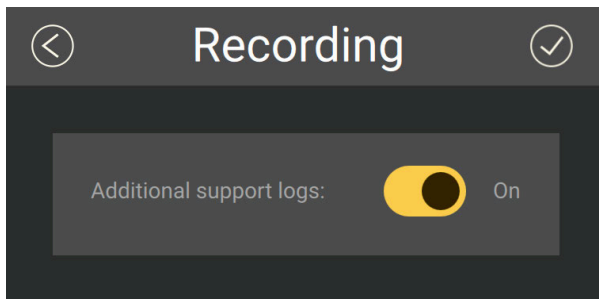
You can see on Mosa2 main page if the memory card recording feature is activated:



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:

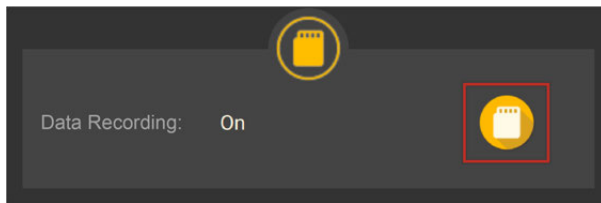
- Files containing measures recorded by the sensor. Their name begins by "450". These data are more precise and recorded more often than data received on the receiver. One file corresponds to a tow (time between entering and leaving water). The recording date displayed in the second column is synchronized 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.

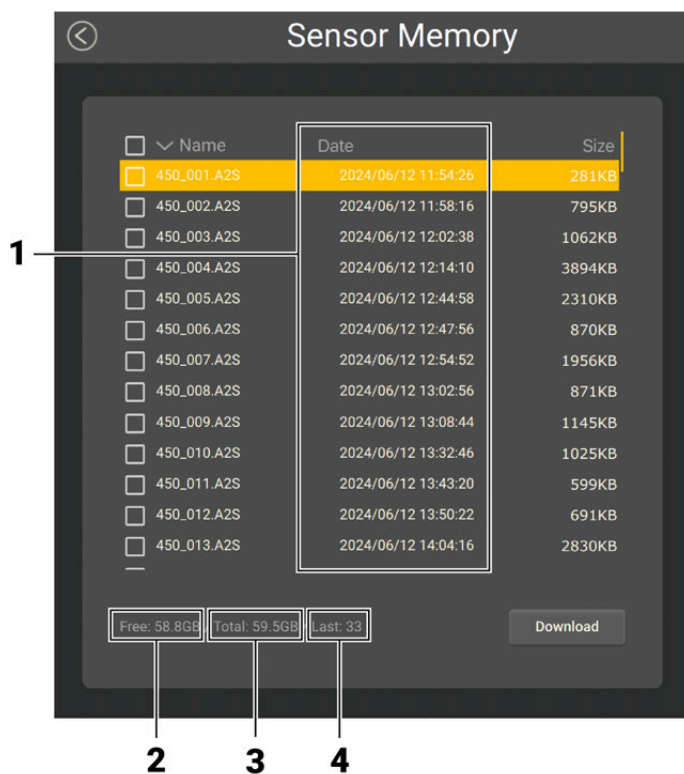
 **Note:** When downloading the files, we recommend to connect the sensor to Mosa2 using the Dock or the Configuration Cable for a better transfer of data.

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 53)** to learn how to replay these data in Scala2.


Saving a Configuration on Mosa2

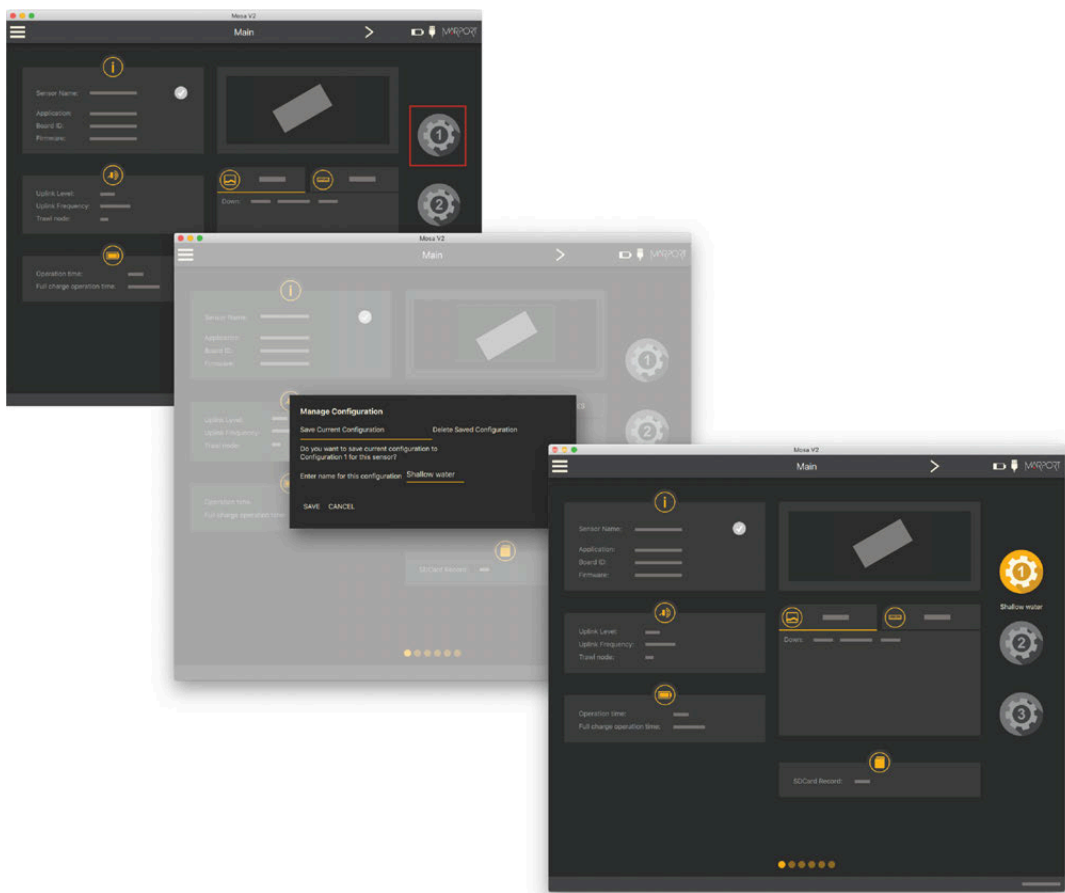
You can save different configurations of the sensor to be able to quickly change the configuration when you change your fishing method.

- You have finished configuring the sensor.

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:

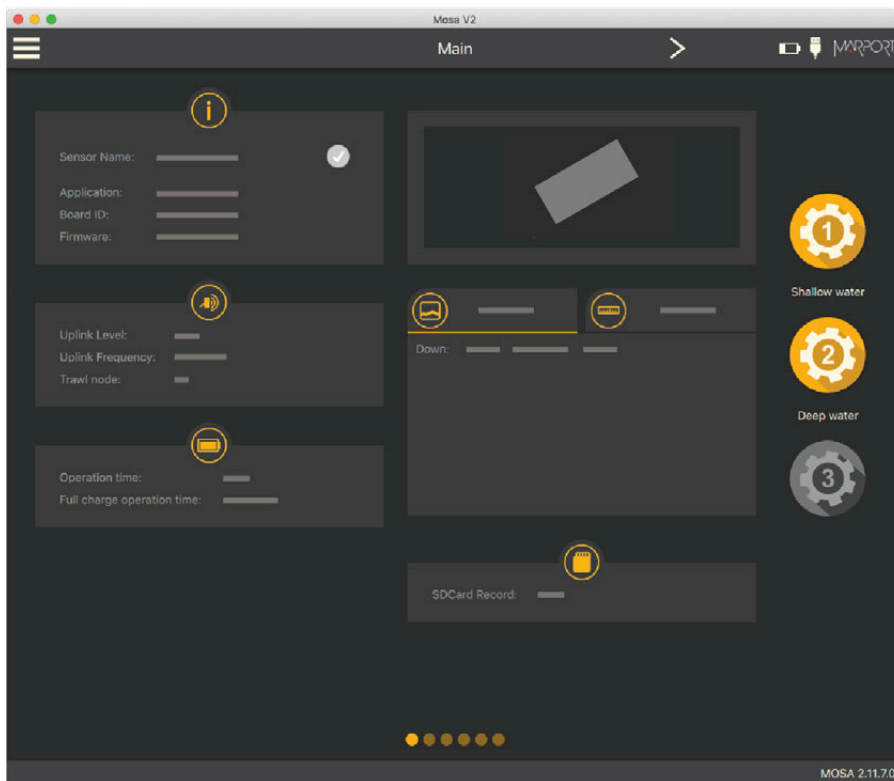
- If fishing in shallow water, you can use a configuration with an uplink level of 33%, a short pulse and a short range.
- If fishing in greater depths, you can change for a configuration with an uplink level of 100%, a long pulse and a long range.

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.
 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**.

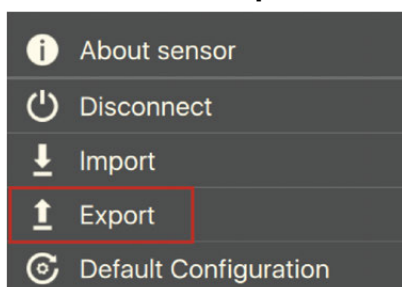
Exporting Sensor Configuration

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

- You are finished configuring the sensor.

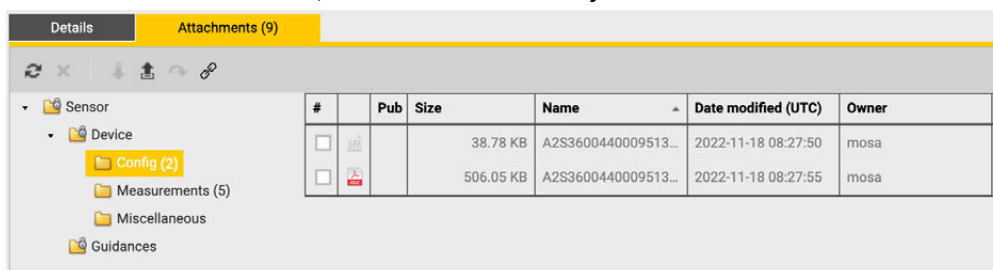
If you have issues with your sensor, send this file to support teams.

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



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

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

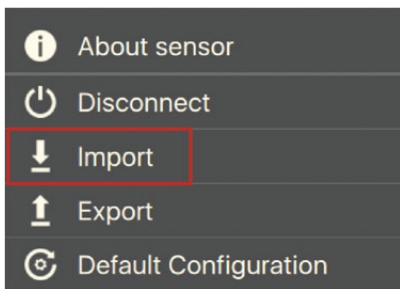
You can apply to a sensor a configuration that has already been made on another sensor.

- You have exported a configuration (see **Exporting Sensor Configuration (on page 41)**) and have the *.A2C or XML configuration file.

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.

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.

The configuration is loaded into the sensor.

System Configuration and Display

Learn how to configure the receiver to be able to receive and display Speed sensor 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.

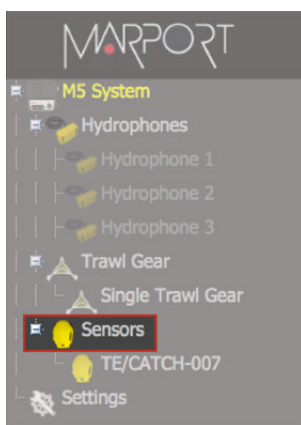
For compatibility details, see **System Compatibility (on page 8)**.

Adding the Sensor to the Receiver

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


 **Important:** To be able to add your sensor to the receiver, make sure your receiver version is compatible. Check **System Compatibility (on page 8)**.

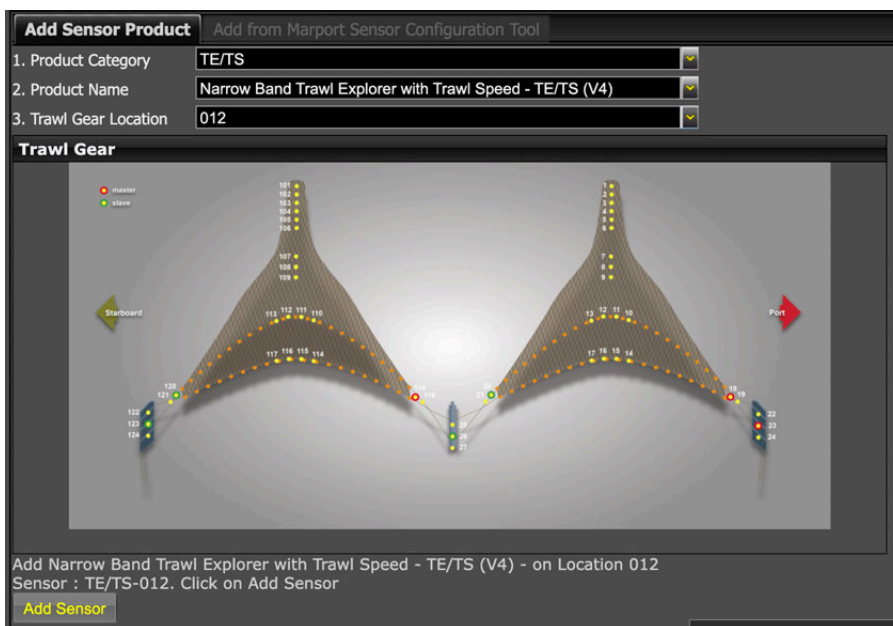
1. From Scala2, click **Menu**  > **Expert Mode** and enter the password `copernic`.
2. Right-click the IP address of the receiver at the bottom of the page, then click **Configure Receiver**.
3. From the left side of the receiver page, click **Sensors**.



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 |
|----------------|------------------|--|--|
| Speed Explorer | TE/TS | Narrow Band Trawl Explorer with Trawl Speed - TE/TS (V4) | Same as defined in Mosa2 (see Configuring the Trawl Node (on page 22))). |
| Trawl Speed | 3N1 | Trawl Speed with...* | |
| Grid | | Grid with...* | |

 **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.

Speed Pro



3N1-013

Sensor Name
 Sensor Name: 3N1-013 1
 Sensor Product: TrawlSpeed with Pitch, Roll and Battery 1
 Remove

Sensor Options

Sensor Processing
 Detection: Detection and 2D 2 Sensitivity: Medium 3

TrawlSpeed
 Frequency (Hz): 44000 Telegram: CL Filter: Configure...

Roll
 Frequency (Hz): 44600 Telegram: AL Filter: Configure... 5

Pitch
 Frequency (Hz): 44400 Telegram: AN Filter: Configure...

Battery
 Frequency (Hz): 44200 Telegram: B1 Filter: Configure...

Apply

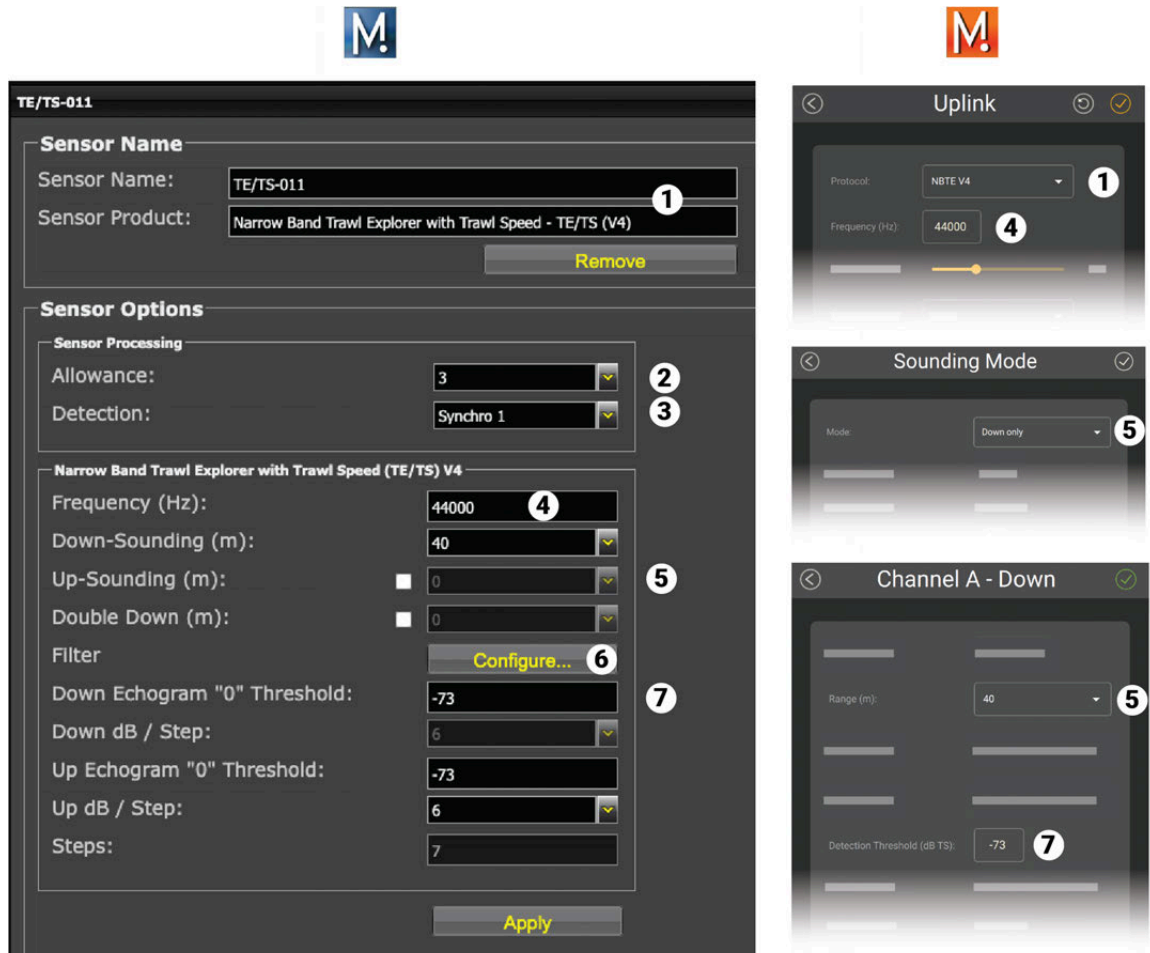
4 Telegrams list

| On/Off | Data | Telegram | Update Frequency | Priority |
|-------------------------------------|--------------|----------|------------------|----------|
| <input checked="" type="checkbox"/> | Along speed | CL | 44000 Hz | |
| <input checked="" type="checkbox"/> | Battery | B1 | 44200 Hz | |
| <input checked="" type="checkbox"/> | Pitch | AN | 44400 Hz | |
| <input checked="" type="checkbox"/> | Roll | AL | 44600 Hz | |
| <input type="checkbox"/> | Across speed | CL | 44000 Hz | |


| | |
|---|---|
| 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.

Speed 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> Tip: Please refer to Scala2 user guide for more information about the filters.</p> |
| 7 | <p>Enter the same detection threshold as set in Mosa2.</p> |


Click **Apply** when you have finished.


What to do next

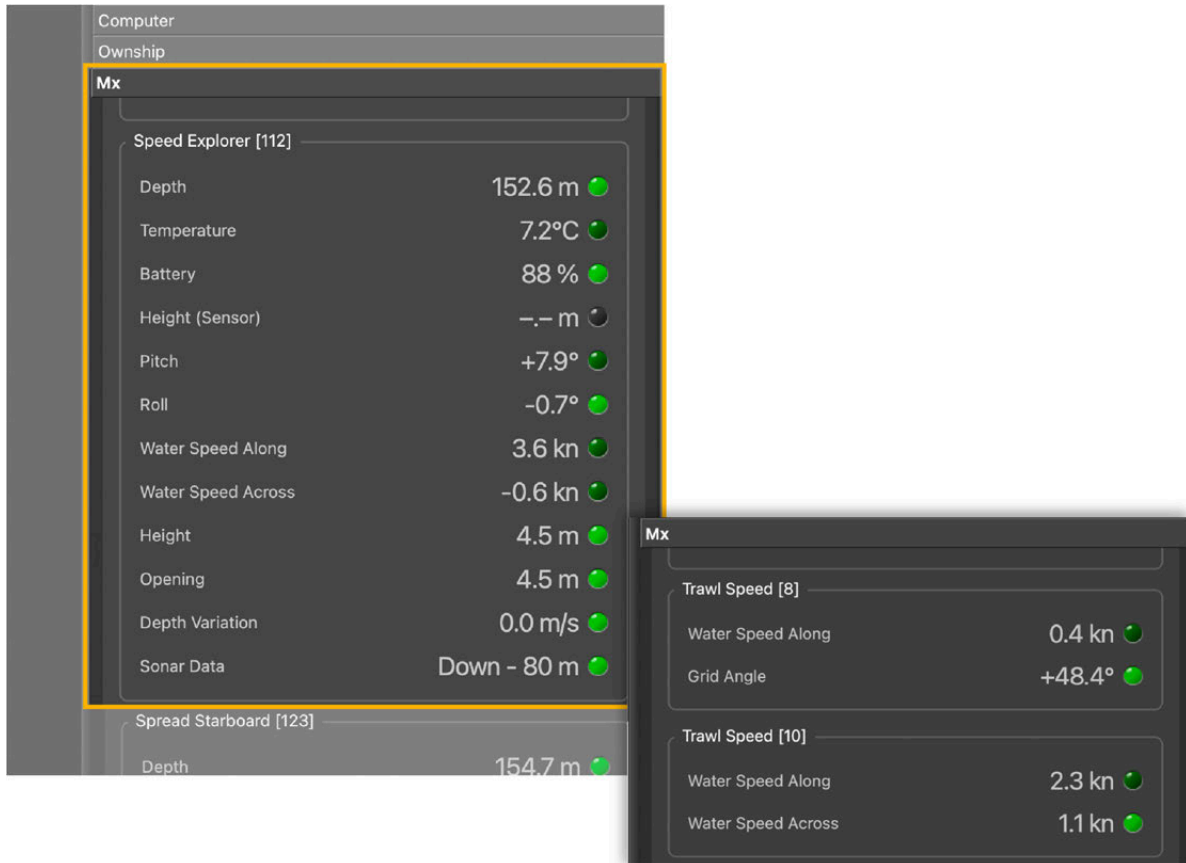
Configure the positioning settings if the sensor has the positioning option.

Configuring Data Display in Scala2

You can display the sensor's measurements and echograms on Scala2 pages.

1. From the top left corner of the screen, click **Menu**  > **Customize** and enter the password `eureka`.
2. Open the control panels and go to the **Mx** tab. Data title should be:
 - Speed Explorer
 - **Trawl Speed** for Grid and Trawl Speed sensors.

 **Note:** Data displayed (e.g. depth, temperature, pitch & roll) depends on the sensor's features that are enabled.



The image shows a software interface with several panels. The main panel, titled 'Mx', displays data for 'Speed Explorer [112]'. Below it is a panel for 'Spread Starboard [123]'. A separate 'Mx' panel is shown to the right, displaying data for 'Trawl Speed [8]' and 'Trawl Speed [10]'.

| Parameter | Value | Status |
|--------------------|-------------|--------|
| Depth | 152.6 m | Green |
| Temperature | 7.2°C | Green |
| Battery | 88 % | Green |
| Height (Sensor) | -. m | Grey |
| Pitch | +7.9° | Green |
| Roll | -0.7° | Green |
| Water Speed Along | 3.6 kn | Green |
| Water Speed Across | -0.6 kn | Green |
| Height | 4.5 m | Green |
| Opening | 4.5 m | Green |
| Depth Variation | 0.0 m/s | Green |
| Sonar Data | Down - 80 m | Green |

| Parameter | Value | Status |
|-----------|---------|--------|
| Depth | 154.7 m | Green |

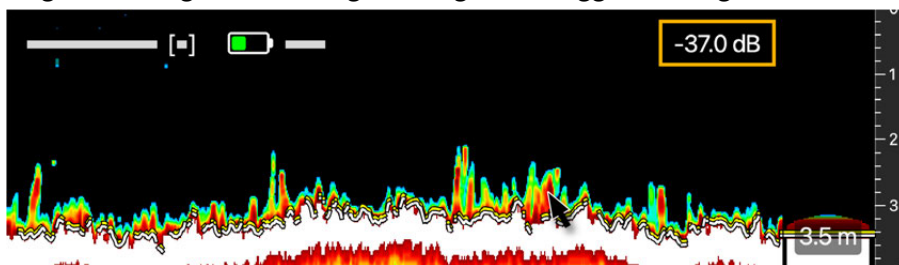
| Parameter | Value | Status |
|-------------------|--------|--------|
| Water Speed Along | 0.4 kn | Green |
| Grid Angle | +48.4° | Green |

| Parameter | Value | Status |
|--------------------|--------|--------|
| Water Speed Along | 2.3 kn | Green |
| Water Speed Across | 1.1 kn | Green |

3. Click + drag to a page **Sonar Data** to display the echogram of a Speed Explorer.



4. Hover the mouse over the echogram to display the target strength of the detected targets. The higher is the target strength, the bigger the target is.




5. Open the customization panels and go to **MX** to display **Water Speed Along** and **Water Speed Across** data in a **TS Dial** or in a **TS 3D**.

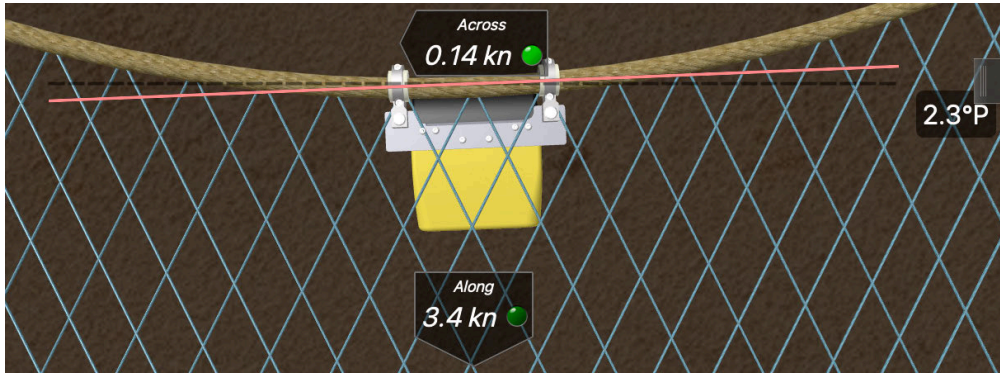


TS Dial:



 **Note:** Bearing angle is negative when the sensor is oriented toward port and positive when oriented toward starboard.

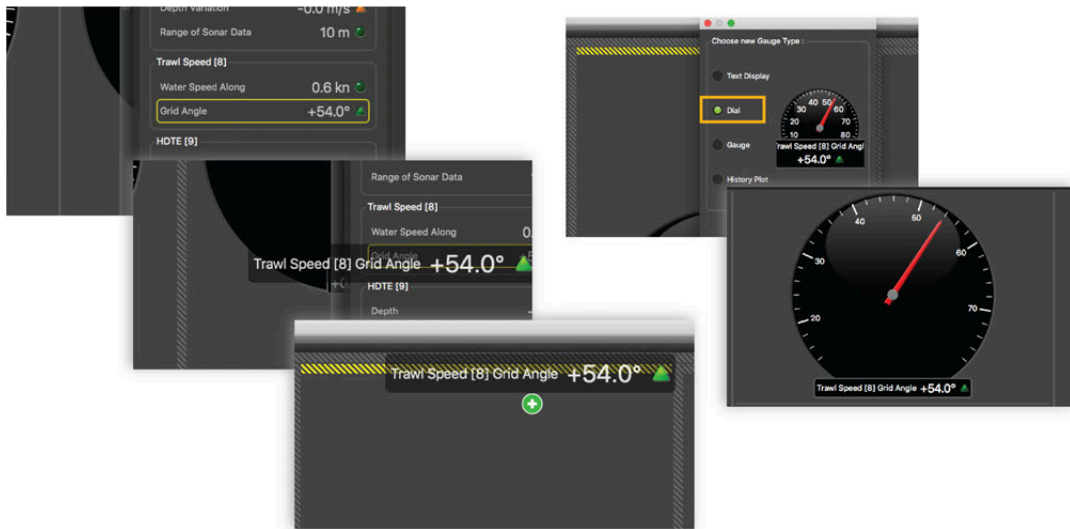
TS 3D:




6. You can also click and drag the data from the control panels, then choose a type of display from **Choose type of display**.



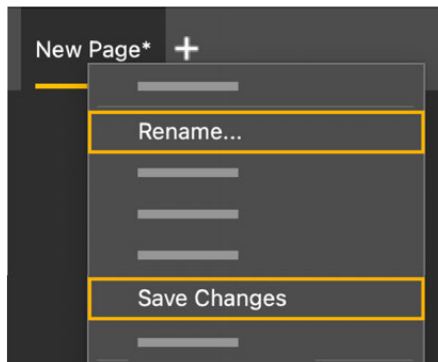
7. To display the angle of a Grid sensor, drag **Grid Angle** data to a page and select **Dial**:




 **Note:** The angle displayed should be 45° when the grid is correctly placed. In this example, the grid angle is slightly too high. If the grid angle is too high, non-targeted species may also be caught in the grid. If the grid angle is too low, targeted species may not enter.

8. To save the changes you made:


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



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

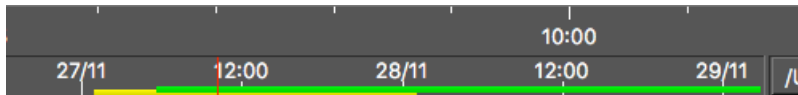
Replaying Data Recorded on a Memory Card

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

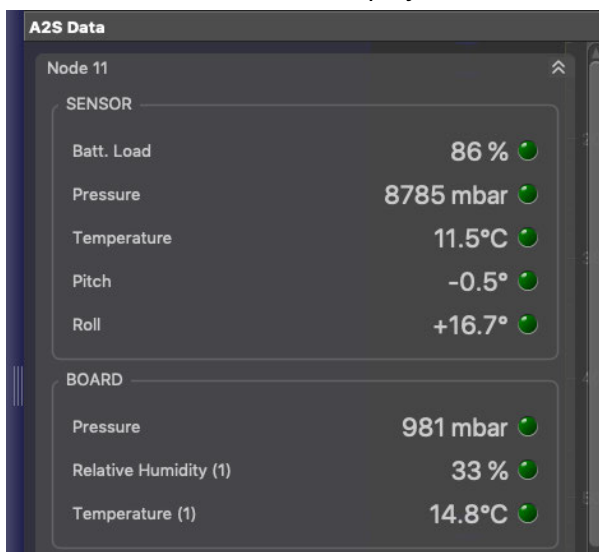
 **Note:** Data in high definition is available only when downloading it from the sensor memory (A2S files). Data received in Scala2 will have a lower definition (SDS files).

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.

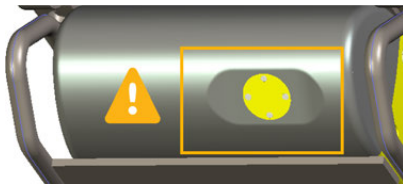
Installation

Learn how to install the sensor on the trawl gear.

Installing the Speed Sensors on the Trawl

Follow these guidelines to install Speed Explorer (standard or reversed), Trawl Speed and Grid sensors on the trawl.

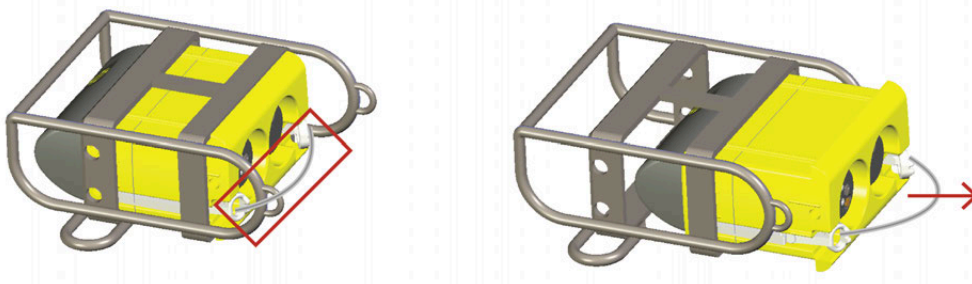
 **CAUTION:**



Handling precaution and a good maintenance of the EM log head is essential for the proper operation and lifetime of the flow sensors. Make sure to always use a protective cage when using the sensor. The protective cage must be approved by Marport. Any additional protective devices installed in front of the head may disrupt the flow and therefore alter the water speed measurements.

Even when the sensor is protected with a cage, make sure the head of the sensor does not hit any rail or protruding object when hauling the trawl on deck.

The sensor is maintained in the cage by a latch mechanism. Pull the cord at the back of the sensor to release the latch and remove the sensor from the cage. The cage will stay mounted to the headrope.

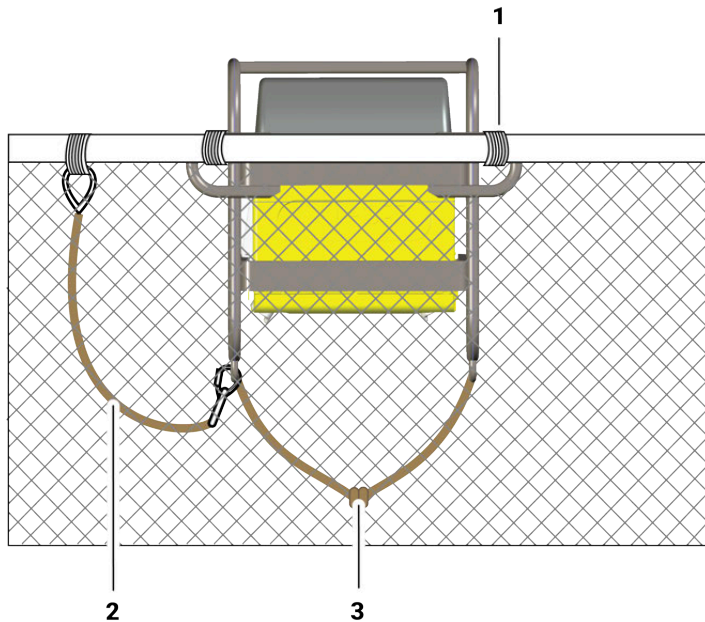


When the sensor is installed on the headrope, you may not see the footrope. If you want to see it, move back the sensor of a few meters.

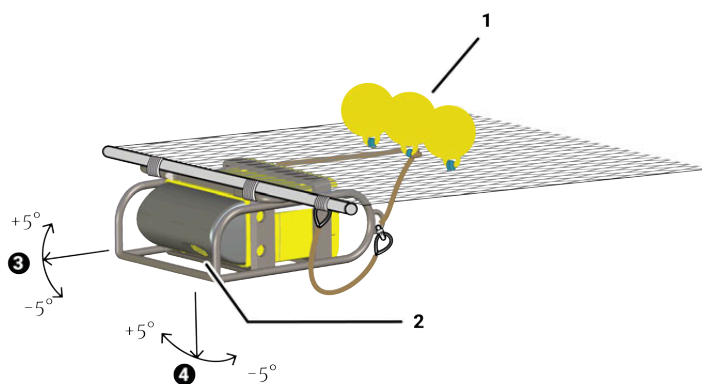
The sensor must be placed in a way that there is less than +/- 5 degrees of pitch and roll. You may need to add floats to the back of the sensor to achieve this.

Standard Installation

The Speed Explorer Pro and Trawl Speed are placed below the headrope, EM log pins facing down.



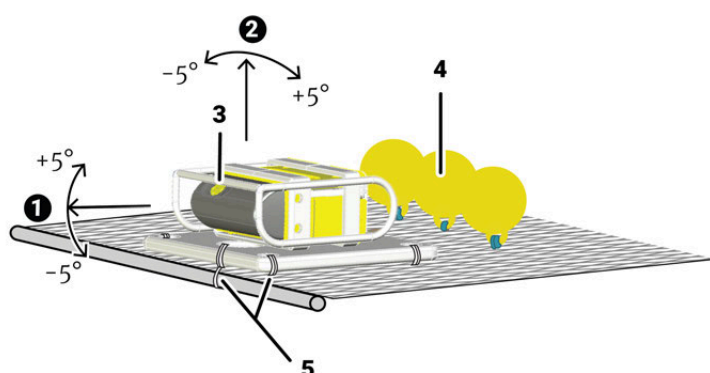
1. Cage attached to the headrope
2. Safety wire with small shackles on both ends to secure the sensor
3. Rope passing between 2 housing attachment lugs and attached to the net



1. Floats at the back help stabilizing the pitch and roll of the sensor.
2. EM log pins facing down. Make sure nothing is in front (rope, floats): it would impede its signal.
3. Maximum pitch + 5° / - 5°
4. Maximum roll + 5° / - 5°

Trawl Explorer: Reversed Installation

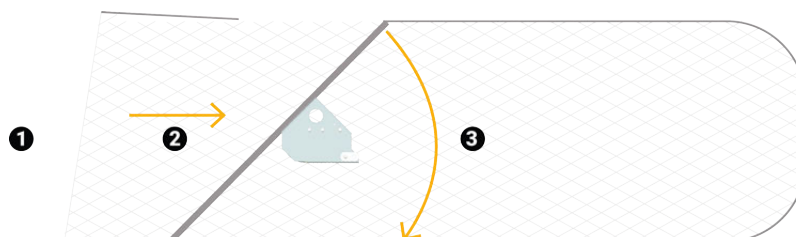
In this installation, the EM log pins face up instead of down. In this case, the Speed Explorer Pro is installed on a board to provide more stability. The aim of this installation is to prevent the EM log pins and transducer to hit the deck when the trawl is hauled.



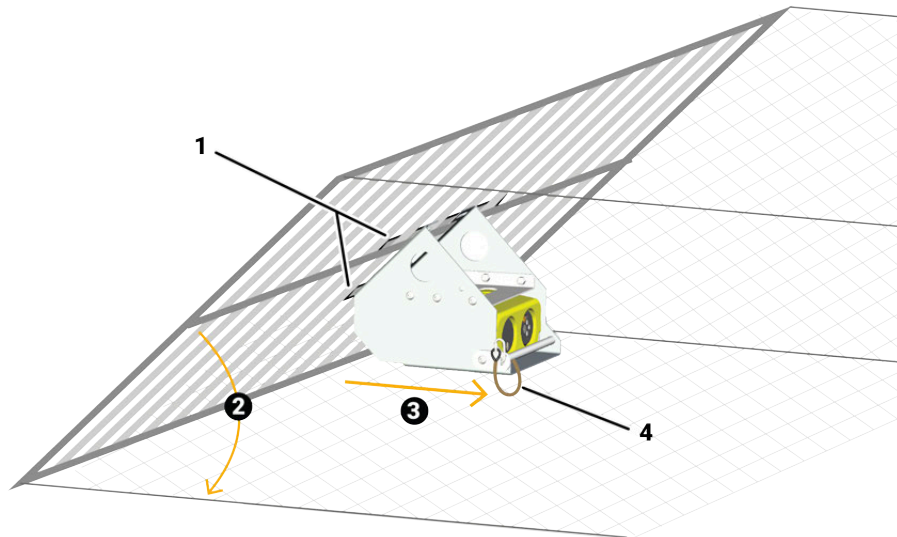
1. Maximum pitch $+5^\circ / -5^\circ$
2. Maximum roll $+5^\circ / -5^\circ$
3. EM log pins facing up. Make sure nothing is in front (rope, floats): it would impede its signal.
4. Floats at the back help stabilizing the pitch and roll of the sensor.
5. Ropes attaching the board to the headline and net.

Grid

We recommend to install the grid with an angle of 45° . The Grid sensor protection cage enables the sensor to be parallel to the ground. The head of the sensor must face the vessel.

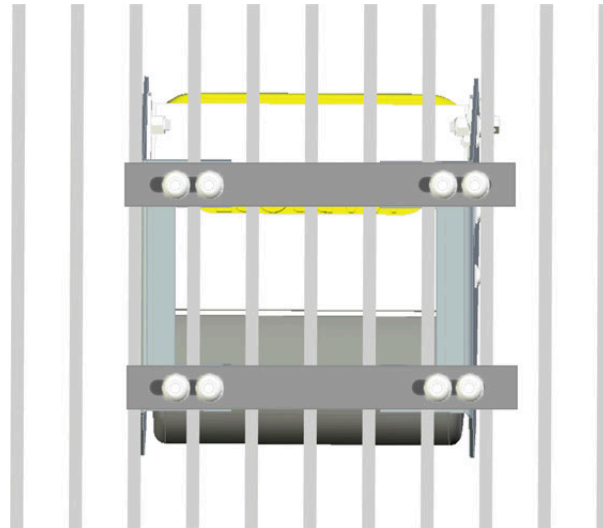


1. Vessel / 2. Direction of the flow / 3. Angle of the grid = 45°




1. Attached to the grid with a stainless steel plate and fastenings / **2.** Grid angle = 45° / **3.** Grid sensor must be parallel to the seabed / **4.** Safety wire between the sensor and the cage to secure the sensor

The sensor is attached to the grid with stainless steel plate and fastenings (not supplied by Marport), like on the image below:



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.


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

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

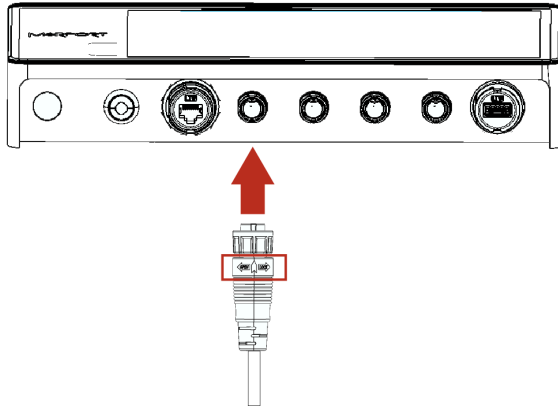
-  **Note:** For Dock products with serial number before DOC2400000: Do not leave the sensors connected on a charger that is switched off. If the charger is not connected to the mains voltage, the sensor switches on and this will drain the battery.

-  **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.

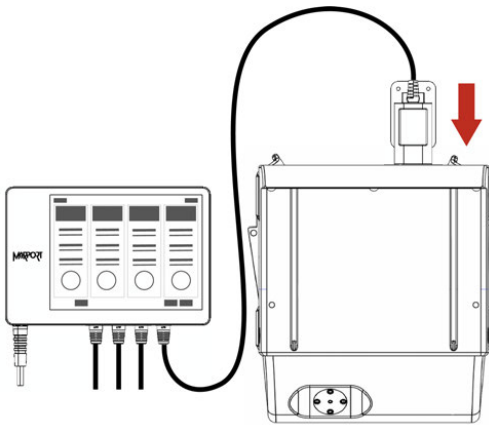
1. Before charging the sensor: wash with fresh water and dry the sensor. This prevents corrosion of the charging pins.

-  **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.



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 60) 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.

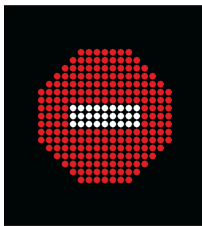
- Switch on the sensor by activating the water-switch, then listen for a ping noise and check if you see the LED switched on.
- Test the sensor measures with Mosa2: depth, temperature, pitch, roll, and if applicable: spread distance, echogram, catch status, speed measures (using the EM log tester).
-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

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.

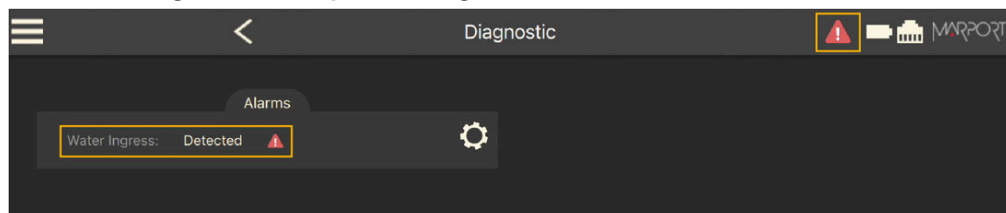


→ The shoulder bolts are dirty or damaged.


- 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.

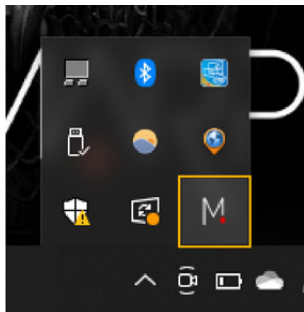
Anywhere option is now displayed in **Security & Privacy** preferences.


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

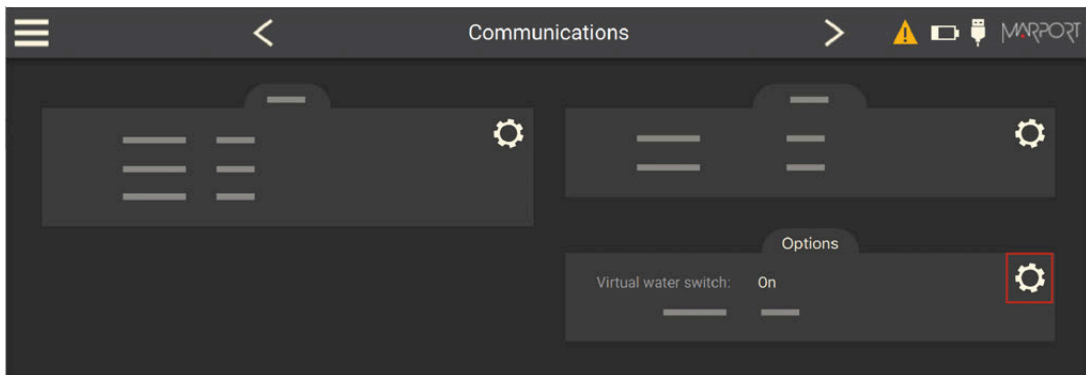
You activated the sensor water switch outside water or in a low level of water (for example for testing purpose) but it does not switch to running mode and does not emit any data.

→ 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 21)**.

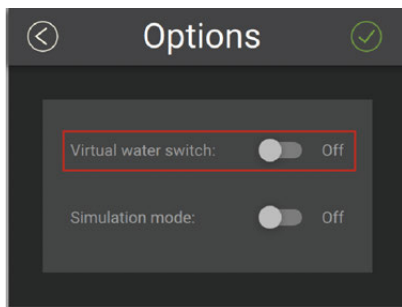
1. Connect the sensor to Mosa2 and check if there is an orange warning sign at the top of the window. If yes, it means the virtual water switch is on.



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).

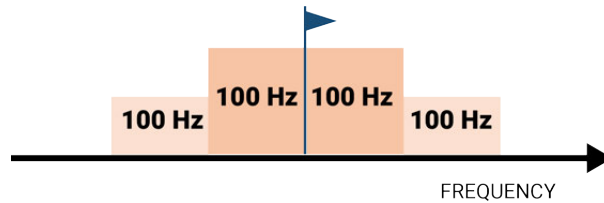
| Codes | | |
|---------|-----------|---------------|
| BC/CH | Frequency | FID (Scanmar) |
| C-1/CH1 | 42833 | 45 |
| C-1/CH2 | 41548 | 32 |
| C-1/CH3 | 41852 | 35 |
| C-1/CH4 | 40810 | 25 |
| C-1/CH5 | 42500 | 42 |
| C-1/CH6 | 43200 | 49 |
| C-2/CH1 | 42631 | 43 |
| C-2/CH2 | 41417 | 31 |
| C-2/CH3 | 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

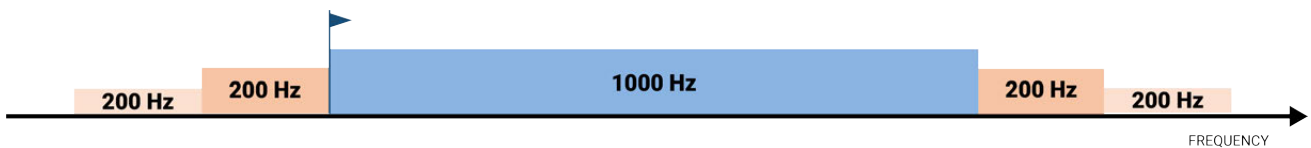
The diagrams below show the bandwidth of the different types of Marport sensors and intervals you must respect when adding other sensors.

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



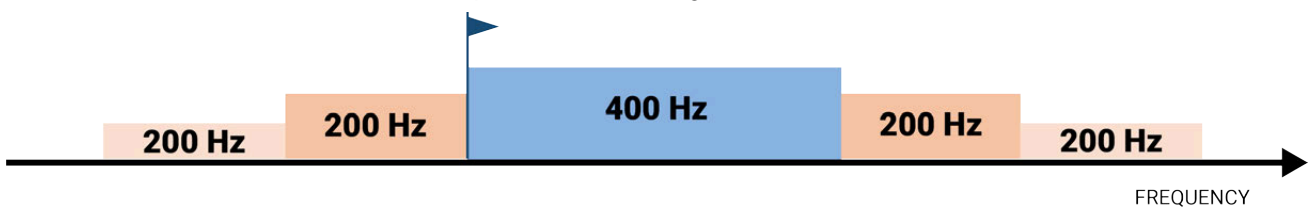
Example: If the frequency of the sensor is 40kHz, there should be no sensors between 39.9 and 40.1kHz.

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



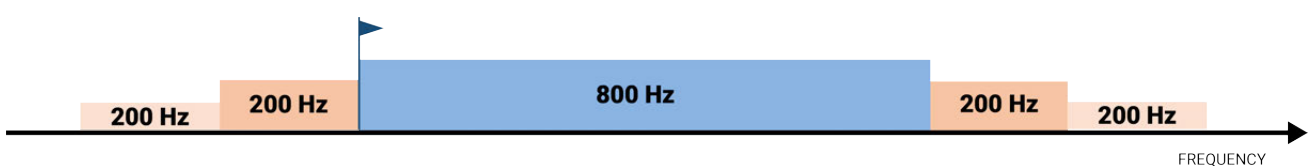
Example: If the frequency of the sensor is 40kHz, there should be no sensors between 39.8 and 41.2kHz.

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

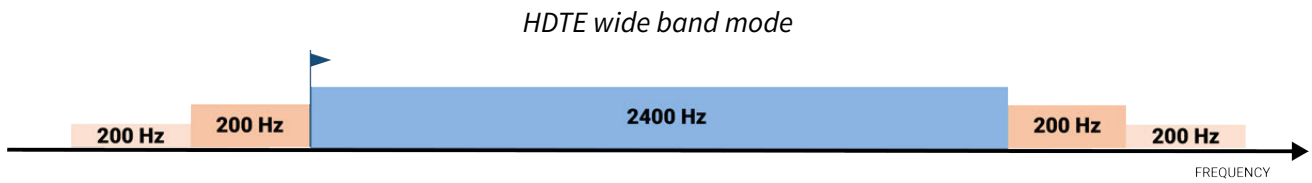


Example: If the frequency of the sensor is 40kHz, there should be no sensors between 39.8kHz and 40.6kHz.

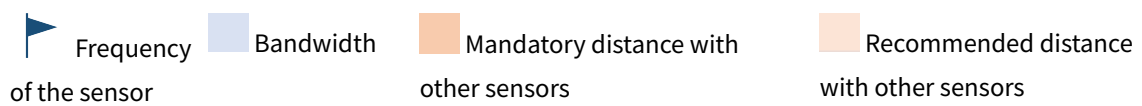
HDTE narrow band mode



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



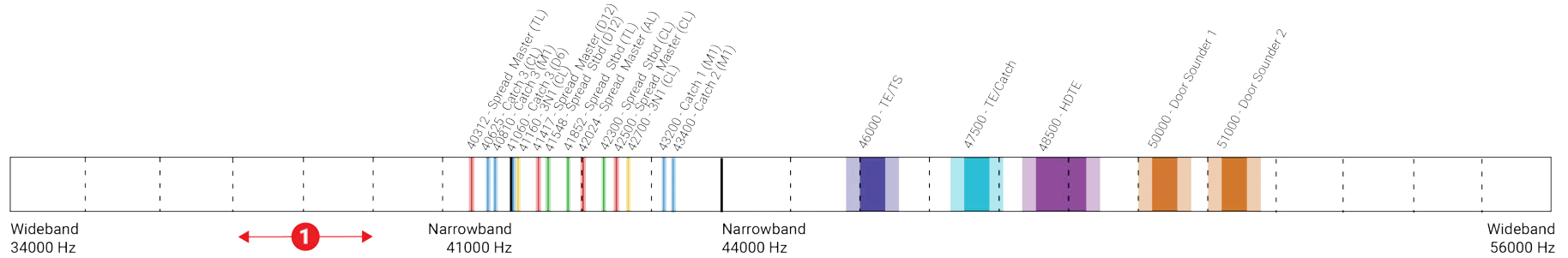
Example: If the frequency of the sensor is 40kHz, there should be no sensors between 39.8kHz and 42.6kHz.



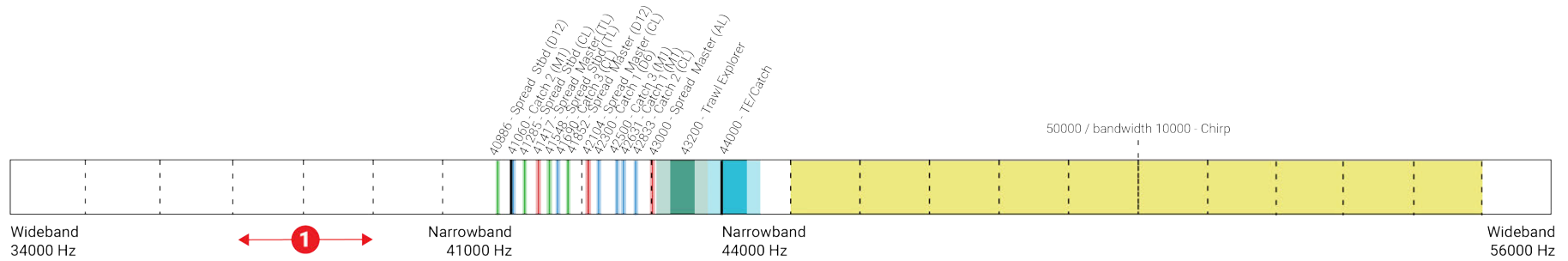
Examples of frequency allocations

- 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.

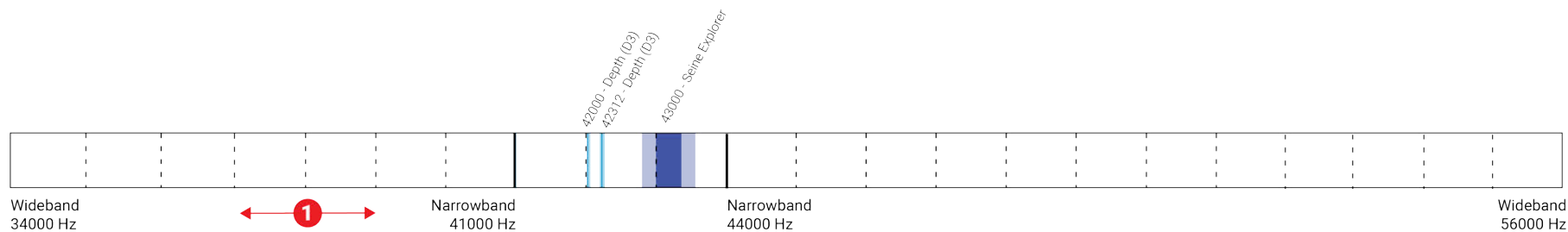
Example of a system with Spread, Catch, Trawl Speed sensors and Speed Explorer, Catch Explorer, HDTE and Door Sounder.




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.

Compatible NMEA Sentences from Winch Control Systems, GPS and Compass Devices

You can add to Scala2 measures coming from winch control systems that use the following NMEA sentences.

NMEA 0183 Standard Sentences

Symbol (*) indicates which parts of the sentence Scala2 uses.

| NMEA Sentence | Format | First compliant version of Scala |
|---|---|----------------------------------|
| <p>GGA - Global Positioning System Fix Data</p> | <pre>\$-- GGA,hhmmss.ss,aaaa.aa,b,cccc.cc,d,e,ff,g.g,h.h, M,i.i,M,j.j,kkkk*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$--: Talker identifier* 2. GGA: Sentence formatter* 3. hhmmss.ss: UTC of position* 4. aaaa.aa, b: Latitude North/South (N/S)* 5. cccc.cc, d: Longitude East/West (E/W)* 6. e: GPS quality indicator 7. ff: Number of satellites in use (00-12) 8. g.g: Horizontal dilution of precision 9. h.h, M: Antenna altitude above/below mean sea level (geoid), meters* 10. i.i, M: Geoidal separation, meters 11. j.j: Age of differential GPS data 12. kkkk: Differential reference station ID 13. *hh: Checksum* | <p>1.0.0.0</p> |
| <p>GLL - Geographic Position - Latt/Long</p> | <pre>\$--GLL, aaaa.aa,L,bbbb.bb,L,hhmmss.ss,C,d*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$--: Talker identifier* 2. GLL: Sentence formatter* 3. aaaa.aa,L: Latitude North/South (N/S)* 4. bbbb.bb,L: Longitude East/West (E/W)* 5. hhmmss.ss: UTC of position* 6. C: status (A: data valid / V: data not valid)* | <p>1.2.6.0</p> |

| NMEA Sentence | Format | First compliant version of Scala |
|--------------------------------------|--|----------------------------------|
| | 7. d: Mode indicator 8. *hh: Checksum* | |
| GNS - GNSS Fix Data | <pre data-bbox="496 517 1038 584">\$--GNS,hhmmss.ss,aaa.aa,L,bbbb.bb,L,c--c,dd,e.e,f.f,g.g,h.h,i.i,a*hh<CR><LF></pre> <ol data-bbox="549 636 1062 1234" style="list-style-type: none"> 1. \$--: Talker identifier* 2. GNS: Sentence formatter* 3. hhmmss.ss: UTC of position* 4. aaaa.aa,L: Latitude North/South (N/S)* 5. bbbbb.bb,L: Longitude East/West (E/W)* 6. c--c: Mode indicator 7. dd: Total number of satellites in use (00-99) 8. e.e: Horizontal dilution of precision 9. f.f: Antenna altitude above/below mean sea level (geoid), in meters* 10. g.g: Geoidal separation, meters 11. h.h: Age of differential data 12. i.i: Differential reference station ID 13. *hh: Checksum* | 1.0.0.0 |
| HDG - Heading, Deviation & Variation | <pre data-bbox="496 1272 922 1294">\$--HDG,a.a,b.b,M,c.c,M*hh<CR><LF></pre> <ol data-bbox="549 1346 1086 1682" style="list-style-type: none"> 1. \$--: Talker identifier* 2. HDG: Sentence formatter* 3. a.a: Sensor magnetic heading (degrees)* 4. b.b,M: Magnetic deviation (degrees), Easterly/Westerly (E/W)* 5. c.c,M: Magnetic variation (degrees), Easterly/Westerly (E/W)* 6. *hh: Checksum* | 1.0.0.0 |
| HDT - Heading, True | <pre data-bbox="496 1756 794 1778">\$--HDT,a.a,T*hh<CR><LF></pre> <ol data-bbox="549 1830 863 1897" style="list-style-type: none"> 1. \$--: Talker identifier* 2. HDT: Sentence formatter* | 1.0.0.0 |

| NMEA Sentence | Format | First compliant version of Scala |
|--|---|----------------------------------|
| | 3. a.a,T: Heading (degrees) True* 4. *hh: Checksum* | |
| RMC - Recommended Minimum Navigation Information | <pre>\$-- RMC , aaaaaa , A , bbbb . bbb , B , ccccc . ccc , C , ddd . d , eee . e , ffffff , ggg . g , G , H * hh < CR > < LF ></pre> <ol style="list-style-type: none"> 1. \$--: Talker identifier* 2. RMC: sentence formatter* 3. aaaaaa: Time (UTC)* 4. A: Status, A = data valid, V = navigation receiver warning* 5. bbbb.bbb, B: Latitude, N/S* 6. ccccc.ccc, C: Longitude, E/W* 7. ddd.d: Speed over ground (knots)* 8. eee.e: Course Over Ground (degrees True)* 9. fffff: Date: ddmmyy* 10. ggg.g, G: Magnetic variation (degrees E/W)* 11. H: mode indicator: A=Autonomous, D=Differential, E=Estimated, M=Manual input, S=Simulator, N=data not valid (sentence is not accepted if mode indicator = N)* 12. *hh: Checksum* | 2.2.2.0 |
| VHW - Water Speed and Heading | <pre>\$--VHW , a . a , T , b . b , M , c . c , N , d . d , K * hh < CR > < LF ></pre> <ol style="list-style-type: none"> 1. \$--: Talker identifier* 2. VHW: Sentence formatter* 3. a.a,T: Heading, degrees True* 4. b.b,M: Heading, degrees Magnetic* 5. c.c,N: Speed, knots* 6. d.d,K: Speed, km/hr 7. *hh: Checksum* | 1.4.0.0 |

| NMEA Sentence | Format | First compliant version of Scala |
|---|--|----------------------------------|
| VTG - Course Over Ground and Ground Speed | <pre>\$--VTG,a.a,T,b.b,M,c.c,N,d.d,K*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$--: Talker identifier* 2. VTG: Sentence formatter* 3. a.a,T: Course over ground, degrees, True* 4. b.b,M: Course over ground, degrees, Magnetic 5. c.c,N: Speed over ground, knots* 6. d.d,K: Speed over ground, km/hr* 7. *hh: Checksum* | 1.3.3.0 |

Proprietary Sentences

Symbol (*) indicates which parts of the sentence Scala2 uses.

| NMEA Sentence | Format | First compliant version of Scala |
|---|---|----------------------------------|
| ATW - Naust Marine winch control system | <pre>\$NMATW,aaaaaa,bbbbbb,cccccc,dddddd,eeeeee,ffffff,ggggg,hhhhh,iiii,jjjjj,kkkkk,lllll,mm:mm*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$NMATW: Talker identifier + sentence formatter* 2. aaaaaa: Winch starboard tension (kg)* 3. bbbbbb: Winch port tension (kg)* 4. cccccc: Winch middle tension (kg)* 5. ddddd: Winch starboard length (meter or feet)* 6. eeeee: Winch port length (meter or feet)* 7. fffff: Winch middle length (meter or feet)* 8. ggggg: RPM starboard 9. hhhhh: RPM port 10. iiii: RPM middle 11. jjjjj: Line speed starboard (meter or feet/min) 12. kkkkk: Line speed port (meter or feet/min) 13. lllll: Line speed middle (meter or feet/min) 14. mm:mm: Towing time (meter or feet/min) | 1.2.0.0 |

| NMEA Sentence | Format | First compliant version of Scala |
|--|---|----------------------------------|
| FEC - Furuno attitude message | <pre>\$PFEC,GPatt,aaa.a,bb.b,cc.c,*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$PFEC: Talker identifier + sentence formatter* 2. GPatt: Global positioning attitude, sentence formatter 3. aaa.a: Heading true* 4. bb.b: Pitch* 5. cc.c: Roll* 6. *hh: Checksum* | 1.0.5.0 |
| KW - Karmoy Winch | <pre>\$KWIN,a,b.b,T,c.c,M,d.d,rpm*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$KWIN: Talker identifier + sentence formatter* 2. a: Winch 0 = Stbd / Trawl 1 = Port Trawl Winch 3. b.b, T: Tensions (tons) 4. c.c, M: Length (meters) 5. d.d, rpm: Speed (rpm) | 1.6.25.0 |
| MA DD - Marelec winch length and tension | <pre># MA DD dd/mm/yy hh:mm:ss LB aaaam LS bbbbm LM ccccm TB ddddK TS eeeeK TM ffffK gg<CR><LF></pre> <ol style="list-style-type: none"> 1. # MA DD: talker identifier* 2. dd/mm/yy: date 3. hh:mm:ss: time 4. LB aaaam: Shooted length portside in meters* 5. LS bbbbm: Shooted length starboard in meters* 6. LM ccccm: Shooted length center in meters* 7. TB ddddK: Tension of portside in kg* 8. TS eeeeK: Tension of starboard in kg* 9. TM ffffK: Tension of center in kg* 10. gg: system in 00 = MANUAL (stop), 10 = auto shooting, 20 = auto fishing, 30 = auto hauling, 40 = slow tension alarm without propeller reduction, 41 = slow tension alarm with | 1.2.0.0 |

| NMEA Sentence | Format | First compliant version of Scala |
|--|--|----------------------------------|
| | propeller reduction, 50 = fast tension alarm without propeller reduction, 51 = fast tension alarm with propeller reduction* | |
| MPT TXOR - Marport, transducer orientation | <pre>\$PMPT, TXOR, aa.a, bb.b, cc.c, d*hh</pre> <ol style="list-style-type: none"> 1. \$PMPT: talker identifier + sentence formatter. 2. TXOR: Transducer Orientation 3. aa.a: pitch* 4. bb.b: roll* 5. cc.c: yaw* 6. s: V = valid / N = not valid* | 2.0.0.0 |
| NAV - Ifremer proprietary sentence | <pre>\$NANAV, 04/ 09/yy, hhhmmss.sss, NASYC, N, 48, 22.92315, W, 004, 28.90527, D, 00.0, WG84, 04/09/13, 13:05:37.000, COU, 346.08, -00.22, +00.13, +00.00, +00052.172, 000, 0000</pre> | 1.0.0.0 |
| IFM - Ifremer versatile sentence | <pre>\$PIFM, EU, MES, dd/mm/yy, hh:hh:ss.sss, TRFUN, ±a, bb, ccccc, dddd, e.e, f, ggggg, hhhh, i.i, j, <CR><LF></pre> <ol style="list-style-type: none"> 1. \$PIFM: Talker identifier + sentence formatter* 2. OCGYR: pitch, roll, heading 3. TRFUN: winch lengths (starboard, port) and winch tensions (starboard, port) | 1.0.0.0 |
| SYN - Winch Syncro 2020, winch length and tension | <pre>\$WMSYN, aaa.a, m, bbb.b, m, ccc.c, m, ddd.d, m, ee.e, t, ff.f, t, gg.g, t, hh.h, t, 0.5, r, 0.7, r, 1.6, s, 2.0, s, 0, 0, 1, 0, 0, 45.5, c, 33.0, p, 32.8, p*31</pre> <ol style="list-style-type: none"> 1. \$WMSYN: Talker identifier + sentence formatter* 2. aaa.a: winch starboard length in meters* 3. bbb.b: winch inner starboard length in meters* 4. ccc.c: winch inner port length in meters* 5. ddd.d: winch port length in meters* 6. ee.e: winch starboard tension in tons* | 1.0.0.0 |

| NMEA Sentence | Format | First compliant version of Scala |
|---|--|----------------------------------|
| | 7. ff.f: winch inner starboard tension in tons* 8. gg.g: winch inner port tension in tons* 9. hh.h: winch port tension in tons* 10. Other strings are not used. | |
| | <pre>\$WMSYN,aaa.a,c,bbb.b,c,ccc.c,c,dd.d,t,ee.e,t,ff.f,t*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$WMSYN: Talker identifier + sentence formatter* 2. aaa.a,l: Starboard wire length (m=meter)* 3. bbb.b,l: Mid wire length (m=meter)* 4. ccc.c,l: port wire length (m=meter)* 5. dd.d,t: Starboard wire tension, tons* 6. ee.e,t: Mid wire tension, tons* 7. ff.f,t: Port wire tension, tons* | 1.6.19.0 |
| TAWWL - RappHydema, PTS Pentagon warp length | <pre>@TAWWL,a,M,b,M,c,M*hh<CR><LF></pre> <p>See below. M = meter</p> | 1.4.4.0 |
| | <pre>@TAWWL,x,y,z*hh<CR><LF></pre> | 1.6.19.0 |
| TAWWT - RappHydema, PTS Pentagon warp tension | <pre>@TAWWT,a.a,T,b.b,T,c.c,T*hh<CR><LF></pre> <p>See below. T = tons</p> | 1.4.4.0 |
| | <pre>@TAWWT,a.a,b.b,c.c*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. @TAWWT: Talker identifier + sentence formatter* 2. a.a: Starboard winch tension* 3. b.b: Port winch tension* 4. c.c: Middle winch tension* | 1.6.19.0 |
| WCT - Warp length and tension (Silecmar) | <pre>\$SIWCT,aaa,bbb,ccc,d.d,e.e,f.f*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$SIWCT: Talker identifier + sentence formatter* 2. aaa: Port winch cable, meters* 3. bbb: Starboard winch cable, meters* 4. ccc: Clump winch cable, meters* | 1.2.6.0 |

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|---|---|----------------------------------|
| | 5. d.d: Tension in the port winch, tons* 6. e.e: Tension in the starboard winch, tons* 7. f.f: Tension in the clump winch, tons* 8. *hh: Checksum* | |
| WIDA1 - Kongsberg warp length (single to triple trawls) | <pre>\$WIDA1,aa,bbbb,cc,0,dd,eeee,ff,1,g,h,i,2,k,l,m,3*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$WIDA1: Talker identifier + sentence formatter* 2. aa: port wire tension, tons* 3. bbbb: port wire out, meters* 4. cc: port wirespeed, m/min 5. 0: port* 6. dd: starboard wire tension, tons* 7. eeee: starboard wire out, meters* 8. ff: starboard wirespeed, m/min 9. 1: starboard* 10. g: port mid wire tension, tons* 11. h: port mid wire out, meters* 12. i: port mid wirespeed, m/min 13. 2: port mid* 14. k: stb mid wire tension, tons* 15. l: stb mid wire out, meters* 16. m: stb mid wirespeed, m/min 17. 3: starboard mid* 18. *hh: Checksum* | 2.2.2.0 |
| WLP - Scantrol winch length (port) | <pre>\$SCWLP,a.a,M,b.b,M*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$SCWLP: Talker identifier + sentence formatter* 2. a.a,M: paid out wire in meters* 3. b.b,M: wirespeed in meters/sec., positive when paying out wire 4. *hh: Checksum* | 1.0.6.0 |
| WLS - Scantrol winch length (starboard) | <pre>\$SCWLS,a.a,M,b.b,M*hh<CR><LF></pre> | 1.0.6.0 |

| NMEA Sentence | Format | First compliant version of Scala |
|---|--|----------------------------------|
| | <ol style="list-style-type: none"> 1. \$SCWLS: Talker identifier + sentence formatter* 2. a.a,M: paid out wire in meters* 3. b.b,M: wirespeed in meters/sec., positive when paying out wire 4. *hh: Checksum* | |
| WLC - Scantrol winch length (clump) | <p>\$SCWLC, a . a , M , b . b , M * hh < CR > < LF ></p> <ol style="list-style-type: none"> 1. \$SCWLC: Talker identifier + sentence formatter* 2. a.a,M: paid out wire in meters* 3. b.b,M: wirespeed in meters/sec., positive when paying out wire 4. *hh: Checksum* | 1.0.6.0 |
| WLD - Scantrol winch length (triple trawl - port clump) | <p>\$SCWLD, a . a , T * hh < CR > < LF ></p> <ol style="list-style-type: none"> 1. \$SCWLD: Talker identifier + sentence formatter* 2. a.a,M: paid out wire in meters* 3. b.b,M: wirespeed in meters/sec., positive when paying out wire 4. *hh: Checksum* | 2.0.0.0 |
| WLE - Scantrol winch length (quad trawl - center clump) | <p>\$SCWLE, a . a , T * hh < CR > < LF ></p> <ol style="list-style-type: none"> 1. \$SCWLE: Talker identifier + sentence formatter* 2. a.a,M: paid out wire in meters* 3. b.b,M: wirespeed in meters/sec., positive when paying out wire 4. *hh: Checksum* | 2.0.0.0 |
| WTP - Scantrol winch tension (port) | <p>\$SCWTP, a . a , T * hh < CR > < LF ></p> <ol style="list-style-type: none"> 1. \$SCWTP: Talker identifier + sentence formatter* 2. a.a,T: tension in tons* 3. *hh: Checksum* | 1.0.6.0 |

| NMEA Sentence | Format | First compliant version of Scala |
|--|--|----------------------------------|
| WTS - Scantrol winch tension (starboard) | <pre>\$SCWTS,a.a,T*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$SCWTS: Talker identifier + sentence formatter* 2. a.a,T: tension in tons* 3. *hh: Checksum* | 1.0.6.0 |
| WTC - Scantrol winch tension (clump) | <pre>\$SCWTC,a.a,T*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$SCWTC: Talker identifier + sentence formatter* 2. a.a,T: tension in tons* 3. *hh: Checksum* | 1.0.6.0 |
| WTD - Scantrol winch tension (triple trawl - port clump) | <pre>\$SCWTD,a.a,T*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$SCWTD: Talker identifier + sentence formatter* 2. a.a,T: tension in tons* 3. *hh: Checksum* | 2.0.0.0 |
| WTE - Scantrol winch tension (quad trawl - center clump) | <pre>\$SCWTD,a.a,T*hh<CR><LF></pre> <ol style="list-style-type: none"> 1. \$SCWTD: Talker identifier + sentence formatter* 2. a.a,T: tension in tons* 3. *hh: Checksum* | 2.0.0.0 |

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