GSFlib, The Generic Sensor Format Library

26 April 2019
## REVISIONS

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<td>Various</td>
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1. INTRODUCTION

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

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

1.1 Implementation Concept

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

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

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

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

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

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

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

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

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

30 Jun 2006    GSF-v2.04    Added support for EM121A data received via Kongsberg SIS. Added support for EM3000D and EM3002D in gsfIsStarboard ping function. Added new service to allow calling programs to register a callback function for reporting progress of index file creation. Updated gsfCopyRecords to copy all HV Nav Error data from source to target data structure. Updates to support compilation on 64-bit architectures, and compilation on MAC OSX operating system.

09 Mar 2007    GSF-v2.05    Added support for bathymetry data from the GeoAcoustics Ltd. GS+ Interferometric side-scan sonar system. Reserve sub-record IDs for the Kongsberg EM122, EM302, and EM710 systems.

04 Sep 2007    GSF-v2.06, GSF-v2.07    Added support for the Kongsberg EM122, EM302, and EM710 multibeam systems. Added application level control over the field size to be used for a subset of the beam array subrecords. Improved error checking in gsfLoadScaleFactor(). Fixed a problem in DecodeSignedByteArray that was only an issue on the SGI platform.

03 Dec 2007    GSF-v2.08    Modified the approach used to parse the beam array subrecords to no longer depend on the compression flag field of the scale factor subrecord for determining the field size. This dependency on the compression flag field was added in GSFv2.06 on the premise that a default value of zero could (always) be expected.

30 Jan 2008    GSF-v2.09    Added support for Klein 5410 Bathymetric Sidescan.

20 Mar 2009    GSF-v03.01    Added support for the Reson 7125 and EM2000. Added fields for height, separation, and gps tide corrector to the gsfSwathBathyPing record. Added new processing parameter record values: vessel_type, full_raw_data, msb_applied_to_attitude, heave_removed_from gps_tc. Added new sensor ids for EM3 sensors to differentiate between data logged from the depth datagram and the raw range and beam angle datagram.
24 Sep 2010   GSF-v03.02   Added support for KM2040. Added support for Imagenex Delta-T. Add new query functions to provide calling applications with a simple means to determine what data are contained in the GSF file and what processing operations can be supported given the parameters available in the input file. Added separation uncertainty field to the Navigation uncertainty record. Several bugs resolved.

24 Sep 2011   GSF-v03.03   Added support for Kongsberg EM12 and R2Sonic

18 April 2012 GSF-v03.04   Several bugs resolved.

30 March 2014 GSF-v03.05   Geodetic functions added. Added new ping subarray for sonar’s vertical uncertainty. Added support for files larger than 2 gigabytes in size. Added support for different number of multibeam transmitters and receivers. Some bugs resolved.

30 June 2014  GSF-v03.06   Minor update to correct large file support issues new to GSF-v03.06.

31 October 2016 GSF-v03.07  Minor update to correct appending to GSF index files.

2 October 2018 GSF-v03.08   Added support for Reson T Series multibeam systems.

4 April 2019   GSF-v03.09   Added support for Kongsberg Multibeam sonars using the KMALL format. Added functionality for storing GSF compressed. Update gsfLoadDepthScaleFactorAutoOffset to work with ERS corrected pings. Added additional vertical datums.

1.3 Restrictions and Limitations

The following restrictions or limitations apply to the GSFlib code.

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

• Time is recorded in precise form only with fractional seconds included in all time fields. The beginning of the epoch is required to be midnight of 1 January 1970, thus data recorded prior to this date is not supported. All times in GSF are required to be relative to UTC.

• The only horizontal datum supported is “WGS-84”; supported tidal datums include “UNKNOWN”, “MLLW”, “MLW”, “ALAT”, “ESLW”, “ISLW”, “LAT”, “LLW”, “LNLW”, “LWD”, “MLHW”, “MLLWS”, “MLWN”, “MSL”, “ALLW”, “LNT”, “AMLWS”, “AMLW”, “MLWS”, “AMSL”, “AMLW”, “AISLW”, and “ALLWS”. This is a limitation with the data structure gsfMBParams which represents horizontal and vertical datums as integers. Only these datums have integer definitions in gsf.h.

• Data record compression is not supported.

• The current version of GSFlib library does provide text string translations for all error code returns; however, all definitions do not have unique values.

• The name of the gsfSwathBathySummary record implies that the data in this structure is specific to the Swath Bathy Ping Record. This is not the case; the data structure is implemented to represent the Summary Record as defined in the specification.

1.4 References

Generic Sensor Format Specification, 02 May 2014, Prepared for: Naval Oceanographic Office, Stennis Space Center, MS, by Leidos, 221 Third Street, Newport RI.

1.5 Distribution

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

Multibeam echosounders

- Elac Bottomchart Mk II
- RESON SEABAT 9000 Series
- RESON 7125
- RESON 8101
- RESON 8111
- RESON 8124
- RESON 8125
- RESON 8150
- RESON 8160
- RESON T-SERIES (T-50, T-20)
- SeaBeam 2100 series
- Kongsberg EM12
- Kongsberg EM100
- Kongsberg EM121
- Kongsberg EM121A
- Kongsberg EM300
- Kongsberg EM950
- Kongsberg EM1000
- Kongsberg EM1002
- Kongsberg EM2000
- Kongsberg EM3000 and EM3000D
- Kongsberg EM120
• Kongsberg EM3002 and EM3002D
• Kongsberg EM122
• Kongsberg EM302
• Kongsberg EM710
• Kongsberg EM2040
• Kongsberg KMALL Systems
• Imagenex Delta-T
• R2Sonic 2022
• R2Sonic 2024
• R2Sonic 2020

Interferrometric Side-Scan Systems
• SEAMAP
• GeoAcoustics GS+

Multibeam Archival Formats
• Compressed SASS

Single-beam Echosounders
• Odom Echotrac
• ODEC Bathy2000
• Reson Navisound

Single-beam Archival Formats
• MGD77
• BDB
• NOS HDB

Bathymetric Sidescan Systems
1.7 Computer Platforms Supported

The GSF library has been used on the following platforms:

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

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

When compiling the source code in Linux, the –D_LARGEFILE_SOURCE flag must be used to provide access to the fopen64, stat64, ftelloc64, and fseeko64 functions. When compiling in Windows/mingW, these functions are available without this define. When compiling in Windows/MSC, the _ftelli64 and _fseeki64 functions are readily available.

1.8 Documentation Conventions

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

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

2.1 Access Functions

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

2.1.1 Function: gsfOpen

Usage:

```c
int gsfOpen(const char *filename,
            const int   mode    ,
            int        *handle  )
```

Description:

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

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

Inputs:
filename  a fully qualified path to the GSF file to be opened

mode  may have the following values:

  * GSF_READONLY  open an existing file for read-only access
  * GSF_UPDATE  open an existing file for reading and writing
  * GSF_CREATE  create a new GSF file
  * GSF_READONLY_INDEX  open an existing file for read only access with an index file
  * GSF_UPDATE_INDEX  open an existing file for reading and writing with an index file
  * GSF_APPEND  open an existing file for appending

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

Returns:

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

Error Conditions:

  * GSF_BAD_ACCESS_MODE
  * GSF_FILE_SEEK_ERROR
  * GSF_FLUSH_ERROR
  * GSF_FOPEN_ERROR
  * GSF_READ_ERROR
  * GSF_SETVBUF_ERROR
  * GSF_TOO_MANY_OPEN_FILES
  * GSF_UNRECOGNIZED_FILE
  * GSF_OPEN_TEMP_FILE_FAILED
  * GSF_CORRUPT_INDEX_FILE_ERROR
2.1.2 Function: gsfOpenBuffered

Usage:

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

Description:

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

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

Inputs:
filename

a fully qualified path to the GSF file to be opened

mode

can have the following values:

- GSF_READONLY open an existing file for read-only access
- GSF_UPDATE open an existing file for reading and writing
- GSF_CREATE create a new GSF file
- GSF_READONLY_INDEX open an existing file for read-only access with an index file
- GSF_UPDATE_INDEX open an existing file for reading and writing with an index file
- GSF_APPEND open an existing file for appending

handle

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

buf_size

an integer buffer size in bytes.

Returns:

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

Error Conditions:

- GSF_BAD_ACCESS_MODE
- GSF_FILESEEK_ERROR
- GSF_FLUSH_ERROR
- GSF_FOPEN_ERROR
- GSF_READ_ERROR
- GSF_SETVBUF_ERROR
- GSF_TOO_MANY_OPEN_FILES
GSF_UNRECOGNIZED_FILE

GSF_OPEN_TEMP_FILE_FAILED

GSF_CORRUPT_INDEX_FILE_ERROR

GSF_INDEX_FILE_OPEN_ERROR

GSF_FILE_TELL_ERROR

GSF_MEMORY_ALLOCATION_FAILED
2.1.3 Function: gsfRead

Usage:

```c
int gsfRead(int handle,
            int desiredRecord,
            gsfDataID *dataID,
            gsfRecords *rptr,
            unsigned char *buf,
            int max_size)
```

Description:

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

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

Inputs:
handle the handle to the file as provided by `gsfOpen` or `gsfOpenBuffered`
desiredRecord the desired record or `GSF_NEXT_RECORD`
dataID a pointer to a `gsfDataID` structure to be populated for the input record.
ptr a pointer to a `gsfRecords` structure to be populated with the data from the input record in internal form.
buf an optional pointer to caller memory to be populated with a copy of the GSF byte stream for this record.
max_size an optional maximum size to copy into `buf`

**Returns:**

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

**Error Conditions:**

- `GSF_ATTITUDE_RECORD_DECODE_FAILED`
- `GSF_BAD_FILE_HANDLE`
- `GSF_CHECKSUM_FAILURE`
- `GSF_COMMENT_RECORD_DECODE_FAILED`
- `GSF_FILE_SEEK_ERROR`
- `GSF_FLUSH_ERROR`
- `GSF_HEADER_RECORD_DECODE_FAILED`
- `GSF_HISTORY_RECORD_DECODE_FAILED`
- `GSF_HV_NAV_ERROR_RECORD_DECODE_FAILED`
- `GSF_INSUFFICIENT_SIZE`
- `GSF_NAV_ERROR_RECORD_DECODE_FAILED`
2.1.4 Function: gsfWrite

Usage:

```c
int gsfWrite(int         handle,
             gsfDataID  *id,
             gsfRecords *rptr)
```

Description:

gsfWrite encodes the data from internal to external form, and then writes the requested record into the file specified by handle, where handle is the value returned by either gsfOpen or gsfOpenBuffered. The record is written to the current file pointer for handle. An optional checksum may be computed and encoded with the data if the checksum flag is set in the gsfDataID structure. If the file is opened for sequential access (GSF_CREATE, or GSF_UPDATE) then the recordID field of the gsfDataID structure is used to specify the record to be written.
When opening the file for direct access (GSF_UPDATE_INDEX), the combination of the recordID and the record_number fields of the gsfDataID structure uniquely identify the record to write. The address of the record of interest is read from the index file and the file pointer is moved to this offset before the record is encoded and written to disk.

**Inputs:**

- handle: the handle for this file as returned by gsfOpen
- id: a pointer to a gsfDataID containing the record ID information for the record to write.
- rptr: a pointer to a gsfRecords structure from which to get the internal form of the record to be written to the file.

**Returns:**

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

**Error Conditions:**

- GSF_ATTITUDE_RECORD_ENCODE_FAILED
- GSF_BAD_FILE_HANDLE
- GSF_COMMENT_RECORD_ENCODE_FAILED
- GSF_FILE_SEEK_ERROR
- GSF_FLUSH_ERROR
- GSF_HEADER_RECORD_ENCODE_FAILED
- GSF_HISTORY_RECORD_ENCODE_FAILED
- GSF_HV_NAV_ERROR_RECORD_ENCODE_FAILED
GSF_NAV_ERROR_RECORD_ENCODE_FAILED

GSF_PROCESS_PARAM_RECORD_ENCODE_FAILED

GSF_SENSOR_PARAM_RECORD_ENCODE_FAILED

GSF_SINGLE_BEAM_ENCODE_FAILED

GSF_SUMMARY_RECORD_ENCODE_FAILED

GSF_SVP_RECORD_ENCODE_FAILED

GSF_UNRECOGNIZED_RECORD_ID

GSF_UNRECOGNIZED_SENSOR_ID

GSF_WRITE_ERROR

GSF_ILLEGAL_SCALE_FACTOR_MULTIPLIER

GSF_INVALID_RECORD_NUMBER

GSF_RECORD_TYPE_NOTAVAILABLE

GSF_INDEX_FILE_READ_ERROR

2.1.5 Function: gsfSeek

Usage:

    int gsfSeek(int handle,
                int option)

Description:

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

Inputs:

handle the integer handle returned from gsfOpen or gsfOpenBuffered
option: the desired action for moving the file pointer, where:

- `GSF_REWIND` moves the pointer to first record in the file.
- `GSF_END_OF_FILE` moves the pointer to the end of the file.
- `GSF_PREVIOUS_RECORD` backup to the beginning of the record just written or just read.

Returns:

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

Error Conditions:

- `GSF_BAD_FILE_HANDLE`
- `GSF_BAD_SEEK_OPTION`
- `GSF_FILE_SEEK_ERROR`
- `GSF_FLUSH_ERROR`

2.1.6 Function: gsfClose

Usage:

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

Description:

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

Inputs:

- `handle`: the handle of the GSF file to be closed.
Returns:

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

Error Conditions:

- *GSF_BAD_FILE_HANDLE*
- *GSF_FILE_CLOSE_ERROR*
2.2 Utility Functions

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

2.2.1 Function: gsfCopyRecords

Usage:

    int gsfCopyRecords (gsfRecords *target,
                        const gsfRecords *source)

Description:

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

Inputs:

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

Returns:

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

Error Conditions:

    GSF_MEMORY_ALLOCATION_FAILED
2.2.2 Function: gsfFree

**Usage:**

```c
void gsfFree (gsfRecords *rec)
```

**Description:**

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

**Inputs:**

- `rec` pointer to a `gsfRecords` data structure

**Returns:**

None

**Error Conditions:**

None

2.2.3 Function: gsfPutMBParams

**Usage:**

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

**Description:**

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

Inputs:

P  a pointer to the gsfMBParams data structure which contains the parameters in internal
form.

rec  a pointer to the gsfRecords data structure into which the parameters are to be written in the
"KEYWORD=VALUE" form.

handle  the integer handle to the file set by gsfOpen or gsfOpenBuffered

numArrays  the integer value specifying the number of pairs of arrays that need to have separate
parameters tracked.

Returns:

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

Error Conditions:


GSF_MEMORY_ALLOCATION_FAILED

GSF_PARAM_SIZE_FIXED
2.2.4 Function: gsfGetMBParams

Usage:

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

Description:

This function moves swath bathymetry sonar processing parameters from external form to internal form. The external "KEYWORD=VALUE" format parameters are read from a gsfProcessingParameters structure of the gsfRecords data structure maintained by the caller. Any parameter not described in a "KEYWORD=VALUE" format will be set to “GSFUNKNOWN_PARAM_VALUE”. The internal form parameters are written into a gsfMBParams data structure maintained by the caller. Parameters for up to two transmitters and two receivers are supported. The 'number_of_transmitters' and 'number_of_receivers' elements of the gsfMBParams data structure are set by determining the number of fields in the parameters for the transmitter(s) and receiver(s), respectively. The ‘numArrays’ argument is set from the number of fields for the transmitter(s).

Inputs:

rec 
a pointer to the gsfRecords data structure from which the parameters in "KEYWORD=VALUE" form are to be read.

p 
a pointer to the gsfMBParams data structure which will be populated.

numArrays 
the integer value specifying the number of pairs of arrays which need to have separate parameters tracked.

Returns:

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

Error Conditions:
None.

2.2.5 Function: gsfStat

Usage:

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

Description:

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

Inputs:

filename    A fully qualified path to the GSF file.

sz          A pointer to an 8 byte long long for return of a GSF file size from a stat64 call.

Returns:

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

Error Conditions:

    GSF_FOPEN_ERROR
    GSF_UNRECOGNIZED_FILE

2.2.6 Function: gsfLoadScaleFactor

Usage:

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

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

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

\[
\text{scaled \_value} = (\text{beam \_value} + \text{offset}) / \text{precision}
\]

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

\[
\text{beam \_value} = (\text{scaled \_value} / \text{precision}) - \text{offset}
\]

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

**Table 2-1 GSF Beam Array Field Size Definitions**
<table>
<thead>
<tr>
<th>Array Subrecord</th>
<th>Data Representation</th>
<th>Size, bits</th>
<th>Scaled Dynamic Range</th>
</tr>
</thead>
<tbody>
<tr>
<td>DEPTH</td>
<td>unsigned short (default)</td>
<td>16</td>
<td>0 to 65535</td>
</tr>
<tr>
<td></td>
<td>unsigned int (option)</td>
<td>32</td>
<td>0 to 4294967295</td>
</tr>
<tr>
<td>NOMINAL DEPTH</td>
<td>unsigned short (default)</td>
<td>16</td>
<td>0 to 65535</td>
</tr>
<tr>
<td></td>
<td>unsigned int (option)</td>
<td>32</td>
<td>0 to 4294967295</td>
</tr>
<tr>
<td>ACROSS_TRACK</td>
<td>signed short (default)</td>
<td>16</td>
<td>-32768 to 32767</td>
</tr>
<tr>
<td></td>
<td>signed int (option)</td>
<td>32</td>
<td>-2147483648 to 2147483647</td>
</tr>
<tr>
<td>ALONG_TRACK</td>
<td>signed short (default)</td>
<td>16</td>
<td>-32768 to 32767</td>
</tr>
<tr>
<td></td>
<td>signed int (option)</td>
<td>32</td>
<td>-2147483648 to 2147483647</td>
</tr>
<tr>
<td>TRAVEL_TIME</td>
<td>unsigned short (default)</td>
<td>16</td>
<td>0 to 65535</td>
</tr>
<tr>
<td></td>
<td>unsigned int (option)</td>
<td>32</td>
<td>0 to 4294967295</td>
</tr>
<tr>
<td>BEAM_ANGLE</td>
<td>signed short</td>
<td>16</td>
<td>-32768 to 32767</td>
</tr>
<tr>
<td>MEAN_CALAMPLITUDE</td>
<td>signed byte (default)</td>
<td>8</td>
<td>-128 to 127</td>
</tr>
<tr>
<td></td>
<td>signed short (option)</td>
<td>16</td>
<td>-32768 to 32767</td>
</tr>
<tr>
<td>MEAN_RELAMPLITUDE</td>
<td>unsigned byte (default)</td>
<td>8</td>
<td>0 to 255</td>
</tr>
<tr>
<td></td>
<td>unsigned short (option)</td>
<td>16</td>
<td>0 to 65535</td>
</tr>
<tr>
<td>ECHO_WIDTH</td>
<td>unsigned byte (default)</td>
<td>8</td>
<td>0 to 255</td>
</tr>
<tr>
<td></td>
<td>unsigned short (option)</td>
<td>16</td>
<td>0 to 65535</td>
</tr>
<tr>
<td>QUALITY_FACTOR</td>
<td>unsigned byte</td>
<td>8</td>
<td>0 to 255</td>
</tr>
<tr>
<td>RECEIVE_HEAVE</td>
<td>signed byte</td>
<td>8</td>
<td>-128 to 127</td>
</tr>
<tr>
<td>DEPTH_ERROR</td>
<td>unsigned short</td>
<td>16</td>
<td>0 to 65535</td>
</tr>
<tr>
<td>ACROSS_TRACK_ERROR</td>
<td>unsigned short</td>
<td>16</td>
<td>0 to 65535</td>
</tr>
</tbody>
</table>
### ALONG TRACK ERROR
- **Type:** unsigned short
- **Size:** 16
- **Range:** 0 to 65535

### QUALITY_FLAGS
- **Type:** unsigned byte
- **Size:** 8
- **Range:** 0 to 255

### BEAM_FLAGS
- **Type:** unsigned byte
- **Size:** 8
- **Range:** 0 to 255

### SIGNAL_TO_NOISE
- **Type:** signed byte
- **Size:** 8
- **Range:** -128 to 127

### BEAM_ANGLE_FORWARD
- **Type:** signed short
- **Size:** 16
- **Range:** -32768 to 32767

### VERTICAL_ERROR
- **Type:** unsigned short
- **Size:** 16
- **Range:** 0 to 65535

### HORIZONTAL_ERROR
- **Type:** unsigned short
- **Size:** 16
- **Range:** 0 to 65535

### SECTOR_NUMBER
- **Type:** unsigned byte
- **Size:** 8
- **Range:** 0 to 255

### DETECTION_INFO
- **Type:** unsigned byte
- **Size:** 8
- **Range:** 0 to 255

### INCIDENT_BEAM_ADJUSTEMENT
- **Type:** signed byte
- **Size:** 8
- **Range:** -128 to 127

### SYSTEM_CLEANING
- **Type:** unsigned byte
- **Size:** 8
- **Range:** 0 to 255

### DOPPLER_CORRECTION
- **Type:** signed byte
- **Size:** 8
- **Range:** -128 to 127

**Inputs:**

- **sf**
  - A pointer to the `gsfScaleFactors` structure to be loaded

- **subrecordID**
  - The subrecord id for the beam array data

- **c_flag**
  - The compression flag for the beam array. This is a bit mask that combines the caller specified field size in the higher order four bits with the lower four bits reserved for future use to specify a compression algorithm. The supported field size values are defined as macros in gsf.h (GSF_FIELD_SIZE_DEFAULT, etc).

- **precision**
  - The precision to which the beam array data are to be stored (a value of 0.1 would indicate decimeter precision for depth)

- **offset**
  - The "DC" offset to scale the data by.

**Outputs:**

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

**Error Conditions:**

- **GSF_CANNOT_REPRESENT PRECISION**
- **GSF_TOO_MANY_ARRAY_SUBRECORDS**

### 2.2.7 Function: gsfGetScaleFactor

**Usage:**

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

**Description:**

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

**Inputs:**

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

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

**Error Conditions:**

- `GSF_BAD_FILE_HANDLE`
- `GSF_ILLEGAL_SCALE_FACTOR_MULTIPLIER`
- `GSF_TOO_MANY_ARRAY_SUBRECORDS`

### 2.2.8 Function: gsfSetDefaultScaleFactor

**Usage:**

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

**Description:**

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

**Inputs:**

| mb_ping | a pointer to the `gsfSwathBathyPing` which contains the beam arrays and will contain the estimated... |
Returns:

The function returns 0 to indicate success.

Error Conditions:

None.

2.2.9 Function: gsfLoadDepthScaleFactorAutoOffset

Usage:

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

Description:

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

Inputs:
ping

a pointer to the `gsfSwathBathyPing` which contains the depth and tide correction values, and the scale factors data structure.

subrecordID

an integer value containing the subrecord ID for the beam array data; this must be either `GSF_SWATH_BATHY_SUBRECORD_DEPTH_ARRAY`, or `GSF_SWATH_BATHY_SUBRECORD_NOMINAL_DEPTH_ARRAY`.

reset

an integer value that will cause the internal logic to be refreshed when the value is non-zero; the first call to this function should use a non-zero reset, from then on, this value may be passed as zero.

min_depth

a double value that should be set to the minimum depth value contained in the depth array specified by `subrecordID`; this argument exists for completeness, but is currently not used.

max_depth

a double value that should be set to the maximum depth value contained in the depth array specified by `subrecordID`; when a depth threshold is exceeded, the offset used to support “signed depth” is no longer required and will no longer be used. This approach is necessary to avoid an integer overflow when the array data are scaled.

last_corrector

an address of a double value stored as permanent memory; successive calls to this function must pass the same address for this argument. This function will take care of setting the value at this address, but the caller is responsible for ensuring that the same permanent memory address is used for each call to this function.

C_flag

the compression flag for the beam array. This is a bit mask that combines the (optional) caller specified field size in the higher order four bits with the lower four bits reserved for future use to specify a compression algorithm. The supported field size values are defined as macros in `gsf.h` (GSF_FIELD_SIZE_DEFAULT, etc). See section 2.2.5 on `gsfLoadScaleFactor` for more information.

precision

the precision to which the beam array data are to be stored (a value of 0.1 would indicate decimeter precision for depth).

Returns:

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

- `GSF_UNRECOGNIZED_ARRAY_SUBRECORD_ID`
- `GSF_CANNOT_REPRESENT_PRECISION`
- `GSF_TOO_MANY_ARRAY_SUBRECORDS`

### 2.2.10 Function: `gsfGetPositionDestination`

**Usage:**

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

**Description:**

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

**Inputs:**

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

**Returns:**

This function returns the destination position.

**Error Conditions:**

None.

### 2.2.11 Function: `gsfGetPositionOffsets`

**Usage:**

```c
```

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

**Description:**

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

**Inputs:**

- gp_from: Reference position (in degrees).
- gp_to: Destination position (in degrees).
- heading: Platform heading (in degrees).
- dist_step: Distance increment used in step-wise calculation to destination (typically 5 – 10 meters).

**Returns:**

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

**Error Conditions:**

None.

### 2.2.12 Macro: gsfTestPingStatus

**Usage:**

```c
unsigned short gsfTestPingStatus(ping_flags, usflag)
```

**Description:**

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

- ping_flags: The contents of the ping_flags field.
- usflag: An unsigned short integer with a single bit set to identify the flag being tested.

**Returns:**

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

**Error Conditions:**

None

### 2.2.13 Macro: gsfSetPingStatus

**Usage:**

```c
unsigned short gsfSetPingStatus(ping_flags, usflag)
```

**Description:**

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

**Inputs:**

- ping_flags: The original contents of the ping_flags field.
- usflag: An unsigned short integer with a single bit set to identify the flag to be set.

**Returns:**

A new copy of the ping_flags field with the corresponding bit set.
Error Conditions:
None

2.2.14 Macro: gsfClearPingStatus

Usage:

```c
unsigned short gsfClearPingStatus(ping_flags, usflag)
```

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

Inputs:
- `ping_flags` The original contents of the `ping_flags` field.
- `usflag` An unsigned short integer with a single bit set to identify the flag to be cleared.

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

Error Conditions:
None

2.3 Information Functions

Information functions include those that
- decode error conditions,
- return the time associated with a record at a specific location,
• return the location of the file pointer as a percentage of the total file size,

• provide the number and types of records within a file,

• provide information about beam widths of various types of sonar data

• for sonars with two transducers, determine whether a specific data record is from the starboard or port transducer.

• provide the name of the sensor

2.3.1 Function: gsfIntError

Usage:

```c
int gsfIntError(void)
```

Description:

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

Inputs:

None

Returns:

The current value of gsfError

Error Conditions:

None

2.3.2 Function: gsfPrintError

Usage:

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


**Description:**

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

**Inputs:**

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

**Returns:**

None

**Error Conditions:**

None

### 2.3.3 Function: gsfStringError

**Usage:**

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

**Description:**

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

**Inputs:**

None

**Returns:**

Pointer to a string containing the text message.
Error Conditions:
None

2.3.4 Function: gsfIndexTime

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

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

Inputs:
- **handle**: GSF file handle assigned by `gsfOpen` or `gsfOpenBuffered`
- **record_type**: record type to be retrieved
- **record_number**: record number to be retrieved  (Setting this argument to -1 will get the time and record number of the last record of type `record_type`)
- **sec**: Seconds since the beginning of the epoch (as defined in the GSF processing parameter record.)
- **nsec**: Nanoseconds since the beginning of the second.

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

**Error Conditions:**

- `GSF_FILESEEK_ERROR`
- `GSF_INDEX_FILE_READ_ERROR`
- `GSF_RECORD_TYPE_NOT_AVAILABLE`

### 2.3.5 Function: **gsfPercent**

**Usage:**

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

**Description:**

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

**Inputs:**

- `handle`: gsf file handle assigned by `gsfOpen` or `gsfOpenBuffered`

**Returns:**

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

GSF_BAD_FILE_HANDLE

GSF_FILE_TELL_ERROR

2.3.6 Function: gsfGetNumberRecords

Usage:

int gsfGetNumberRecords (int handle,
                          int desiredRecord)

Description:
This function returns the number of records of a given type. The number of records is retrieved from the index file, so the file must have been opened for direct access (GSF_READONLY_INDEX, or GSF_UPDATE_INDEX).

Inputs:

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

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

Error Conditions:

GSF_BAD_FILE_HANDLE
2.3.7 Function: gsfGetSwathBathyBeamWidths

Usage:

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

Description:

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

Inputs:

data

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

fore_aft

The address of a double allocated by the caller which will be loaded with the sonar's fore/aft beam width in degrees. A value of GSF_BEAM_WIDTH_UNKNOWN is used when the beam width is not known.

athwartship

The address of a double allocated by the caller which will be loaded with the sonar's athwartship beam width in degrees. A value of GSF_BEAM_WIDTH_UNKNOWN is used when the beam width is not known.

Returns:

This function returns zero if successful, or -1 if an error occurred. `gsfError` is set to indicate the error.
Error Conditions:
None.

2.3.8 Function: `gsfGetSwathBathyArrayMinMax`

Usage:

```c
int gsfGetSwathBathyArrayMinMax(const gsfSwathBathyPing *ping,
                                   int subrecordID,
                                   double *min_value,
                                   double *max_value)
```

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

Inputs:

- **ping**
  The address of a `gsfSwathBathyPing` data structure that contains the depth and tide correction values, as well as the scale factors data structure.

- **subrecordID**
  The subrecord ID for the beam array data.

- **min_value**
  The address of a double value allocated by the caller into which will be placed the minimum value that may be represented for this array type.

- **max_value**
  The address of a double value allocated by the caller into which will be placed the maximum value that may be represented for this array type.

Returns:
This function returns zero if successful, or -1 if an error occurred. `gsfError` is set to indicate the error.
Error Conditions:

- **GSF_UNRECOGNIZED_ARRAY_SUBRECORD_ID**
- **GSF_ILLEGAL_SCALE_FACTOR_MULTIPLIER**

### 2.3.9 Function: `gsfIsStarboardPing`

**Usage:**

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

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

**Inputs:**

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

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

**Error Conditions:**
None
2.3.10 Function: gsf_register_progress_callback

Usage:

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

Description:

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

Inputs:

- `progressCB` The name of the progress callback function to call when creating the GSF index file. The progress callback will accept two integer arguments, and this function will be called whenever the percent complete changes. This first argument will be one of the following three values, to represent the state of the progress:
  
  1 = Reading GSF file
  
  2 = Creating new index file
  
  3 = Appending to existing index file

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

Returns:

None

Error Conditions:

None
2.3.11 Function: gsfGetSonarTextName

Usage:

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

Description:

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

Inputs:

Ping

The address of a `gsfSwathBathyPing` data structure that contains the sensor_id value, as well as the mode value (mode is used for the Reson SeaBat 9001, 9002, and 9003)

Returns:

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

Error Conditions:

None

2.3.12 Function: gsfFileSupportsRecalculateXYZ

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

Description:

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

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

**status**  
A pointer to an integer allocated by caller into which the function result is placed. `*status` is assigned a value of 1 if this file provides sufficient information to support full recalculation of the platform relative XYZ values, otherwise `*status` is assigned a value of 0.

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

**Error Conditions:**

- `GSF_BAD_FILE_HANDLE`
- `GSF_FILE_SEEK_ERROR`
- `GSF_FLUSH_ERROR`
- `GSF_READ_TO_END_OF_FILE`
- `GSF_PARTIAL_RECORD_AT_END_OF_FILE`
- `GSF_READ_ERROR`
- `GSF_RECORD_SIZE_ERROR`
- `GSF_INSUFFICIENT_SIZE`
- `GSF_CHECKSUM_FAILURE`
- `GSF_UNRECOGNIZED_RECORD_ID`
- `GSF_HEADER_RECORD_DECODE_FAILED`
- `GSF_SVP_RECORD_DECODE_FAILED`
- `GSF_PROCESS_PARAM_RECORD_DECODE_FAILED`
- `GSF_SENSOR_PARAM_RECORD_DECODE_FAILED`
- `GSF_COMMENT_RECORD_DECODE_FAILED`
- `GSF_HISTORY_RECORD_DECODE_FAILED`
GSF_NAV_ERROR_RECORD_DECODE_FAILED
GSF_ATTITUDE_RECORD_DECODE_FAILED
GSF_HV_NAV_ERROR_RECORD_DECODE_FAILED
GSF_SUMMARY_RECORD_DECODE_FAILED
GSF_UNRECOGNIZED_SUBRECORD_ID
GSF_INVALID_RECORD_NUMBER
GSF_RECORD_TYPE_NOT_AVAILABLE
GSF_INDEX_FILE_READ_ERROR

2.3.13 Function: gsfFileSupportsRecalculateTPU

Usage: int gsfFileSupportsRecalculateTPU(int handle, int *status)

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

Inputs:

Handle
GSF file handle assigned by gsfOpen or gsfOpenBuffered

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

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

GSF_BAD_FILE_HANDLE
GSF_FILESEEK_ERROR
GSF_FLUSH_ERROR
GSF_READ_TO_END_OF_FILE
GSF_PARTIAL_RECORD_AT_END_OF_FILE
GSF_READ_ERROR
GSF_RECORD_SIZE_ERROR
GSF_INSUFFICIENT_SIZE
GSF_CHECKSUM_FAILURE
GSF_UNRECOGNIZED_RECORD_ID
GSF_HEADER_RECORD_DECODE_FAILED
GSF_SVP_RECORD_DECODE_FAILED
GSF_PROCESS_PARAM_RECORD_DECODE_FAILED
GSF_SENSOR_PARAM_RECORD_DECODE_FAILED
GSF_COMMENT_RECORD_DECODE_FAILED
GSF_HISTORY_RECORD_DECODE_FAILED
GSF_NAV_ERROR_RECORD_DECODE_FAILED
GSF_ATTITUDE_RECORD_DECODE_FAILED
GSF_HV_NAV_ERROR_RECORD_DECODE_FAILED
GSF_SUMMARY_RECORD_DECODE_FAILED
GSF_UNRECOGNIZED_SUBRECORD_ID
GSF_INVALID_RECORD_NUMBER
GSF_RECORD_TYPE_NOT_AVAILABLE
GSF_INDEX_FILE_READ_ERROR
2.3.14 Function: gsfFileSupportsRecalculateNominalDepth

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

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

Inputs:

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

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

Error Conditions:

GSF_BAD_FILE_HANDLE
GSF_FILESEEK_ERROR
GSF_FLUSH_ERROR
GSF_READ_TO_END_OF_FILE
GSF_PARTIAL_RECORD_AT_END_OF_FILE
GSF_READ_ERROR
GSF_RECORD_SIZE_ERROR
GSF_INSUFFICIENT_SIZE
GSF_CHECKSUM_FAILURE
GSF_UNRECOGNIZED_RECORD_ID
GSF_HEADER_RECORD_DECODE_FAILED
GSF_SVP_RECORD_DECODE_FAILED
GSF_PROCESS_PARAM_RECORD_DECODE_FAILED
GSF_SENSOR_PARAM_RECORD_DECODE_FAILED
GSF_COMMENT_RECORD_DECODE_FAILED
GSF_HISTORY_RECORD_DECODE_FAILED
GSF_NAV_ERROR_RECORD_DECODE_FAILED
GSF_ATTITUDE_RECORD_DECODE_FAILED
GSF_HV_NAV_ERROR_RECORD_DECODE_FAILED
GSF_SUMMARY_RECORD_DECODE_FAILED
GSF_UNRECOGNIZED_SUBRECORD_ID
GSF_INVALID_RECORD_NUMBER
GSF_RECORD_TYPE_NOT_AVAILABLE
GSF_INDEX_FILE_READ_ERROR

2.3.15 Function: gsfFileContainsMBAmplitude

Usage: int gsfFileContainsMBAmplitude(int handle, int *status)

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

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

**status**
A pointer to an integer allocated by caller into which the function result is placed. `*status` is assigned a value of 1 if this file contains the optional per-receive-beam average amplitude beam array, otherwise `*status` is assigned a value of 0.

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

**Error Conditions:**

- `GSF_BAD_FILE_HANDLE`
- `GSF_FILE_SEEK_ERROR`
- `GSF_FLUSH_ERROR`
- `GSF_READ_TO_END_OF_FILE`
- `GSF_PARTIAL_RECORD_AT_END_OF_FILE`
- `GSF_READ_ERROR`
- `GSF_RECORD_SIZE_ERROR`
- `GSF_INSUFFICIENT_SIZE`
- `GSF_CHECKSUM_FAILURE`
- `GSF_UNRECOGNIZED_RECORD_ID`
- `GSF_HEADER_RECORD_DECODE_FAILED`
- `GSF_SVP_RECORD_DECODE_FAILED`
- `GSF_PROCESS_PARAM_RECORD_DECODE_FAILED`
- `GSF_SENSOR_PARAM_RECORD_DECODE_FAILED`
- `GSF_COMMENT_RECORD_DECODE_FAILED`
- `GSF_HISTORY_RECORD_DECODE_FAILED`
GSF_NAV_ERROR_RECORD_DECODE_FAILED
GSF_ATTITUDE_RECORD_DECODE_FAILED
GSF_HV_NAV_ERROR_RECORD_DECODE_FAILED
GSF_SUMMARY_RECORD_DECODE_FAILED
GSF_UNRECOGNIZED_SUBRECORD_ID
GSF_INVALID_RECORD_NUMBER
GSF_RECORD_TYPE_NOT_AVAILAB
GSF_INDEX_FILE_READ_ERROR

2.3.16 Function: gsfFileContainsMBImagery

Usage: int gsfFileContainsMBImagery(int handle, int *status)

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

Inputs:

handle
GSF file handle assigned by gsfOpen or gsfOpenBuffered

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

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

- GSF_BAD_FILE_HANDLE
- GSF_FILESEEK_ERROR
- GSF_FLUSH_ERROR
- GSF_READ_TO_END_OF_FILE
- GSF_PARTIAL_RECORD_AT_END_OF_FILE
- GSF_READ_ERROR
- GSF_RECORD_SIZE_ERROR
- GSF_INSUFFICIENT_SIZE
- GSF_CHECKSUM_FAILURE
- GSF_UNRECOGNIZED_RECORD_ID
- GSF_HEADER_RECORD_DECODE_FAILED
- GSF_SVP_RECORD_DECODE_FAILED
- GSF_PROCESS_PARAM_RECORD_DECODE_FAILED
- GSF_SENSOR_PARAM_RECORD_DECODE_FAILED
- GSF_COMMENT_RECORD_DECODE_FAILED
- GSF_HISTORY_RECORD_DECODE_FAILED
- GSF_NAV_ERROR_RECORD_DECODE_FAILED
- GSF_ATTITUDE_RECORD_DECODE_FAILED
- GSF_HV_NAV_ERROR_RECORD_DECODE_FAILED
- GSF_SUMMARY_RECORD_DECODE_FAILED
- GSF_UNRECOGNIZED_SUBRECORD_ID
- GSF_INVALID_RECORD_NUMBER
- GSF_RECORD_TYPE_NOT_AVAILABLE
- GSF_INDEX_FILE_READ_ERROR
2.3.17 Function: gsfIsNewSurveyLine

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

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

**Inputs:**

- **handle** 
  GSF file handle assigned by gsfOpen or gsfOpenBuffered

- **rec** 
  The address of a gsfRecords data structure maintained by the caller which contains a populated gsfSwathBathyPing substructure obtained from recent call to gsfRead.

- **azimuth_change** 
  A trigger value set by the calling application to be used as the threshold for detecting the end heading change associated with the end of a survey line.

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

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

**Error Conditions:**

None.
2.3.18 Function: gsfInitializeMBParams

**Usage:** int gsfInitializeMBParams (gsfMBParams *p)

**Description:** This function provides a way to initialize all the sonar processing parameters to “unknown”.

**Inputs:**

p pointer to the gsfMBParams data structure which will be populated with “unknown”

**Returns:**

None.

**Error Conditions:**

None.

3. ERROR CODE DESCRIPTIONS

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

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

<table>
<thead>
<tr>
<th>Value of gsfError</th>
<th>Value</th>
<th>Reason for error</th>
</tr>
</thead>
<tbody>
<tr>
<td>GSF_ATTITUDE_RECORD_DECODE_FAILED</td>
<td>-50</td>
<td>“GSF Error decoding attitude record”</td>
</tr>
<tr>
<td>GSF_ATTITUDE_RECORD_ENCODE_FAILED</td>
<td>-49</td>
<td></td>
</tr>
<tr>
<td>GSF_BAD_ACCESS_MODE</td>
<td>-3</td>
<td>“GSF Error illegal access mode”</td>
</tr>
<tr>
<td>GSF_BAD_FILE_HANDLE</td>
<td>-24</td>
<td>“GSF Error bad file handle”</td>
</tr>
<tr>
<td>GSF_BADSEEK_OPTION</td>
<td>-15</td>
<td>“GSF Error unrecognized file seek option”</td>
</tr>
<tr>
<td>GSF_CANNOT_REPRESENT_PRECISION</td>
<td>-22</td>
<td>“GSF Error illegal scale factor multiplier specified”</td>
</tr>
<tr>
<td>GSF_CHECKSUM_FAILURE</td>
<td>-8</td>
<td>“GSF Error data checksum failure”</td>
</tr>
<tr>
<td>GSF_COMMENT_RECORD_DECODE_FAILED</td>
<td>-30</td>
<td>“GSF Error decoding comment record”</td>
</tr>
<tr>
<td>GSF_COMMENT_RECORD_ENCODE_FAILED</td>
<td>-30</td>
<td></td>
</tr>
<tr>
<td>GSF_CORRUPT_INDEX_FILE_ERROR</td>
<td>-37</td>
<td>“GSF Error index file is corrupted, delete index file”</td>
</tr>
<tr>
<td>GSF_FILE_CLOSE_ERROR</td>
<td>-9</td>
<td>“GSF Error closing gsf file”</td>
</tr>
<tr>
<td>GSF_FILE_SEEK_ERROR</td>
<td>-16</td>
<td>“GSF Error file seek failed”</td>
</tr>
<tr>
<td>GSF_FILE_TELL_ERROR</td>
<td>-35</td>
<td>“GSF Error file tell failed”</td>
</tr>
<tr>
<td>GSF_FLUSH_ERROR</td>
<td>-34</td>
<td>“GSF Error flushing data buffers(s)”</td>
</tr>
<tr>
<td>GSF_FOPEN_ERROR</td>
<td>-1</td>
<td>“GSF Unable to open requested file”</td>
</tr>
<tr>
<td>GSF_HEADER_RECORD_DECODE_FAILED</td>
<td>-25</td>
<td>“GSF Error decoding header record”</td>
</tr>
<tr>
<td>GSF_HEADER_RECORD_ENCODE_FAILED</td>
<td>-25</td>
<td></td>
</tr>
<tr>
<td>GSF_HISTORY_RECORD_DECODE_FAILED</td>
<td>-31</td>
<td>“GSF Error decoding history record”</td>
</tr>
<tr>
<td>GSF_HISTORY_RECORD_ENCODE_FAILED</td>
<td>-31</td>
<td></td>
</tr>
<tr>
<td>GSF_HV_NAV_ERROR_RECORD_DECODE_FAILED</td>
<td>-48</td>
<td>“GSF Error decoding horizontal/vertical navigation error record”</td>
</tr>
<tr>
<td>GSF_HV_NAV_ERROR_RECORD_ENCODE_FAILED</td>
<td>-47</td>
<td>“GSF Error encoding horizontal/vertical navigation error record”</td>
</tr>
<tr>
<td>Error Code</td>
<td>Description</td>
<td></td>
</tr>
<tr>
<td>------------</td>
<td>-------------</td>
<td></td>
</tr>
<tr>
<td>GSF_ILLEGAL_SCALE_FACTOR_MULTIPLIER</td>
<td>-21</td>
<td>“GSF Error illegal scale factor multiplier specified”</td>
</tr>
<tr>
<td>GSF_INDEX_FILE_OPEN_ERROR</td>
<td>-36</td>
<td>“GSF Error open of index file failed”</td>
</tr>
<tr>
<td>GSF_INDEX_FILE_READ_ERROR</td>
<td>-44</td>
<td>“GSF Error index file read error”</td>
</tr>
<tr>
<td>GSF_INSUFFICIENT_SIZE</td>
<td>-6</td>
<td>“GSF Error insufficient size specified”</td>
</tr>
<tr>
<td>GSF_INVALID_NUM_BEAMS</td>
<td>-42</td>
<td>“GSF Error invalid number of beams”</td>
</tr>
<tr>
<td>GSF_INVALID_RECORD_NUMBER</td>
<td>-43</td>
<td>“GSF Error invalid record number”</td>
</tr>
<tr>
<td>GSF_MB_PING_RECORD_DECODE_FAILED</td>
<td>-26</td>
<td>“GSF Error decoding multibeam ping record”</td>
</tr>
<tr>
<td>GSF_MB_PING_RECORD_ENCODE_FAILED</td>
<td>-26</td>
<td></td>
</tr>
<tr>
<td>GSF_MEMORY_ALLOCATION_FAILED</td>
<td>-12</td>
<td>“GSF Error memory allocation failure”</td>
</tr>
<tr>
<td>GSF_NAV_ERROR_RECORD_DECODE_FAILED</td>
<td>-32</td>
<td>“GSF Error decoding latitude/longitude navigation error record”</td>
</tr>
<tr>
<td>GSF_NAV_ERROR_RECORD_ENCODE_FAILED</td>
<td>-32</td>
<td></td>
</tr>
<tr>
<td>GSF_NORMAL</td>
<td>0</td>
<td></td>
</tr>
<tr>
<td>GSF_OPEN_TEMP_FILE_FAILED</td>
<td>-51</td>
<td>“GSF Failed to open temporary file for index creation”</td>
</tr>
<tr>
<td>GSF_PARAM_SIZE_FIXED</td>
<td>-45</td>
<td>“GSF Error unable to update existing file with increased record size”</td>
</tr>
<tr>
<td>GSF_PARTIAL_RECORD_AT_END_OF_FILE</td>
<td>-52</td>
<td>“GSF Error corrupt/partial record at end of the file”</td>
</tr>
<tr>
<td>GSF_PROCESS_PARAM_RECORD_DECODE_FAILED</td>
<td>-28</td>
<td>“GSF Error decoding processing parameters record”</td>
</tr>
<tr>
<td>GSF_PROCESS_PARAM_RECORD_ENCODE_FAILED</td>
<td>-28</td>
<td></td>
</tr>
<tr>
<td>GSF_READ_ERROR</td>
<td>-4</td>
<td>“GSF Error reading input data”</td>
</tr>
<tr>
<td>GSF_READ_TO_END_OF_FILE</td>
<td>-23</td>
<td>“GSF End of file encountered”</td>
</tr>
<tr>
<td>GSF_RECORD_SIZE_ERROR</td>
<td>-7</td>
<td>“GSF Error record size is out of bounds”</td>
</tr>
<tr>
<td>GSF_RECORD_TYPE_NOTAVAILABLE</td>
<td>-39</td>
<td>“GSF Error requested indexed record type not in gsf file”</td>
</tr>
<tr>
<td>GSF_SCALE_INDEX_CALLOC_ERROR</td>
<td>-38</td>
<td>“GSF Error calloc of scale factor index memory failed”</td>
</tr>
<tr>
<td>Error Code</td>
<td>Description</td>
<td></td>
</tr>
<tr>
<td>------------</td>
<td>-------------</td>
<td></td>
</tr>
<tr>
<td>GSF_SENSOR_PARAM_RECORD_DECODE_FAILED</td>
<td>-29</td>
<td>“GSF Error decoding sensor parameters record”</td>
</tr>
<tr>
<td>GSF_SENSOR_PARAM_RECORD_ENCODE_FAILED</td>
<td>-29</td>
<td></td>
</tr>
<tr>
<td>GSF_SETVBUF_ERROR</td>
<td>-33</td>
<td>“GSF Error setting internal file buffering”</td>
</tr>
<tr>
<td>GSF_SINGLE_BEAM_ENCODE_FAILED</td>
<td>-46</td>
<td>“GSF Error single beam encode failure”</td>
</tr>
<tr>
<td>GSF_STREAM_DECODE_FAILURE</td>
<td>-14</td>
<td>“GSF Error stream decode failure” ***Note: error code is not used</td>
</tr>
<tr>
<td>GSF_SUMMARY_RECORD_DECODE_FAILED</td>
<td>-40</td>
<td>“GSF Error decoding summary record”</td>
</tr>
<tr>
<td>GSF_SUMMARY_RECORD_ENCODE_FAILED</td>
<td>-41</td>
<td>“GSF Error encoding summary record”</td>
</tr>
<tr>
<td>GSF_SVP_RECORD_DECODE_FAILED</td>
<td>-27</td>
<td>“GSF Error decoding SVP record”</td>
</tr>
<tr>
<td>GSF_SVP_RECORD_ENCODE_FAILED</td>
<td>-27</td>
<td></td>
</tr>
<tr>
<td>GSF_TOO_MANY_ARRAY_SUBRECORDS</td>
<td>-10</td>
<td>“GSF Error too many array subrecords”</td>
</tr>
<tr>
<td>GSF_TOO_MANY_OPEN_FILES</td>
<td>-11</td>
<td>“GSF Error too many open files”</td>
</tr>
<tr>
<td>GSF_UNRECOGNIZED_ARRAY_SUBRECORD_ID</td>
<td>-19</td>
<td>“GSF Error unrecognized array subrecord id”</td>
</tr>
<tr>
<td>GSF_UNRECOGNIZED_DATA_RECORD</td>
<td>-18</td>
<td>“GSF Error unrecognized data record id”</td>
</tr>
<tr>
<td>GSF_UNRECOGNIZED_FILE</td>
<td>-2</td>
<td>“GSF Error unrecognized file”</td>
</tr>
<tr>
<td>GSF_UNRECOGNIZED_RECORD_ID</td>
<td>-13</td>
<td>“GSF Error unrecognized record id”</td>
</tr>
<tr>
<td>GSF_UNRECOGNIZED_SENSOR_ID</td>
<td>-17</td>
<td>“GSF Error unrecognized sensor specific subrecord id”</td>
</tr>
<tr>
<td>GSF_UNRECOGNIZED_SUBRECORD_ID</td>
<td>-20</td>
<td>“GSF Error unrecognized subrecord id”</td>
</tr>
<tr>
<td>GSF_WRITE_ERROR</td>
<td>-5</td>
<td>“GSF Error writing output data”</td>
</tr>
<tr>
<td>GSF_QUALITY_FLAGS_DECODE_ERROR</td>
<td>-53</td>
<td>“GSF error decoding quality flags record”</td>
</tr>
<tr>
<td>Unrecognized error condition</td>
<td></td>
<td>“GSF unknown error”</td>
</tr>
</tbody>
</table>
4. C-LANGUAGE DEFINITIONS OF STRUCTURES USED BY GSFLIB

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

4.1 Definition of GSF Data Records

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

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

4.1.1 Header Record

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

#define GSF_VERSION_SIZE 12

typedef struct t_gsfHeader
4.1.2 Swath Bathymetry Ping Record

typedef struct t_gsfSwathBathyPing
{
  struct timespec ping_time; /* seconds and nanoseconds */
  double latitude; /* in degrees, north is positive */
  double longitude; /* in degrees, west is positive */
  double height; /* height above ellipsoid */
  double sep; /* ellipsoid to chart datum */
  short number_beams; /* in this ping */
  short center_beam; /* offset into array (0 = portmost outer) */
  unsigned short ping_flags; /* flags to mark status of this ping */
  short reserved; /* for future use */
  double tide_corrector; /* in meters */
  double gps_tide_corrector; /* in meters */
  double depth_corrector; /* in meters */
  double heading; /* in degrees */
  double pitch; /* in degrees */
  double roll; /* in degrees */
  double heave; /* in meters */
  double course; /* in degrees */
  double speed; /* in knots */
  gsfScaleFactors scaleFactors; /* The array scale factors for this data */
  double *depth; /* depth array (meters) */
  double *nominal_depth; /* Array of depth relative to 1500 m/s */
  double *across_track; /* across track array (meters) */
}
double *along_track;  /* along track array (meters) */

double *travel_time;  /* roundtrip travel time array (seconds) */

double *beam_angle;   /* beam angle array degrees from vertical */

double *mc_amplitude; /* mean, calibrated beam amplitude array (dB re 1V/micro pascal at 1 meter) */

double *mr_amplitude; /* mean, relative beam amplitude array (dB re 1V/micro pascal at 1 meter) */

double *echo_width;   /* echo width array (seconds) */

double *quality_factor; /* quality factor array (dimensionless) */

double *receive_heave; /* Array of heave data (meters) */

double *beam_angle_forward; /* beam angle forward array (degrees counterclockwise from stbd.) */

double *vertical_error; /* Array of estimated vertical error (meters, at 95% confidence) */

double *horizontal_error; /* Array of estimated horizontal error (meters, at 95% confidence */

unsigned short *sector_number; /* Array of values that specify the transit sector for this beam */

unsigned short *detection_info; /* Array of values that specify the method of bottom detection */

double *incident_beam_adj; /* Array of values that specify incident beam angle adjustment from beam_angle */

unsigned short *system_cleaning; /* Array of values that specify data cleaning information from the sensor system */
double *doppler_corr;  /* Array of values used to correct the travel times for Doppler when transmission is FM */

double *sonar_vert_uncert;  /* vertical uncertainty from sonar */

double *sonar_horz_uncert;  /* horizontal uncertainty provided by the sonar (Added in KMALL) */

double *detection_window;   /* Length of the detection window in seconds provided by the sonar (Added in KMALL) */

double *mean_abs_coeff;     /* Mean absolute coefficient provided by the sonar (Added in KMALL) */

int sensor_id;           /* a definition which specifies the sensor*/

gsfSensorSpecific sensor_data;  /* union of known sensor specific data */

gsfBRBIntensity *brb_inten;    /* Structure containing bathymetric receive beam time series intensities */

} gsfSwathBathyPing;

4.1.2.1 Scale Factor Subrecord
typedef struct t_gsfScaleInfo
{
    unsigned char  compressionFlag;  /* Specifies bytes of storage in high order nibble and type of compression in low order nibble */
    double multiplier;  /* the scale factor (millionths) for the array */
    double offset;  /* dc offset to scale data by */
} gsfScaleInfo;

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

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

t_gsfTypeIIISpecific;

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

/* Define the CMP (Compressed) SASS specific data structure (from sass.h) */
typedef struct t_gsfCmpSassSpecific
{
    /*----------------------------------------------------------
     * Mapping from Compressed SASS (BOSDAT) to GSF record
     *----------------------------------------------------------
     * from       to              comment
     *----------------------------------------------------------
     * lntens     ping.heave      mapped only when year is post 1991 or
     * lfreq      not-mapped
     * ldraft     comment          APPLIED_DRAFT comment record
*/
double lfreq; /* sea-surface sound velocity in feet/sec from bosdat(lfreq) */

double lintens; /* since 1992 this value has represented the heave associated with the ping; prior to 1992, field description unknown */

}  
t_gsfCmpSassSpecific;

/* Define the 16 Beam SeaBeam specific data structure */
typedef struct t_gsfSeabeamSpecific
{
    unsigned short EclipseTime; /* In 10ths of seconds */
}
typedef struct _t_gsfSBampSpecific
{
    unsigned char hour;
    unsigned char minute;
    unsigned char second;
    unsigned char hundredths;
    unsigned int block_number;
    short avg_gate_depth;
}

_t_gsfSBampSpecific;

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

_t_gsfSeamapSpecific;
typedef struct t_gsfEM950Specific
{
    int      ping_number;
    int      mode;
    int      ping_quality;
    double   ship_pitch;
    double   transducer_pitch;
    double   surface_velocity;
}
t_gsfEM950Specific;

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

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

typedef struct t_gsfEM3RunTime
{
    int             model_number;           /* from the run-time parameter datagram */
    struct timespec dg_time;                /* from the run-time parameter datagram */
    int             ping_number;            /* sequential counter 0 - 65535 */
    int             serial_number;          /* The sonar head serial number */
    int             system_status;          /* normally = 0 */
    int             mode;                   /* 0=nearfield, 1=normal, 2=target, 3=deep, 4=very deep */
    int             filter_id;
    double          min_depth;              /* meters */
    double          max_depth;              /* meters */
    double          absorption;             /* dB/km */
    double          pulse_length;           /* micro seconds */
    double          transmit_beam_width;    /* degrees */
    int             power_reduction;        /* dB */
    double          receive_beam_width;     /* degrees */
    int             receive_bandwidth;      /* Hz */
};

t_gsfEM121ASpecific;
int receive_gain; /* dB */
int cross_over_angle; /* degrees */
int ssv_source; /* 0=sensor, 1=manual, 2=profile */
int swath_width; /* total swath width in meters */
int beam_spacing; /* 0=beamwidth, 1=equiangle, 2=equidistant, 3=intermediate */
int coverage_sector; /* total coverage in degrees */
int stabilization;
int port_swath_width; /* maximum port swath width in meters */
int stbd_swath_width; /* maximum starboard swath width in meters */
int port_coverage_sector; /* maximum port coverage in degrees */
int stbd_coverage_sector; /* maximum starboard coverage in degrees */
int hilo_freq_absorp_ratio;
int spare1; /* four spare bytes */
}

t_gsfEM3RunTime;

/* Define the Simrad EM3000 series specific data structure */
typedef struct t_gsfEM3Specific
{
 /* The first nine values are updated with each depth datagram */
 int model_number; /* ie: 3000, ... */
 int ping_number; /* 0 - 65535 */
 int serial_number; /* 100 - 65535 */
 double surface_velocity; /* in m/s */
 double transducer_depth; /* transmit transducer depth in meters */
 int valid_beams; /* number of valid beams for this ping */
 int sample_rate; /* in Hz */
}
double depth_difference;  /* in meters between sonar heads in em3000d configuration */
int offset_multiplier;  /* transducer depth offset multiplier */
/* The gsfEM3RunTime data structure is updated with each run-time parameter datagram*/
gsfEM3RunTime run_time[2]; /* A two element array is needed to support em3000d */
}
t_gsfEM3Specific;

/* Define the Reson SeaBat specific data structure */
typedef struct t_gsfSeaBatSpecific
{
    int ping_number;
    double surface_velocity;
    int mode;
    int sonar_range;
    int transmit_power;
    int receive_gain;
}
t_gsfSeaBatSpecific;

/* The gsfSeaBatIISpecific data structure is intended to replace the
 * gsfSeaBatSpecific data structure as of GSF_1.04. */
typedef struct t_gsfSeaBatIISpecific
{
    int ping_number; /* 1 - 32767 */
    double surface_velocity; /* meters/second */
    int mode; /* bit mapped, see macros below */
    int sonar_range; /* meters */
int transmit_power;
int receive_gain;
double fore_aft_bw; /* fore/aft beam width in degrees */
double athwart_bw; /* athwartships beam width in degrees */
char spare[4]; /* Four bytes of spare space, for future use */
}
t_gsfSeaBatIISpecific;

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

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

t_gsfSeaBat8101Specific;

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

/* Define the SeaBeam 2112/36 specific data structure */
typedef struct t_gsfSeaBeam2112Specific
{
    int mode;        /* bit mapped, see macros below */
    double surface_velocity; /* meters/second */
    char ssv_source;    /* (V)elocimeter, (M)anual, (T)emperature, (E)xternal, or (U)nknown */
    int ping_gain;     /* dB */
    int pulse_width;   /* in milliseconds */
    int transmitter_attenuation; /* dB */
    int number_algorithms; /* algorithms per beam (1-4) */
    char algorithm_order[5]; /* null terminated string, each char will be either a space, W(MT), or B(DI). If number_algorithms equals one, this will be four spaces */
}
char spare[2]; /* Two bytes of spare space, for future use */

}

t_gsfSeaBeam2112Specific;

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

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

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

t_gsfElacMkIISpecific;

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

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

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

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

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

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

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

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

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

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

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

unsigned int control_flags; /* 0-3: Auto range method
4-7: Auto bottom detect filter method
8: Bottom detect range filter
9: Bottom detect depth filter
10-14: Auto receiver gain method
15-31: Reserved */
unsigned int  projector_id;          /* projector selection, from record 7000 */
double        projector_steer_angl_vert; /* degrees, from record 7000 */
double        projector_steer_angl_horz; /* degrees, from record 7000 */
double        projector_beam_wdth_vert; /* degrees, from record 7000 */
double        projector_beam_wdth_horz; /* degrees, from record 7000 */
double        projector_beam_focal_pt;  /* meters, from record 7000 */
unsigned int  projector_beam_weighting_window_type; /* 0-Rectangular, 1-Chebychhev, from record 7000 */
unsigned int  projector_beam_weighting_window_param; /* four byte projector weighting parameter, no definition or units available, from record 7000 */
unsigned int  transmit_flags;         /* 0-3: Pitch stabilization method 4-6: Yaw stabilization method 8-31: Reserved */
unsigned int  hydrophone_id;          /* hydrophone selection, from record 7000 */
unsigned int  receiving_beam_weighting_window_type; /* 0-Chebychev, 1-Kaiser, from record 7000 */
unsigned int  receiving_beam_weighting_window_param; /* four byte receiver weighting parameter, no definition or units available, from record 7000 */
unsigned int  receive_flags;          /* 0-3: Roll stabilization method 4-7: Dynamic focusing method */
8-11: Doppler compensation method
12-15: Match filtering method
16-19: TVG method
20-23: Multi-Ping Mode
24-31: Reserved */

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

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

/* Define the Reson T50/20 Series specific data structure */
typedef struct t_gsfResonTSeriesSpecific
{
    unsigned int protocol_version; /* Obtained from the Data Record Frame (DRF) */
    unsigned int device_id; /* i.e. 7101, 7111, 7125, etc. Obtained from the DRF */
    unsigned int number_devices; /* Number of devices from the 7001 record */
    unsigned short system_enumerator; /* From Data Record Frame. In Dual head configuration, specifies sensor 0 - Both Sonars 1 - Port Sonar 2 - Starboard Sonar */
    unsigned char reserved_1[10]; /* Placeholder for growth of fields from DRF */
    unsigned int major_serial_number; /* high order 4 bytes of sonar serial number, from record 7000 */
    unsigned int minor_serial_number; /* low order 4 bytes of sonar serial number, from record 7000 */
    unsigned int ping_number; /* sequential number, unique for each ping, wraps at boundary */
    unsigned int multi_ping_seq; /* 0 if not in multi-ping mode, otherwise number of pings in a multi-ping sequence */
    double frequency; /* Sonar operating frequency in Hz. From record 7000 */
    double sample_rate; /* Sonar system sampling rate in Hz. From record 7027 */
    double receiver_bandwidth; /* Sonar system signal bandwidth in Hz. From record 7000 */
    double tx_pulse_width; /* Transmit pulse length in seconds. From record 7000 */
};
```
unsigned int tx_pulse_type_id; /* 0=CW, 1=Linear chirp, from record 7000 */

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

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

unsigned short tx_pulse_mode; /* 1 - single ping, 2 - multi-ping 2, 3 - multi-ping 3, 4 - multi-ping 4 */

unsigned short tx_pulse_reserved; /* two byte field reserved for future growth, from record 7000 */

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

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

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

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

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

(0: Disabled, 1: Enabled)
24: Trigger out
   (0: Disabled, 1: Enabled)
25: Trigger in edge
   (0: Positive, 1: Negative)
26: PPS Edge
   (0: Positive, 1: Negative)
27-28: Timestamp state (  
   0: Not applicable,  
   1: Error / not valid,  
   2: warning,  
   3: ok)
29: Depth filter follows seafloor
   (0: Fix depth,  
   1: Follow seafloor)
30: Reduced coverage for constant
    spacing
   (0: Always maintain swath coverage,  
   1: Allow swath coverage to be reduced)
31: 0: 7K. 1: Simulator/*

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

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

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

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

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

double            projector_beam_focal_pt;   /* meters, from record 7000 */

unsigned int      projector_beam_weighting_window_type;   /* 0-Rectangular,  
                                                             1-Chebychev,  
                                                             from record 7000 */

double            projector_beam_weighting_window_param; /* four byte projector  
                                                             weighting parameter,  
                                                             no definition or units available, from record 7000 */

unsigned int      transmit_flags;        /* 0-3: Pitch stabilization method  
                                          4-6: Yaw stabilization method  
                                          8-31: Reserved */

unsigned int      hydrophone_id;         /* hydrophone selection,  
                                          from record 7000 */
unsigned int receiving_beam_weighting_window_type; /* 0-Chebychev, 1-Kaiser, from record 7000 */

double receiving_beam_weighting_window_param; /* four byte receiver weighting parameter, no definition or units available, from record 7000 */


double receive_beam_width; /* angle in degrees, from record 7000 */

double range_filt_min; /* range filter, minimum value, meters, from record 7000 */

double range_filt_max; /* range filter, maximum value, meters, from record 7000 */

double depth_filt_min; /* depth filter, minimum value, meters, from record 7000 */

double depth_filt_max; /* depth filter, maximum value, meters, from record 7000 */

double absorption; /* absorption in dB/km, from record 7000 */

double sound_velocity; /* sound speed in m/s at transducer, from record 7000 (in T Series) */

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

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

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

unsigned short sonar_source_mode; /* 7k sonar source mode from record 7503 (0: Normal, */
unsigned char coverage_mode;  
/* Coverage mode from 7503 record  
(0: Reduce Spacing,  
1: Reduce Beams) */

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

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

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

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

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

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

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

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

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

unsigned char reserved_7027[420];  
/* Space space from 7027 record, for future use */

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

}  

t_gsfResonTSeriesSpecific;

/* Define the Reson 8100 specific data structure */
typedef struct t_gsfReson8100Specific
{
   int latency;  
   /* time from ping to output (milliseconds) */
}
int ping_number; /* 4 byte ping number */
int sonar_id; /* least significant 4 bytes of Ethernet address */
int sonar_model; /* */
int frequency; /* KHz */
double surface_velocity; /* meters/second */
int sample_rate; /* A/D samples per second */
int ping_rate; /* pings per second * 1000 */
int mode; /* bit mapped, see macros below */
int range; /* meters */
int power; /* 0-8 + status bits */
int gain; /* 1-45 + status bits */
int pulse_width; /* in microseconds */
int tvg_spreading; /* tvg spreading coefficient * 4 */
int tvg_absorption; /* tvg absorption coefficient */
double fore_aft_bw; /* fore/aft beam width in degrees */
double athwart_bw; /* athwartships beam width in degrees */
int projector_type; /* projector type */
int projector_angle; /* projector pitch steering angle (degrees * 100) */
double range_filt_min; /* range filter, minimum value, meters */
double range_filt_max; /* range filter, maximum value, meters */
double depth_filt_min; /* depth filter, minimum value, meters */
double depth_filt_max; /* depth filter, maximum value, meters */
int filters_active; /* bit 0 - range filter, bit 1 - depth filter */
int temperature; /* temperature at sonar head (deg C * 10) */
double beam_spacing; /* across track receive beam angular spacing */
char spare[2]; /* Two bytes of spare space, for future use */
/* Define the Echotrac Single-Beam sensor specific data structure. */

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

typedef struct t_gsfSBEEchotracSpecific
{
    int           navigation_error;
    unsigned short mpp_source;       /* Flag To determine mpp source - See above */
    unsigned short tide_source;        /* in GSF Version 2.02+ this is in ping flags */
    double     dynamic_draft;        /* speed induced draft im meters */
    char        spare[4];           /* four bytes of reserved space */
/* Define the MGD77 Single-Beam sensor specific data structure. */
typedef struct t_gsfSBMGD77Specific
{
    unsigned short  time_zone_corr;
    unsigned short  position_type_code;
    unsigned short  correction_code;
    unsigned short  bathy_type_code;
    unsigned short  quality_code;
    double          travel_time;
    char            spare[4];                  /* four bytes of reserved space */
} t_gsfSBMGD77Specific;

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

t_gsfSBBDBSpecific;

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

t_gsfSBNOSHDBSpecific;

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

t_gsfSBNavisoundSpecific;

/* Define the GeoSwath sensor specific data structure */
typedef struct t_gsfGeoSwathPlusSpecific
{
    int data_source; /* 0 = CBF, 1 = RDF */
    int side; /* 0 = port, 1 = stbd */
    int model_number; /* ie: 100, 250, 500, ... */
    double frequency; /* Hz */
    int echosounder_type; /* ? */
long    ping_number;       /* 0 - 4,294,967,295 */
int     num_nav_samples;  /* number of navigation samples in this ping */
int     num_attitude_samples;  /* number of attitude samples in this ping */
int     num_heading_samples;  /* number of heading samples in this ping */
int     num_miniSVS_samples;  /* number of miniSVS samples in this ping */
int     num_echosounder_samples;  /* number of echosounder samples in ping */
int     num_raa_samples;  /* number of RAA (Range/Angle/Amplitude) samples in ping */
double  mean_sv;       /* meters per second */
double  surface_velocity;  /* in m/s */
int     valid_beams;  /* number of valid beams for this ping */
double  sample_rate;  /* Hz */
double  pulse_length;  /* micro seconds */
int     ping_length;  /* meters */
int     transmit_power;  /* ? */
int     sidescan_gain_channel;  /* RDF documentation = 0 - 3 */
int     stabilization;  /* 0 or 1 */
int     gps_quality;  /* ? */
double  range_uncertainty;  /* meters */
double  angle_uncertainty;  /* degrees */
char     spare[32];  /* 32 bytes of reserved space */
}

t_gsfGeoSwathPlusSpecific;

#define GSF_GEOSWATH_PLUS_PORT_PING 0
#define GSF_GEOSWATH_PLUS_STBD_PING 1
/* Macro definitions for EM4 series sector data details */
#define GSF_MAX_EM4_SECTORS 9

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

/* Define sub-structure for the transmit sectors */
#define GSF_EM_WAVEFORM_CW 0
#define GSF_EM_WAVEFORM_FM_UP 1
#define GSF_EM_WAVEFORM_FM_DOWN 2

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

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

/* The following macro definitions are to aid in interpretation of the sonar mode field */
#define GSF_EM_MODE_VERY_SHALLOW 0x00          /* Bits 2,1,0 cleared means very shallow 
mode */
#define GSF_EM_MODE_SHALLOW 0x01          /* Bit zero set means shallow mode */
#define GSF_EM_MODE_MEDIUM 0x02          /* Bit one set means medium mode */
#define GSF_EM_MODE_DEEP 0x03          /* Bits one and zero set means deep 
mode */
#define GSF_EM_MODE_VERY_DEEP 0x04          /* Bit two set means very deep mode */
#define GSF_EM_MODE_EXTRA_DEEP 0x05          /* Bits two and one set means extra deep 
mode */
#define GSF_EM_MODE_MASK 0x07          /* Mask off bits 2,1,0 to determine just 
the mode */
/* Exact definition of bits 5,4,3 not 
clear from document rev J. */
#define GSF_EM_MODE_DS_OFF 0xC0          /* bits 7 and 6 cleared means dual swath 
off */
```c
#define GSF_EM_MODE_DS_FIXED 0x40 /* bit 6 set means dual swath in fixed mode */
#define GSF_EM_MODE_DS_DYNAMIC 0x80 /* bit 7 set means dual swath in dynamic mode */

/* Define a data structure to hold the Simrad EM series run time parameters per datagram document rev I. */
typedef struct t_gsfEMRunTime
{
    int            model_number;  /* from the run-time parameter datagram */
    struct timespec dg_time;      /* from the run-time parameter datagram */
    int            ping_counter;  /* sequential counter 0 - 65535 */
    int            serial_number; /* The primary sonar head serial number */
    unsigned char  operator_station_status; /* Bit mask of status information for operator station */
    unsigned char  processing_unit_status; /* Bit mask of status information for sonar processor unit */
    unsigned char  bsp_status;         /* Bit mask of status information for BSP status */
    unsigned char  head_transceiver_status; /* Bit mask of status information for sonar head or sonar transceiver */
    unsigned char  mode;              /* Bit mask of sonar operating information, see mode bit mask definitions */
    unsigned char  filter_id;         /* one byte tit mask for various sonar processing filter settings */
    double         min_depth;         /* meters */
    double         max_depth;         /* meters */
    double         absorption;        /* dB/km */
    double         tx_pulse_length;   /* in micro seconds */
} t_gsfEMRunTime;
```
double tx_beam_width;            /* degrees */
double tx_power_re_max;          /* The transmit power referenced to maximum power in dB */
double rx_beam_width;            /* degrees */
double rx_bandwidth;             /* Hz */
double rx_fixed_gain;            /* dB */
double tvg_cross_over_angle;     /* degrees */
unsigned char ssv_source;       /* one byte bit mask defining SSSV source -> 0=sensor, 1=manual, 2=profile */
int max_port_swath_width;        /* total swath width to port side in meters */
unsigned char beam_spacing;      /* one byte bit mask -> 0=beamwidth, 1=equiangle, 2=equidistant, 3=intermediate */
int max_port_coverage;           /* coverage to port side in degrees */
unsigned char stabilization;     /* one byte bit mask defining yaw and pitch stabilization mode */
int max_stbd_coverage;           /* coverage to starboard side in degrees */
int max_stbd_swath_width;        /* total swath width to starboard side in meters */
double durotong_speed;           /* Sound speed in durotong for the EM1002 transducer, zero if not available */
double hi_low_absorption_ratio;  /* Absorption coefficient ratio */
double tx_along_tilt;            /* Transmit fan along track tilt angle in degrees */
unsigned char filter_id_2;       /* two lowest order bits define the penetration filter setting: off, weak, medium, or strong */
unsigned char spare[16];         /* 16 spare bytes */
}
t_gsfEMRunTime;
/* Macro definitions for bits of pu_status field */
#define GSF_EM_VALID_1_PPS 0x0001 /* If set, then 1 PPS timing is valid */
#define GSF_EM_VALID_POSITION 0x0002 /* If set, then position input is valid */
#define GSF_EM_VALID_ATTITUDE 0x0004 /* If set, then attitude input is valid */
#define GSF_EM_VALID_CLOCK 0x0008 /* If set, then clock status is valid */
#define GSF_EM_VALID_HEADING 0x0010 /* If set, then heading status is valid */
#define GSF_EM_PU_ACTIVE 0x0020 /* If set, then PU is active (i.e. pinging) */

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

/* Define sensor specific data structures for the Kongsberg 710/302/122 */
typedef struct t_gsfEM4Specific
{
    /* values from the XYZ datagram and raw range datagram */
    int model_number; /* 122, or 302, or 710, or ... */
    int ping_counter; /* Sequential ping counter, 1 through 65535 */
int serial_number;  /* System unique serial number, 100 - ? */
double surface_velocity;  /* Measured sound speed near the surface in m/s */
double transducer_depth;  /* The transmit transducer depth in meters relative water level at ping time */
int valid_detections;  /* number of beams with a valid bottom detection for this ping */
double sampling_frequency;  /* The system digitizing rate in Hz */
unsigned int doppler_corr_scale;  /* Scale factor value to be applied to Doppler correction field prior to applying corrections */
double vehicle_depth;  /* From 0x66 datagram, non-zero when sonar head is mounted on a sub-sea platform */
unsigned char spare_1[16];
int transmit_sectors;  /* The number of transmit sectors for this ping */
t_gsfEM4TxSector sector[GSF_MAX_EM4_SECTORS];  /* Array of structures with transmit sector information */
unsigned char spare_2[16];

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

/* Values from the PU status datagram */
t_gsfEMPUSStatus pu_status;
}
t_gsfEM4Specific;

/* Define sensor specific data structures for the Kongsberg 3000, etc which use raw range and beam angle */
typedef struct t_gsfEM3RawSpecific
{
    /* values from the XYZ datagram and raw range datagram */
int    model_number;       /* ie 3000 ... */
int    ping_counter;      /* Sequential ping counter, 0 through 65535 */
int    serial_number;     /* System unique serial number, 100 - ? */
double surface_velocity;  /* Measured sound speed near the surface in m/s */
double transducer_depth;  /* The transmit transducer depth in meters re water level at ping time */
int    valid_detections;  /* number of beams with a valid bottom detection for this ping */
double sampling_frequency; /* The system digitizing rate in Hz */
double vehicle_depth;     /* vehicle depth in 0.01 m */
double depth_difference;  /* in meters between sonar heads in em3000d configuration */
int    offset_multiplier; /* transducer depth offset multiplier */
unsigned char spare_1[16];
int    transmit_sectors;  /* The number of transmit sectors for this ping */
t_gsfEM3RawTxSector sector[GSF_MAX_EM3_SECTORS]; /* Array of structures with transmit sector information */
unsigned char spare_2[16];

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

/* Values from the PU status datagram */
t_gsfEMPUSStatus pu_status;
}
typedef struct t_gsfKlein5410BssSpecific {
    int data_source; /* 0 = SDF */
    int side; /* 0 = port, 1 = stbd */
    int model_number; /* ie: 5410 */
    double acoustic_frequency; /* system frequency in Hz */
    double sampling_frequency; /* sampling frequency in Hz */
    unsigned int ping_number; /* 0 - 4,294,967,295 */
    unsigned int num_samples; /* total number of samples in this ping */
    unsigned int num_raa_samples; /* number of valid range, angle, amplitude samples in ping */
    unsigned int error_flags; /* error flags for this ping */
    unsigned int range; /* sonar range setting */
    double fish_depth; /* reading from the towfish pressure sensor in Volts */
    double fish_altitude; /* towfish altitude in m */
    double sound_speed; /* speed of sound at the transducer face in m/sec */
    int tx_waveform; /* transmit pulse: 0 = 132 microsec CW; 1 = 132 microsec FM; */
    /* 2 = 176 microsec CW; 3 = 176 microsec FM */
    int altimeter; /* altimeter status: 0 = passive, 1 = active */
    unsigned int raw_data_config; /* raw data configuration */
    char spare[32]; /* 32 bytes of reserved space */
} t_gsfKlein5410BssSpecific;
/* Define the Imagenex Delta T sensor specific data structure */

typedef struct t_gsfDeltaTSpecific
{
    char        decode_file_type[4];          /* contains the decoded files extension. */
    char        version;                      /* contains the minor version number of the
      delta t */
    int         ping_byte_size;              /* size in bytes of this ping (256 + 
      (((byte 117[1 or 0])*2) + 2) * number of beams)) */
    struct timespec interrogation_time;       /* The sonar interrogation time */
    int         samples_per_beam;             /* number of samples per beam */
    double      sector_size;                 /* size of the sector in degrees */
    double      start_angle;                 /* the angle that beam 0 starts at in
      degrees. */
    double      angle_increment;             /* the number of degrees the angle
      increments per beam */
    int         acoustic_range;               /* acoustic range in meters */
    int         acoustic_frequency;           /* acoustic frequency in kHz */
    double      sound_velocity;               /* the velocity of sound at the transducer
      face in m/s */
    double      range_resolution;             /* range resolution in centimeters
      (documentation says mm but all example data is in cm) */
    double      profile_tilt_angle;           /* the mounting offset */
    double      repetition_rate;              /* time between pings in milliseconds */
    unsigned long ping_number;               /* the current ping number of this ping. */
    unsigned char intensity_flag;             /* this tells whether the GSF will have
      intensity data (1=true) */
    double      ping_latency;                 /* time from sonar ping interrogation to
      actual ping in seconds */
    double      data_latency;                 /* time from sonar ping interrogation to
      83F UDF datagram in seconds */
}
unsigned char sample_rate_flag; /* sampling rate 0 = (1 in 500); 1 = (1 in 5000) */

unsigned char option_flags; /* this flag states whether the data is
roll corrected or raybend corrected (1 = roll, 2 = raybend, 3 = both) */

int num_pings_avg; /* number of pings averaged 1 - 25 */

double center_ping_time_offset; /* the time difference in seconds between
the center ping interrogation and the current ping interrogation */

unsigned char user_defined_byte; /* contains a user defined byte */

double altitude; /* the height of the fish above the ocean
floor. */

char external_sensor_flags; /* this flag is a bit mask where (1 =
external heading, 2 = external roll, 4 = external pitch, 8 = external heave) */

double pulse_length; /* acoustic pulse length in seconds */

double fore_aft_beamwidth; /* Effective f/a beam width in degrees */

double athwartships_beamwidth; /* Effective athwartships beam width in
degrees */

unsigned char spare[32]; /* room to grow */
}

t_gsfDeltaTSpecific;

/* Define sensor specific data structures for the EM12 */
typedef struct t_gsfEM12Specific
{
  int ping_number; /* 0 to 65535 */
  int resolution; /* 1 = high, 2 = low */
  int ping_quality; /* 21 to 81; number of beams with accepted
bottom detections */
  double sound_velocity; /* m/s */
  int mode; /* 1 to 8; shallow, deep, type of beam
spacing */
  unsigned char spare[32]; /* room to grow */
} t_gsfEM12Specific;
typedef struct t_gsfR2SonicSpecific
{
  unsigned char model_number[12]; /* Model number, e.g. "2024". Unused chars are nulls */
  unsigned char serial_number[12]; /* Serial number, e.g. "100017". Unused chars are nulls */
  struct timespec dg_time; /* Ping time, re 00:00:00, Jan 1, 1970 ("Unix time") */
  unsigned int ping_number; /* Sequential ping counter relative to power up or reboot */
  float ping_period; /* Time interval between two most recent pings, seconds */
  float sound_speed; /* Sound speed at transducer face, m/s */
  float frequency; /* Sonar center frequency (Hz) */
  float tx_power; /* TX source level, dB re 1uPa at 1 meter */
  float tx_pulse_width; /* Pulse width, seconds */
  float tx_beamwidth_vert; /* Fore-aft beamwidth, radians */
  float tx_beamwidth_horiz; /* Athwartship beamwidth, radians */
  float tx_steering_vert; /* Fore-aft beam steering angle, radians, -pi to +pi */
  float tx_steering_horiz; /* Athwartship beam steering angle, radians, -pi to +pi */
  unsigned int tx_misc_info; /* Reserved for future use */
  float rx_bandwidth; /* Receiver bandwidth, Hz */
  float rx_sample_rate; /* Receiver sample rate, Hz */
  float rx_range; /* Receiver range setting */
};
float rx_gain;            /* receiver gain setting, 2dB increments between steps */
float rx_spreading;       /* TVG spreading law coefficient, e.g. 20log10(range) */
float rx_absorption;      /* TVG absorption coefficient, dB/km */
float rx_mount_tilt;      /* radians, -pi to +pi */
unsigned int rx_misc_info; /* reserved for future use */
unsigned short reserved;           /* reserved for future use */
unsigned short num_beams;          /* number of beams in this ping */

/* These fields are from the BTH0 packet only */
float A0_more_info[6];     /* Additional fields associated with equi-angular mode; first element of array is roll */
float A2_more_info[6];     /* Additional fields associated with equi-distant mode; first element of array is roll */
float G0_depth_gate_min;   /* global minimum gate in seconds (twtt) */
float G0_depth_gate_max;   /* global maximum gate in seconds (twtt) */
float G0_depth_gate_slope; /* slope of depth gate (radians, -pi to +pi) */
unsigned char spare[32];           /* saved for future expansion */
}
t_gsfR2SonicSpecific;

/* The following macro definitions are for the KMALL structures */
#define GSF_MAX_KMALL_EXTRA_CLASSES    11
#define GSF_MAX_KMALL_EXTRA_DETECT     1024
#define GSF_KMALL_MRZ                 1
typedef struct t_gsfKMALLTxSector
{
    int txSectorNumb;   /* transmit sector number */
    int txArrNumber;    /* transmit array number */
    int txSubArray;     /* transmit sub-array number: 0 = Port, 1 = Middle, 2 = Starboard */
    double sectorTransmitDelay_sec; /* seconds, time difference of midpoint of current tx pulse over first tx pulse of ping (which is equivalent to the datagram header time) */
    double tiltAngleReTx_deg;        /* degrees, transmitter beam along ship steering angle wrt. transmitter coordinate system */
    double txNominalSourceLevel_dB;  /* decibels, relative 1 microPascal */
    double txFocusRange_m;           /* meters, 0 = no focusing applied */
    double centreFreq_Hz;            /* Hertz, center frequency */
    double signalBandWidth_Hz;       /* Hertz, FM mode: effective bandwidth, CW mode: 1/(effective tx pulse length) */
    double totalSignalLength_sec;    /* seconds, transmit pulse length */
    int pulseShading;                /* Percent amplitude shading. Shading in time. Cos2 function used for shading */
    int signalWaveForm;              /* 0 = CW, 1 = FM upsweep, 2 = FM downsweep */
    unsigned char spare1[20];
}

} t_gsfKMALLTxSector;

typedef struct t_gsfKMALLExtraDetClass
{
    int numExtraDetInClass; /* number of extra detections of this class */
    int alarmFlag;          /* 0 = no alarm, 1 = alarm */
    unsigned char spare[32];
}

typedef struct t_gsfKMALLSpecific {
    int gsfKMALLVersion; /* == 1 for GSF_03.09 */
    int dgmType; /* a one byte integer value: 1 == #MRZ, ... */
    int dgmVersion; /* a one byte integer value */
    int systemID; /* parameter used to identify datagrams from separate echosounders when multiple echosounders are connected */
    int echoSounderID; /* 122, 302, 710, 712, 2040, ... */
    unsigned char spare1[8];
    int numBytesCmnPart; /* Size of cmnPart */
    int pingCnt; /* (short in kmall) Sequential ping counter, 1 through 65535 */
    int rxFansPerPing; /* Number of rx fans per ping, together with swaths per ping determines number of datagrams per swath */
    int rxFanIndex; /* Index of rx fan, 0 = aft, port swath */
    int swathsPerPing; /* Swaths per ping, swath is a complete set of across track data, may contain several transmit sectors and RX fans */
    int swathAlongPosition; /* Alongship index for swath in multi-swath mode, 0 = aftmost */
    int txTransducerInd; /* Transducer used in this rx fan: 0 = TRAI_TX1, 1 = TRAI_TX2, ... */
    int rxTransducerInd; /* Transducer used in this rx fan: 0 = TRAI_RX1, 1 = TRAI_RX2, ... */
    int numRxTransducers; /* Total number of recieving units */
    int algorithmType; /* Future use. 0 = current, else future */
    unsigned char spare2[16];
}
int numBytesInfoData; /* Size of ping info structure */

double pingRate_Hz; /* Ping rate computed by the sonar */

int beamSpacing; /* 0 = Equidistance, 1 = Equiangle, 2 = High Density */

int depthMode; /* 0 = Very shallow, 1 = Shallow, 2 = Medium, 3 = Deep, 4 = Deeper, 5 = Very Deep, 6 = Extra Deep, 7 = Extreme deep */

int subDepthMode; /* Advanced use for manual depth mode, 0 = unused */

int distanceBtwSwath; /* achieved istance between swaths as percentage of requirement: 0=unused, 100=achieved equals required */

int detectionMode; /* Bottom detection: 0 = normal, 1 = waterway, 2 = tracking, 3 = minimum depth */

int pulseForm; /* 0 = CW, 1 = mix, 2 = FM */

double frequencyMode_Hz; /* A code if < 100, otherwise the transmit frequency Hz. Codes: -1 = not used, 0 = 40-100 khz, 1 = 50-100khz, 2 = 70-100khz, 3 = 50khz, 4 = 40khz */

double freqRangeLowLim_Hz; /* In hertz, lowest center frequency of swath's sectors */

double freqRangeHighLim_Hz; /* In hertz, highest center frequency of swath's sectors */

double maxTotalTxPulseLength_sec; /* In seconds, longest tx pulse of swath's sectors */

double maxEffTxPulseLength_sec; /* In seconds, longest effective tx pulse of swath's sectors */

double maxEffTxBandWidth_Hz; /* Effective bandwidth (-3dB envelope) of the sector with the highest bandwidth */

double absCoeff_dBPerkm; /* Average absorption coefficient, in dB/km for vertical beam at current depth */

double portSectorEdge_deg; /* Port sector edge, for use by beamformer, referenced to z of SCS */

double starbSectorEdge_deg; /* Starboard sector edge, for use by beamformer, referenced to z of SCS */
double portMeanCov_deg; /* Coverage achieved in degrees, corrected for raybending, referenced to z of SCS */
double starbMeanCov_deg; /* Coverage achieved in degrees, corrected for raybending, referenced to z of SCS */
double portMeanCov_m; /* Coverage achieved in meters, corrected for raybending, referenced to z of SCS */
double starbMeanCov_m; /* Coverage achieved in meters, corrected for raybending, referenced to z of SCS */
int modeAndStabilisation; /* Bit mask: 1 = Pitch, 2 = yaw, 3 = sonar mode, 4 = angular converage mode, 5 = sector mode, 6 = swath along position, 7 & 8 = future use */
int runtimeFilter1; /* Bit mask: 1 = Slope, 2 = Aeration, 3 = Sector, 4 = Interference, 5 = Special Amplitude, 6 - 8 = future use */
    int runtimeFilter2; /* Bit mask: 1-4 = range gate, 5-8 = spike filter, 9-12 penetration filter, 13-16 phase ramp */
int pipeTrackingStatus; /* Pipe tracking status. Describes how angle and range of top of pipe is determined. 0 = for future use, 1 = PU uses guidance from SIS */
double transmitArraySizeUsed_deg; /* degrees, transmit array size along ship */
double receiveArraySizeUsed_deg; /* degrees, receiver array size across ship */
double transmitPower_dB; /* dB, transmit power relative to maximum (0 dB, -10 dB, -20 dB ...) */
int SLrampUpTimeRemaining; /* percentage, time remaining until max source level is acheived */
double yawAngle_deg; /* degrees, yaw correction angle */
int numTxSectors; /* The number of transmit sectors for this ping */
int numBytesPerTxSector; /* Number of bytes in the EMdgmMRZ_txSectorInfo */
double headingVessel_deg;        /* Degrees, Heading of vessel at time of
midpoint of first tx pulse */

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

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

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

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

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

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

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

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

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

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

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

unsigned char spare3[32];

/* values from the sectorInfo of #MRZ */

t_gsfKMALLTxSector sector[GSF_MAX_KMALL_SECTORS]; /* Array of structures with
transmit sector information */
/* values from the rxInfo of #MRZ */

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

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

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

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

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

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

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

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

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

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

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

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

unsigned char spare4[32];

/* Values from the extraDetClassInfo array */

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

unsigned char spare5[32];

}

t_gsfKMALLSpecific;

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

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

t_gsfCmpSassSpecific  gsfCmpSassSpecific;
t_gsfSBAmpSpecific    gsfSBAmpSpecific;
t_gsfSeaBatIISpecific gsfSeaBatIISpecific;
t_gsfSeaBat8101Specific  gsfSeaBat8101Specific;
t_gsfSeaBeam2112Specific  gsfSeaBeam2112Specific;
t_gsfElacMkIISpecific gsfElacMkIISpecific;
t_gsfEM3Specific     gsfEM3Specific;          /* used for EM120, EM300, EM1002,
EM3000, EM3002, and EM121A_SIS */
t_gsfEM3RawSpecific   gsfEM3RawSpecific;       /* used for EM120, EM300, EM1002,
EM3000, EM3002, and EM121A_SIS
with raw range and beam angle */
t_gsfReson8100Specific  gsfReson8100Specific;
t_gsfReson7100Specific  gsfReson7100Specific;
t_gsfResonTSeriesSpecific  gsfResonTSeriesSpecific; /* used for T50 and T20 */
t_gsfEM4Specific      gsfEM4Specific;          /* used for EM710, EM302, EM122,
and EM2040 */
t_gsfGeoSwathPlusSpecific gsfGeoSwathPlusSpecific; /* DHG 2006/09/27 Use for GeoSwath+ interferometer */

t_gsfKlein5410BssSpecific gsfKlein5410BssSpecific; /* Use for Klein 5410 Bathy Sidescan. */

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

/* Single beam sensors added */

t_gsfSBEchotracSpecific gsfSBEchotracSpecific;
t_gsfSBEchotracSpecific gsfSBBathy2000Specific;
t_gsfSBMGD77Specific gsfSBMGD77Specific;
t_gsfSBBDBSpecific gsfSBBDBSpecific;
t_gsfSBNOSHDBSpecific gsfSBNOSHDBSpecific;
t_gsfSBEchotracSpecific gsfSBPDDSpecific;
t_gsfSBNavisoundSpecific gsfSBNavisoundSpecific;
}
}

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

<table>
<thead>
<tr>
<th>Sensor ID</th>
<th>Sensor Specific Subrecord Structure</th>
</tr>
</thead>
<tbody>
<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_SEABEAM_SPECIFIC</td>
<td>gsfSeaBeamSpecific</td>
</tr>
<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_EM100_SPECIFIC</td>
<td>gsfEM100Specific</td>
</tr>
<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_EM12_SPECIFIC</td>
<td>gsfEM12Specific</td>
</tr>
<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_EM121A_SPECIFIC</td>
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<tr>
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<td>gsfEM121Specific</td>
</tr>
<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_SEABAT_SPECIFIC</td>
<td>gsfSeaBatSpecific</td>
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<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_EM950_SPECIFIC</td>
<td>gsfEM950Specific</td>
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<tr>
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<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_SEAMAP_SPECIFIC</td>
<td>gsfSeamapSpecific</td>
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<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_TYPEIII_SEABEAM_SPECIFIC</td>
<td>gsfTypeIIISeaBeamSpecific</td>
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<td>gsfCmpSassSpecific</td>
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<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_SB_AMP_SPECIFIC</td>
<td>gsfSBAmppSpecific</td>
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<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_SEABAT_II_SPECIFIC</td>
<td>gsfSeaBatIISpecific</td>
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<td>gsfSeaBeam2112Specific</td>
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<td>gsfElacMkIISpecific</td>
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<td>gsfEM122Specific</td>
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<tr>
<td>GSF_SWATH_BATHY_SUBRECORD_EM2040_SPECIFIC</td>
<td>gsfEM2040Specific</td>
</tr>
</tbody>
</table>
4.1.2.3 Bathymetric Receive Beam Time Series Intensity Subrecord

typedef struct gsfTimeSeriesIntensity
{
    unsigned short sample_count;       /* number of amplitude samples per beam */
    unsigned short detect_sample;    /* index of bottom detection sample for the beam */
    unsigned short start_range_samples; /* Kmall start of sample index*/
    unsigned char spare[6];           /* for future use */
    unsigned int *samples;            /* Array of per-beam time series intensity samples */
} gsfTimeSeriesIntensity;
#define GSF_INTENSITY_LINEAR    (unsigned)0x01
#define GSF_INTENSITY_CALIBRATED (unsigned)0x02
#define GSF_INTENSITY_POWER      (unsigned)0x04
#define GSF_INTENSITY_GAIN       (unsigned)0x08

typedef struct t_gsfBRBIntensity
{
    unsigned char           bits_per_sample;       /* bits per intensity sample */
    unsigned int            applied_corrections;   /* flags to describe corrections 
                                             applied to intensity values */
    unsigned char           spare[16];             /* spare header space */
    gsfSensorImagery        sensor_imagery;        /* sensor specific per-ping imagery 
                                             information */
    gsfTimeSeriesIntensity *time_series;           /* array of per-beam time series 
                                             intensity records */
} gsfBRBIntensity;

typedef struct t_gsfEM3ImagerySpecific
{
    unsigned short range_norm;          /* range to normal incidence used to correct 
                                           sample amplitudes (in samples) */
    unsigned short start_tvg_ramp;      /* start range sample of TVG ramp if not enough 
                                           dynamic range (0 else) */
    unsigned short stop_tvg_ramp;       /* stop range sample of TVG ramp if not enough 
                                           dynamic range (0 else) */
    char           bsn;                 /* normal incidence BS in dB */
    char           bso;                 /* oblique BS in dB */
    double         mean_absorption;     /* mean absorption coefficient in dB/km, 
                                           resolution of 0.01 dB/km */
} gsfEM3ImagerySpecific;
short          offset;  /* Value that has been added to all imagery samples to convert to a positive value */
short          scale;  /* Manufacturer's specified scale value for each sample. This value is 2 for data from EM3000/EM3002/EM1002/EM300/EM120 */
unsigned char spare[4];  /* spare sensor specific subrecord space, reserved for future expansion */
} t_gsfEM3ImagerySpecific;

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

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

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

typedef struct t_gsfEM4ImagerySpecific
{
    double         sampling_frequency; /* The system digitizing rate in Hz, value retrieved from the imagery datagram */
typedef struct t_gsfEM4ImagerySpecific
{
  double mean_absorption; /* mean absorption coefficient in dB/km, from 0x53 datagram, 0 if data is from 0x59 */
  double tx_pulse_length; /* transmit pulse length in microseconds from imagery datagram 0x53, or 0x59 */
  int range_norm; /* range to normal incidence used to correct sample amplitudes (in samples) */
  int start_tvg_ramp; /* start range (in samples) of TVG ramp if not enough dynamic range 0 means not used */
  int stop_tvg_ramp; /* stop range (in samples) of TVG ramp if not enough dynamic range 0 means not used */
  double bsn; /* normal incidence BS in dB */
  double bso; /* oblique incidence BS in dB */
  double tx_beam_width; /* transmit beam width in degrees from imagery datagram */
  double tvg_cross_over; /* The TVG law crossover angle in degrees */
  short offset; /* Value that has been added to all imagery samples to convert to a positive value */
  short scale; /* Manufacturer's specified scale value for each sample. This value is 10 for data from EM710/EM302/EM122 */
  unsigned char spare[20]; /* spare sensor specific subrecord space, reserved for future expansion */
} t_gsfEM4ImagerySpecific;

typedef struct t_gsfKlein5410BssImagerySpecific
{
  unsigned int res_mode; /* Descriptor for resolution mode: 0 = normal; 1 = high */
  unsigned int tvg_page; /* TVG page number */
  unsigned int beam_id[5]; /* array of identifiers for five sidescan beam magnitude time series, starting with beam id 1 as the forward-most */
  unsigned char spare[4]; /* spare sensor specific subrecord space, reserved for future expansion */
} t_gsfKlein5410BssImagerySpecific;
typedef struct t_gsfR2SonicImagerySpecific
{
    unsigned char model_number[12]; /* Model number, e.g. "2024". Unused chars are nulls */
    unsigned char serial_number[12]; /* Serial number, e.g. "100017". Unused chars are nulls */
    struct timespec dg_time; /* Ping time, re 00:00:00, Jan 1, 1970 ("Unix time") */
    unsigned int ping_number; /* Sequential ping counter relative to power up or reboot */
    float ping_period; /* Time interval between two most recent pings, seconds */
    float sound_speed; /* Sound speed at transducer face, m/s */
    float frequency; /* Sonar center frequency (Hz) */
    float tx_power; /* TX source level, dB re 1uPa at 1 meter */
    float tx_pulse_width; /* pulse width, seconds */
    float tx_beamwidth_vert; /* fore-aft beamwidth, radians */
    float tx_beamwidth_horiz; /* athwartship beamwidth, radians */
    float tx_steering_vert; /* fore-aft beam steering angle, radians, -pi to +pi */
    float tx_steering_horiz; /* athwartship beam steering angle, radians, -pi to +pi */
    unsigned int tx_misc_info; /* reserved for future use */
    float rx_bandwidth; /* receiver bandwidth, Hz */
    float rx_sample_rate; /* receiver sample rate, Hz */
    float rx_range; /* receiver range setting, seconds in doc */
    float rx_gain; /* receiver gain setting, 2dB increments */
float rx_spreading; /* TVG spreading law coefficient, e.g. 20log10(range) */
float rx_absorption; /* TVG absorption coefficient, dB/km */
float rx_mount_tilt; /* radians, -pi to +pi */
unsigned int rx_misc_info; /* reserved for future use */
unsigned short reserved; /* reserved for future use */
unsigned short num_beams; /* number of beams in this ping */
float more_info[6]; /* reserved for future use, from SNI0 datagram */
unsigned spare[32]; /* saved for future expansion */
}

t_gsfR2SonicImagerySpecific;

typedef union t_gsfSensorImagery
{
    t_gsfEM3ImagerySpecific gsfEM3ImagerySpecific; /* used for EM120, EM300, EM1002, EM3000 */
    t_gsfReson7100ImagerySpecific gsfReson7100ImagerySpecific; /* For Reson 71P "snippet" imagery */
    t_gsfReson8100ImagerySpecific gsfReson8100ImagerySpecific; /* For Reson 81P "snippet" imagery */
    t_gsfResonTSeriesImagerySpecific gsfResonTSeriesImagerySpecific; /* For Reson TSeries "snippet" imagery */
    t_gsfEM4ImagerySpecific gsfEM4ImagerySpecific; /* used for EM122, EM302, EM710 */
    t_gsfKlein5410BssImagerySpecific gsfKlein5410BssImagerySpecific; /* used for Klein 5410 Bathy Sidescan */
4.1.3 Single-beam Bathymetry Record

/* Define a single beam record structure */
typedef struct t_gsfSingleBeamPing
{
    struct timespec ping_time;        /* Time the sounding was made */
    double latitude;                 /* latitude (degrees) of sounding */
    double longitude;                /* longitude (degrees) of sounding */
    double tide_corrector;           /* in meters */
    double depth_corrector;          /* in meters, draft corrector for sensor */
    double heading;                  /* in degrees */
    double pitch;                    /* in meters */
    double roll;                     /* in meters */
    double heave;                    /* in meters */
    double depth;                    /* in meters */
    double sound_speed_correction;   /* in meters */
    unsigned short positioning_system_type;
    int sensor_id;
    gsfSBSensorSpecific sensor_data;
} gsfSingleBeamPing;

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

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

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

/*@ Define the BDB sensor specific data struct */
typedef struct t_gsfBDBSpecific
{
    int doc_no; /* Document number (5 digits) */
    char eval; /* Evaluation (1-best, 4-worst) */
    char classification; /* Classification ((U)nclass, (C)onfidential,  

4.1.4 Sound Velocity Profile (SVP) Record

typedef struct t_gsfSVP
{
    struct timespec observation_time;    /* time the SVP measurement was made */
    struct timespec application_time;    /* time the SVP was used by the sonar */
    double latitude;                    /* latitude (degrees) of SVP measurement */
    double longitude;                   /* longitude (degrees) of SVP measurement */
    int number_points;                  /* number of data points in the profile */
    double *depth;                      /* array of profile depth values in meters */
    double *sound_speed;                /* array of profile sound velocity values in m/s */
} t_gsfSVP;
4.1.5 Processing Parameters Record

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

4.1.5.1 Internal Structure for Processing Parameters

#define GSF_MAX_OFFSETS  2
#define GSF_COMPENSATED 1
#define GSF_UNCOMPENSATED 0
#define GSF_TRUEDEPTHS   1
#define GSF_DEPTH_RE_1500_MS 2
#define GSF_DEPTH_CALC_UNKNOWN 3
#define GSF_UNKNOWN_PARAM_VALUE DBL_MIN        /* defined in <float.h> */
#define GSF_TRUE           1
#define GSF_FALSE          0

/* Macro definitions for type of platform */
#define GSF_PLATFORM_TYPE_SURFACE_SHIP  0        /* Add for AUV vs Surface Ship */
/* Add for AUV vs Surface Ship discrimination */
#define GSF_PLATFORM_TYPE_AUV 1
/* Add for AUV vs Surface Ship discrimination */
#define GSF_PLATFORM_TYPE_ROTV 2
typedef struct t_gsfMBOffsets
{
    double draft[GSF_MAX_OFFSETS]; /* meters */
    double roll_bias[GSF_MAX_OFFSETS]; /* degrees */
    double pitch_bias[GSF_MAX_OFFSETS]; /* degrees */
    double gyro_bias[GSF_MAX_OFFSETS]; /* degrees */
    double position_x_offset; /* meters */
    double position_y_offset; /* meters */
    double position_z_offset; /* meters */
    double antenna_x_offset; /* meters */
    double antenna_y_offset; /* meters */
    double antenna_z_offset; /* meters */
    double transducer_x_offset[GSF_MAX_OFFSETS]; /* meters */
    double transducer_y_offset[GSF_MAX_OFFSETS]; /* meters */
    double transducer_z_offset[GSF_MAX_OFFSETS]; /* meters */
    double transducer_pitch_offset[GSF_MAX_OFFSETS]; /* degrees */
    double transducer_roll_offset[GSF_MAX_OFFSETS]; /* degrees */
    double transducer_heading_offset[GSF_MAX_OFFSETS]; /* degrees */
    double mru_roll_bias; /* degrees */
    double mru_pitch_bias; /* degrees */
    double mru_heading_bias; /* degrees */
    double mru_x_offset; /* meters */
    double mru_y_offset; /* meters */
    double mru_z_offset; /* meters */
}
double  center_of_rotation_x_offset;                   /* meters */
double  center_of_rotation_y_offset;                   /* meters */
double  center_of_rotation_z_offset;                   /* meters */
double  position_latency;                               /* seconds */
double  attitude_latency;                               /* seconds */
double  depth_sensor_latency;                           /* seconds */
double  depth_sensor_x_offset;                          /* meters */
double  depth_sensor_y_offset;                          /* meters */
double  depth_sensor_z_offset;                          /* meters */
double  rx_transducer_x_offset[GSF_MAX_OFFSETS];        /* meters */
double  rx_transducer_y_offset[GSF_MAX_OFFSETS];        /* meters */
double  rx_transducer_z_offset[GSF_MAX_OFFSETS];        /* meters */
double  rx_transducer_pitch_offset[GSF_MAX_OFFSETS];    /* degrees */
double  rx_transducer_roll_offset[GSF_MAX_OFFSETS];     /* degrees */
double  rx_transducer_heading_offset[GSF_MAX_OFFSETS];  /* degrees */
} gsfMBOffsets;

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

    /* These parameters defined the installed hardware */
    int number_of_transmitters;
    int number_of Receivers;
/* These parameters specify what corrections have been applied to the data */

int roll_reference; /* = roll is horizontal or rotated pitch axis */
int roll_compensated; /* = GSF_COMPENSATED if depth data roll corrected */
int pitch_compensated; /* = GSF_COMPENSATED if depth data pitch corrected */
int heave_compensated; /* = GSF_COMPENSATED if depth data heave corrected */
int tide_compensated; /* = GSF_COMPENSATED if depth data tide corrected */
int ray_tracing; /* = GSF_COMPENSATED if travel time/angle pairs are compensated for ray tracing */
int depth_calculation; /* = GSF_TRUE Depths, or GSF DEPTHS_RE_1500_MS, applicable to the depth field */
int vessel_type; /* Surface ship, AUV, etc. */
int full_raw_data; /* = GSF_TRUE all data required for full recalculation */
int msb_applied_to_attitude; /* = GSF_TRUE if contains motion sensor biases */
int heave_removed_from_gps_tc; /* = GSF_TRUE if heave removed from gps_tide_corrector */

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

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

} gsfMBParams;

4.1.6 Sensor Parameters Record

#define GSF_MAX_SENSOR_PARAMETERS 128
typedef struct t_gsfSensorParameters
```c
{
    struct timespec param_time;
    int number_parameters;
    short param_size[GSF_MAX_SENSOR_PARAMETERS]; /* array of sizes of param text*/
    char *param[GSF_MAX_SENSOR_PARAMETERS]; /* array of parameters: "param_name=param_value" */
}
gsfSensorParameters;

4.1.7  Comment Record

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

4.1.8  History Record

#define GSF_OPERATOR_LENGTH  64
#define GSF_HOST_NAME_LENGTH 64
typedef struct t_gsfHistory
{
    struct timespec history_time;
    char host_name[GSF_HOST_NAME_LENGTH + 1];
    char operator_name[GSF_OPERATOR_LENGTH + 1];
    char *command_line;
```
4.1.9 Navigation Error Record

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

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

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

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

4.1.11 Attitude Record

typedef struct t_gsfAttitude
{
    short num_measurements; /* number of attitude measurements in this record */
    struct timespec *attitude_time; /* seconds and nanoseconds */
    double *pitch; /* in degrees */
    double *roll; /* in degrees */
    double *heave; /* in meters */
    double *heading; /* in degrees */
}

4.2 Supporting Data Structures and Definitions

4.2.1 Record Identifier

typedef struct t_gsfDataID {
    int checksumFlag;  /* boolean */
    int reserved;      /* up to 9 bits */
    int recordID;      /* bits 00-11 => data type number */
                        /* bits 12-22 => registry number */
    int record_number; /* specifies the nth occurrence of */
                        /* record type specified by recordID */
                        /* relevant only for direct access */
                        /* the record_number counts from 1 */
} gsfDataID;

4.2.2 Time Structure

struct timespec {
    time_t   tv_sec;
    long     tv_nsec;
};

4.2.3 Null values used to represent missing data
/* Define null values to be used for missing data */
#define GSF_NULL_LATITUDE 91.0
#define GSF_NULL_LONGITUDE 181.0
#define GSF_NULL_HEADING 361.0
#define GSF_NULL_COURSE 361.0
#define GSF_NULL_SPEED 99.0
#define GSF_NULL_PITCH 99.0
#define GSF_NULL_ROLL 99.0
#define GSF_NULL_HEAVE 99.0
#define GSF_NULL_DRAFT 0.0
#define GSF_NULL_DEPTH_CORRECTOR 99.99
#define GSF_NULL_TIDE_CORRECTOR 99.99
#define GSF_NULL_SOUND_SPEED_CORRECTION 99.99
#define GSF_NULL_HORIZONTAL_ERROR -1.00
#define GSF_NULL_VERTICAL_ERROR -1.00
#define GSF_NULL_HEIGHT 9999.99
#define GSF_NULL_SEP 9999.99
#define GSF_NULL_SEP_UNCERTAINTY 0.0

/* Define null values for the swath bathymetry ping array types. Note that
* these zero values do not necessarily indicate a non-valid value. The
* beam flags array should be used to determine data validity.
*/
#define GSF_NULL_DEPTH 0.0
#define GSF_NULL_ACROSS_TRACK 0.0
#define GSF_NULL_ALONG_TRACK 0.0
#define GSF_NULL_TRAVEL_TIME 0.0
#define GSF_NULL_BEAM_ANGLE 0.0
#define GSF_NULL_MC_AMPLITUDE 0.0
#define GSF_NULL_MR_AMPLITUDE 0.0
#define GSF_NULL_ECHO_WIDTH 0.0
#define GSF_NULL_QUALITY_FACTOR 0.0
#define GSF_NULL_RECEIVE_HEAVE 0.0
#define GSF_NULL_DEPTH_ERROR 0.0
#define GSF_NULL_ACROSS_TRACK_ERROR 0.0
#define GSF_NULL_ALONG_TRACK_ERROR 0.0
#define GSF_NULL_NAV_POS_ERROR 0.0

4.2.4 Positioning System Type Codes

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

#define GSF_POS_TYPE_UNKN "UNKN"    /* Unknown positioning system type */
#define GSF_POS_TYPE_GPSU "GPSU"    /* GPS Position, unknown positioning service */
#define GSF_POS_TYPE_PPSD "PPSD"    /* Precise positioning service - differential */
#define GSF_POS_TYPE_PPSK "PPSK"    /* Precise positioning service - kinematic */
#define GSF_POS_TYPE_PPSS "PPSS"    /* Precise positioning service - standalone */
#define GSF_POS_TYPE_PPSG "PPSG"    /* Precise positioning service - gypsy */
#define GSF_POS_TYPE_SPSD "SPSD"    /* Standard positioning service - differential */
#define GSF_POS_TYPE_SPSK "SPSK"    /* Standard positioning service - kinematic */
#define GSF_POS_TYPE_SPSS "SPSS"    /* Standard positioning service - standalone */
#define GSF_POS_TYPE_SPSG "SPSG"    /* Standard positioning service - gypsy */
#define GSF_POS_TYPE_GPPP "GPPP"    /* Post Processing - Precise Point Positioning */
#define GSF_POS_TYPE_GPPK "GPPK"    /* Post Processing - Post Processed Kinematic */
#define GSF_POS_TYPE_INUA "INUA"    /* Inertial measurements only, unaided */
#define GSF_POS_TYPE_INVA "INVA"    /* Inertial measurements with absolute velocity aiding */
#define GSF_POS_TYPE_INWA "INWA"    /* Inertial measurements with water-relative
velocity aiding */

#define GSF_POS_TYPE_LBLN "LBLN"   /* One or more long-baseline acoustic navigation lines of position */

#define GSF_POS_TYPE_USBL "USBL"   /* ultra-short baseline acoustic navigation */

#define GSF_POS_TYPE_PIUA "PIUA"   /* Post-processed inertial measurements only, unaided */

#define GSF_POS_TYPE_PIVA "PIVA"   /* Post-processed Inertial measurements with absolute velocity aiding */

#define GSF_POS_TYPE_PIWA "PIWA"   /* Post-processed Inertial measurements with water-relative velocity aiding */

#define GSF_POS_TYPE_PLBL "PLBL"   /* Post-processed One or more long-baseline acoustic navigation lines of position */

#define GSF_POS_TYPE_PSBL "PSBL"   /* Post-processed ultra-short baseline acoustic navigation */