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A DIGITAL FILTER REPRESENTATION OF THE ASQ-81
MAGNETOMETER

by

Michael Charles Huete

September 1983

Thesis Advisor: Andrew R. Ochadlick

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A Digital Filter Representation of the ASQ-81
Magnetometer

by

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requirements for the degree of

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ABSTRACT

A digital filter representation of the ASQ-81 magnetometer is derived from the s-plane transfer functions of the system through the use of a bilinear transformation. A FORTRAN computer program is written which applies this representation to time-sampled total magnetic field data in order to obtain a time series representation of ASQ-81 filtered total field. A series of simulations and a field experiment are conducted which verify the program output. Applications of this program include usage in conjunction with geomagnetic field data in order to produce a new data set representative of geomagnetic noise observed by Navy MAD (Magnetic Anomaly Detection) aircraft with the potential to investigate techniques of reducing geomagnetic noise in MAD aircraft.

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I. INTRODUCTION

The detection and location of submarines (and other magnetic bodies) through the discrimination of changes or anomalies in the Earth's magnetic field is called Magnetic Anomaly Detection or MAD. In this technique, a magnetometer measures the magnitude of the Earth's magnetic field and provides an indication of that magnitude, or, more usually, an indication of changes in the magnitude of the Earth's field. These changes, or anomalies, can indicate the presence of magnetized bodies which may or may not be a submarine.

The magnetometer currently in use in the United States Navy for use in this MAD process is the AN/ASQ-81 metastable helium vapor total field magnetometer.

Research is currently being conducted at the Naval Postgraduate School in Monterey, California, in various aspects of the applications of magnetometers, including Magnetic Anomaly Detection (MAD). Within the context of this research, magnetic field measurements are made through the use of sets of wire wound coils vice any specific magnetometer or magnetic detecting system. The data collected through the use of these coils is evaluated and

processed in a variety of methods for different project goals.

This thesis project is designed to produce an acceptable alternative to the physical presence of an experimental AN/ASQ-81 magnetometer at the postgraduate school by allowing the determination, in conjunction with other research in progress, of the output of the AN/ASQ-81 magnetometer from the data collected from the school's measurement coils. It is hoped that this will assist future research projects as, for example, in allowing a determination of environmental noise of such characteristics as to affect the AN/ASQ-81 magnetometer operationally with the eventual goal of providing an environmental noise index or a system of removing such noise from the magnetometer-detection system.

II. GEOMAGNETICS REVIEW

A. EARTH'S MAGNETIC FIELD

1. Constituents of the Geomagnetic Field

The most common method of specifying the constituting parts of the geomagnetic field is to divide the field in terms of distance from the center of the Earth. This method results in three classifications: internal, crustal, and external. [Ref. 1]

The internal field originates in the core region and is the most stable field, containing only extremely low frequency temporal variations. The crustal, or anomalous, field arises from modifications made on the internal field by materials and structures in the Earth's crust. These variations are not constant with regard to spatial locations, and comprise part of what is known as geological variations. The external field is the most dynamic and arises from many sources, including the interaction between the solar wind and the Earth's magnetic field.

In addition to this method of defining the Earth's magnetic field is the method of time variations. This method consists of considering that part of the field which varies with periodicities greater than about one year as the

steady field and everything else as the variation field.

[Ref. 2]

The steady field consists of the internal field, also referred to as the main field. Slow variations of the main field with periods of years or longer are referred to as secular variations.

There are various elements that contribute to the geomagnetic field, some of which are external to the Earth's surface. External contributions make up only a small part of the steady field, but play an important role in the variation field. These external sources include current systems in the Earth's upper atmosphere affected by solar electromagnetic radiation and gravitation, solar corpuscular radiation and the interaction of solar plasma with the main field, and the effect of the solar interplanetary field.

[Ref. 3]

The geomagnetic field changes with time. As previously mentioned, very slow variations in the main field with periods of on the order of years to thousands of years are referred to as secular variations. Secular variations are caused by a variation in the strength or orientation of the Earth's center dipole.

Other time variations of the field can be categorized into quiet variation fields and disturbed variation fields. Disturbed variation fields include geomagnetic micropulsations, which are of particular interest to

operational forces as these can mask target signatures and are therefore a source of noise to MAD sensors.

Quiet variation fields are those which are not due to disturbances in the interplanetary environment and which vary slowly and regularly. [Ref. 3]

Disturbed variation fields are geomagnetic field variations that appear to be the result of interplanetary environmental changes and do not possess a simple periodicity. These variations include ionospheric disturbances, the aurora, geomagnetic storms, and geomagnetic micropulsations.

2. Elements of the Magnetic Field Vector

The geomagnetic field vector is characterized at any point by its direction and magnitude. This is commonly accomplished through a system of coordinates as shown in Figure 2.1. The field is measured in terms of local coordinates with respect to true North. [Ref. 3]

The various coordinates are referred to as magnetic elements and are defined as follows:

B: Total field intensity (the symbol F is sometimes also used, as in this figure.)

H: Horizontal component

X: Northward, or NorthSouth component

Y: Eastward, or EastWest component

Z: Downward, or Vertical component

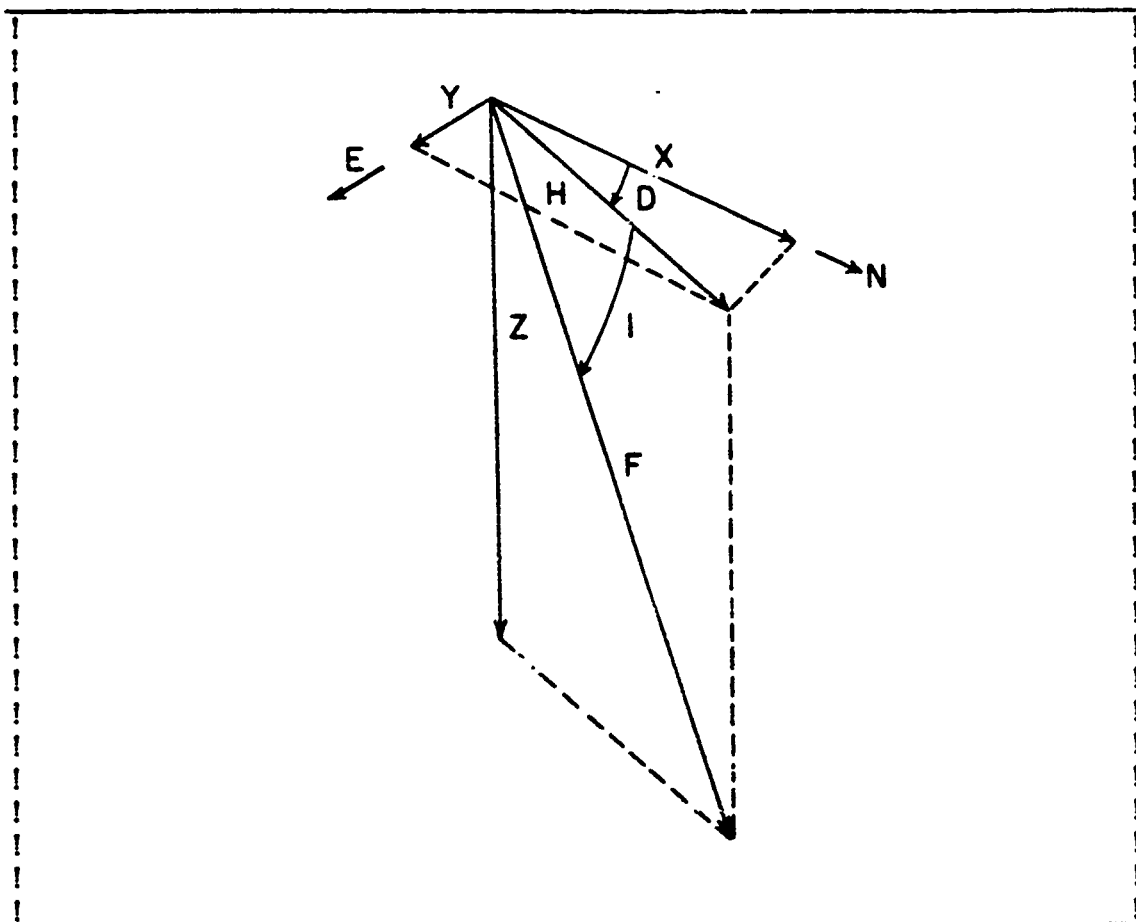


Figure 2.1 Magnetic Field Elements [Ref. 4].

D: Declination or magnetic variation

This is the angle between X and H and is measured positive eastward.

I Inclination or Dip Angle.

This is the angle between H and B (or F) and is measured positive downward.

III. THE AN/ASQ-81 MAGNETOMETER

A. DESCRIPTION OF SYSTEM OPERATION

The Magnetic Anomaly Detecting set currently in use in the U S Navy is the AN/ASQ-81 magnetometer. This set is used to locate and classify submerged submarines by sensing disturbances in the Earth's magnetic field (anomalies) caused by the presence of the magnetic mass of the submarine. The disturbance of the Earth's field is detected by the magnetometer, processed through filtering circuits, and amplified. The output signal of the magnetometer is displayed on a chart recorder for interpretation by an operator.

The magnetic detecting set is a metastable helium vapor magnetometer. The operation of the magnetometer is based on the light absorption properties of helium gas subjected to certain light stimulus (optical pumping), radio frequency excitation, and the Earth's magnetic field. The magnetometer consists of a helium lamp, lens and polarizer to generate a beam of polarized light radiation. This focused and polarized light beam is directed through a helium absorption cell to an infrared (IR) detector. Some of the helium gas in the absorption cell is maintained in a metastable state by application of VHF excitation.

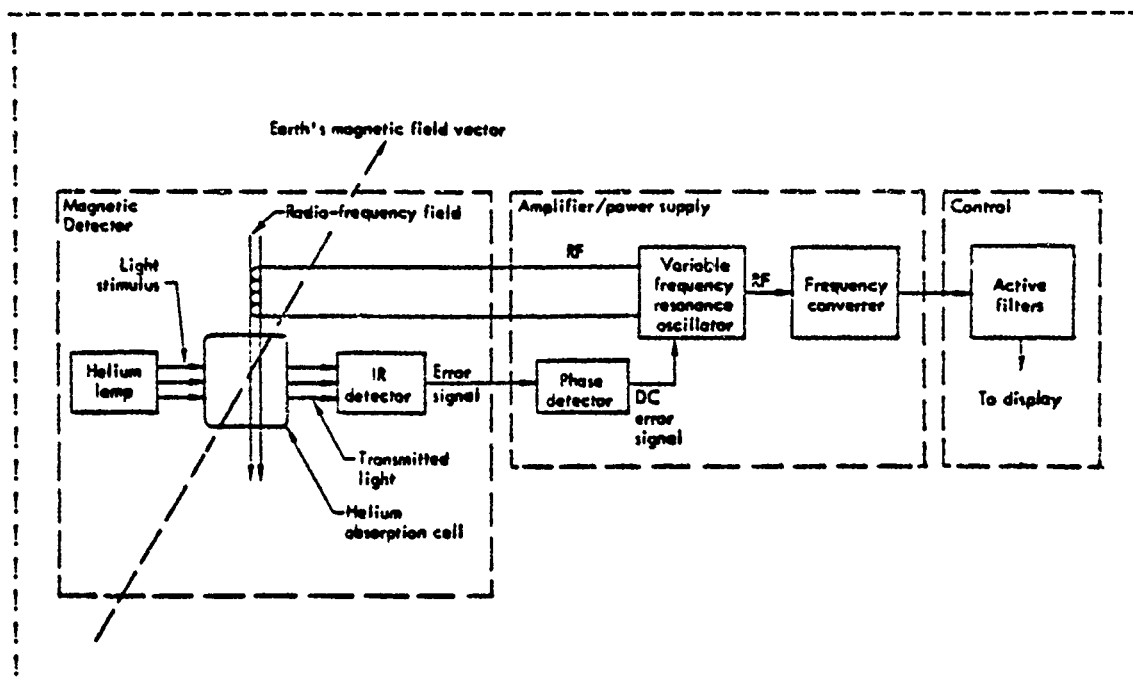


Figure 3.1 : Metastable Helium Magnetometer [Ref.5].

The Earth's magnetic field imposes a magnetic force upon the excited helium vapor atoms to force the atoms into one of three energy sublevels. This is called the Zeeman effect. The rate or frequency of atomic precession caused by this effect is called the Larmor frequency. A helium lamp is used to optically pump the atoms in the absorption cell, with the result that the polarized light energy passing through the absorption cell will polarize (magnetize) the helium atoms in the absorption cells by selectively pumping the Zeeman levels of the energy of the helium atoms in the cell. The magnetization direction is determined by the polarization of the photons from the helium lamp.

RF energy is then introduced to the absorption cell in the form of an additional magnetic field imposed through the use of coils oriented perpendicular to the precessed polarized helium atoms in the absorption cell and energized by a variable frequency RF oscillator. The RF oscillator is tuned to the Larmor frequency, which results in depolarization of the atoms. The atoms attempt to equally repopulate the Zeeman energy levels. However, the helium lamp is still beaming polarized light energy into the absorption cell, causing the atoms to absorb light energy and rise to an excited energy level. This absorption of light energy is detected through the use of an infrared detector. The RF oscillator frequency producing maximum light absorption is called the resonant frequency, and is determined through the use of a servo loop from the infrared detector to the RF variable frequency oscillator.

Therefore, any change in the Earth's magnetic field intensity will result in a change in the Larmor frequency of the helium atoms in the helium absorption cell. This new Larmor frequency will be detected by the ASQ-81 magnetometer. Since the gyromagnetic ratio of helium is 28.024 HZ per gamma, this detection of the resonant frequency provides a measurement of the Earth's magnetic field intensity at any given time. A change in the Earth's

magnetic field intensity could signal the presence of a submerged submarine.

The output resonant frequency developed by the magnetometer is converted to a proportional output voltage which is filtered through the Magnetic Anomaly Detection (MAD) bandpass filters for environmental noise reduction and utilized to drive a chart recorder for observation by an operator. [Ref. 6]

B. TRANSFER FUNCTIONS

Transfer functions for the AN/ASQ-81 filters were obtained from the manufacturer of the AN/ASQ-81 detecting set, Texas Instruments of Dallas, Texas. These transfer functions are listed in Appendix A and are in the form of $H(s)$, that is, the frequency domain, or S domain, where $S = j\omega$. The s -domain representation for transfer functions is routinely utilized to express output system characteristics for given system inputs. As the S domain representation is not utilized further in this discussion, it will not be further explained.

As the output signal of the ASQ-81 magnetometer is filtered through a fixed high-pass system, then through a selectable low pass system and a selectable high pass system (as shown in Figure 3.2 below), the transfer functions are listed in this order.

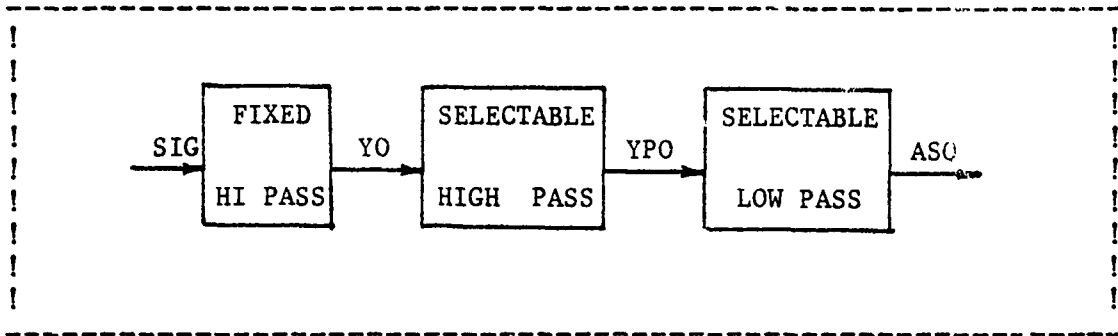


Figure 3.2 : Signal Flow Diagram for ASQ-81

Further discussion will be made of the selectable filters later.

IV. DIGITAL FILTERING MODELLING OF SYSTEMS

A. SEQUENCE REPRESENTATION OF TIME FUNCTIONS

1. Signal Representation

A signal can be defined as a function that conveys information, generally about the state or behavior of a physical system. Although signals can be represented in many ways, the information conveyed by the signal is contained in a pattern of variations of some form. Signals are represented mathematically as functions of one or more independent variables, one of the most common of which is time.

The independent variable of the mathematical representation of a signal may be continuous or discrete. Continuous time signals are signals that are defined over continually values of time and are therefore represented by continuous-variabed functions. Discrete time signals are defined at discrete time intervals and are therefore represented by functions whose independent variable(s) take on discrete values only. Discrete-time signals are represented as sequences of numbers. [Ref. 7]

In addition to the fact that the independent variables can be either continuous or discrete, the signal amplitude can be either continuous or discrete. Digital

signals are those for which both time and amplitude are discrete. Analog signals are those for which both time and amplitude are continuous.

Digital signal processing deals with transformations of signals that are discrete in both time and amplitude, usually represented by sequences of numbers. The nth number in the sequence x being processed is usually represented as x(n), and is formally written as:

$$x=[x(n)], \quad -\infty < n < +\infty$$

In general, an arbitrary sequence can be expressed as

$$x(n) = \sum_{k=-\infty}^{\infty} x(k) d(n-k)$$

where d(n-k) is the unit sample at time k. In other words, an arbitrary sequence may be expressed as a sum of scaled, shifted unit samples, where the scaling factor is equal to the amplitude of the sequence at that time.

2. Linear Shift-Invariant Systems

A system is defined mathematically as a unique transformation or operator that maps an input sequence [x(n)] into an output sequence [y(n)]. This is denoted as:

$$y(n) = T[x(n)]$$

and is often depicted as in Figure 4.1.

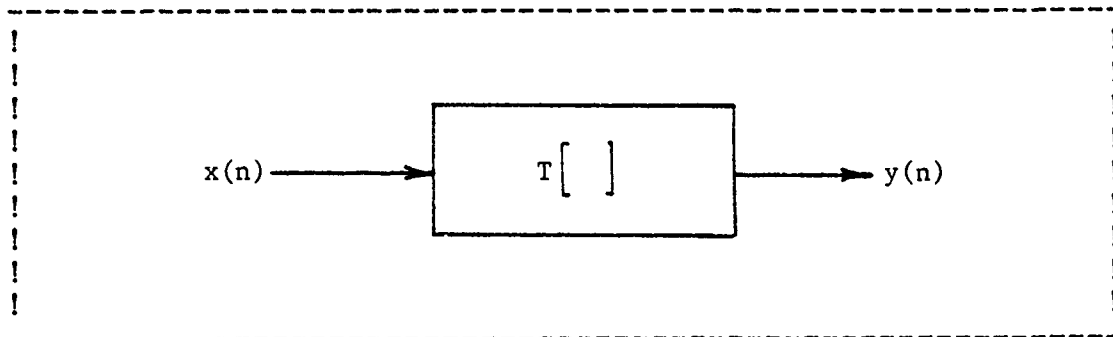


Figure 4.1: Representation of Transformation of an Input Sequence to an Output Sequence. [Ref.7]

Classes of discrete time systems are defined by placing constraints on the transformation $T[\]$.

The class of linear systems is defined by the principle of superposition. If $y_1(n)$ and $y_2(n)$ are the responses when $x_1(n)$ and $x_2(n)$ are the inputs, then a system is linear if

$$\begin{aligned} T[ax_1(n) + bx_2(n)] &= aT[x_1(n)] + bT[x_2(n)] \\ &= ay_1(n) + by_2(n) \end{aligned}$$

for any arbitrary constants a and b . This, together with the concept of representing a sequence by a sum of delayed and scaled unit-sample sequences, suggests that a linear system can be characterized by its unit-sample response. Specifically, let $h_k(n)$ be the response of the system to $d(n-k)$, a unit sample occurring at $n=k$. Then

$$y(n) = T\left[\sum_{k=-\infty}^{\infty} x(k) d(n-k)\right] \quad \text{or,}$$

$$y(n) = \sum_{k=-\infty}^{\infty} x(k) T[d(n-k)] = \sum_{k=-\infty}^{\infty} x(k) h_k(n)$$

Thus the system response can be expressed in terms of the response of the system to $d(n-k)$.

The class of shift invariant systems is characterized by the property that if $y(n)$ is the response to $x(n)$, then $y(n-k)$ is the response to $x(n-k)$, where k is a positive or negative integer. When the index n is associated with time, shift-invariance corresponds to time-invariance. The property of shift invariance implies that if $h(n)$ is the response to $d(n)$, then the response to $d(n-k)$ is simply $h(n-k)$. Therefore

$$y(n) = \sum_{k=-\infty}^{\infty} x(k) h(n-k)$$

and any linear shift-invariant system is completely characterized by its unit-sample response $h(n)$.

A subclass of linear shift-invariant systems consists of those systems for which the input $x(n)$ and the output $y(n)$ satisfy an N th-order linear constant-coefficient difference equation of the form

$$\sum_{k=0}^N a_k y(n-k) = \sum_{r=0}^M b_r x(n-r)$$

If the assumption of causality is made about the system, a linear difference equation provides an explicit relationship between the input to the system and the output of the system. This can be seen by rewriting the previous equation as

$$y(n) = \sum_{k=1}^N c_k y(n-k) + \sum_{r=0}^M d_r x(n-r)$$

where $c_k = -a_k / a_0$ and $d_r = b_r / a_0$.

Thus the n th value of the output can be computed from the n th value of the input and the N and M past values of the output and input, respectively. The difference equation not only represents the system for theoretical purposes, but it may also serve as a computational realization of the system. The z -Transform makes use of this property to realize systems.

B. THE z -TRANSFORM

1. Description of the z -Transform

The z -transform plays an important role in the analysis and representation of discrete-time linear shift-invariant systems. The z -transform, $X(z)$, of a sequence $x(n)$ is defined as

$$X(z) = \sum_{n=-\infty}^{\infty} x(n)z^{-n}$$

where z is a complex variable. This representation of the z -transform is referred to as the two-sided z transform. The one sided z -transform consists of the same summation for terms of n greater than or equal to zero. For the case that $x(n)=0$ for $n<0$, the one sided and two sided z transforms are equivalent.

By expressing the complex variable z in polar form as $z = re^{j\omega}$, the z -transform can be interpreted as the Fourier transform of $x(n)$ multiplied by an exponential sequence. For $r = 1$, that is, for $|z| = 1$, the z -transform is equal to the Fourier transform of the sequence.

2. The Bilinear Transformation

The transfer functions of analog systems are most often expressed in terms of $s = j\omega$ (see section III B.). This corresponds to the analog frequency response of the system. This analog frequency response can be "mapped", that is, transformed to the z -plane from the s -plane through the use of the bilinear transformation. The effect of utilizing the bilinear transformation is to convert a system transfer function in terms of the variable S into the system transfer function in terms of the variable z . The transformation itself is:

$$s = \frac{2}{T} \frac{1 - z^{-1}}{1 + z^{-1}}$$

and

$$z = \frac{(2/T) + s}{(2/T) - s}$$

where T is the sampling period, that is, the time between data samples.

Thus a transform can be made from one plane to the other. In this manner, the transfer function, $H(z)$, of a system may be obtained.

The bilinear transformation equations may be shown to hold in general, and the use of this transformation may be shown to yield stable digital filters from stable analog filters [Ref. 7]. The bilinear transformation maps the imaginary $j\omega$ axis in the s -plane onto a unit circle (of the region of convergence) in the z -plane, with the left half s -plane mapped onto the region inside the circle and the right hand (region of instability) s -plane mapped onto the region outside this circle [Ref. 8]. A complete discussion of the z -transform is available in several texts, some of which are listed in the Bibliography.

C. THE DIGITAL COMPUTATIONAL ALGORITHM

In implementing a digital filter on a digital computer such as the IBM 3033, the input-output relationship of the signals through the system being synthesized must be converted to a computational algorithm. The algorithm is specified in terms of a set of basic computations of elements. For the implementation of discrete-time systems

described by linear constant coefficient difference equations, such as the AN/ASQ-81, it is convenient to choose as these elements the basic operations of addition, delay, and multiplication by a constant. The computational algorithm for implementing the filter is then defined by a structure or network consisting of an interconnection of these basic operations. For a system transfer function of the form

$$H(z) = \frac{\sum_{k=0}^M b_k z^{-k}}{1 - \sum_{k=1}^N a_k z^{-k}} = \frac{Y(z)}{X(z)}$$

the difference equation relating input and output is easily written down directly from the system function and is given by

$$y(n) = \sum_{k=1}^N a_k y(n-k) + \sum_{k=0}^M b_k x(n-k) \quad [\text{Ref. 7}]$$

This difference equation can be interpreted directly as a computational algorithm in which the delayed values of the input are multiplied by the coefficients b_k , the delayed values of the output are multiplied by the coefficients a_k , and the resulting products are added. It is now easy to see the process to be followed in obtaining the computational algorithm for the AN/ASQ-81 magnetometer

transfer function. The z-transform of the system transfer function is obtained through the use of the bilinear transformation, and is then converted into a difference equation relating input and output signals, thence to a FORTRAN computer program. A table of z-transforms of system functions is included in Appendix B.

In the FORTRAN computer program realization of the total system computational algorithm, each filter block is transformed into a separate difference equation and algorithm. This was done to enable a "building block" type approach to the program, and to minimize computational and roundoff errors.

D. THE CASCADE FORM OF THE COMPUTATIONAL ALGORITHM

Even though the direct form realization of the digital filter design may be perfectly satisfactory in a theoretical sense, it may be less than desirable in the context of realization through the use of a general purpose computer of fixed register length. The parameters of a digital filter are usually obtained with a high degree of accuracy, which results in a faithful realization of the desired system. When these parameters are quantized, as in a finite memory register within a computer, the frequency response of the resulting digital filter may differ appreciably from the original design. In fact, the quantized filter may fail to

meet design specifications although the unquantized filter does. [Ref. 7]

The sensitivity of the filter response to errors in the filter parameters is dependent upon the structure of the filter realization. Therefore, in the event of an unacceptable change in the frequency response of the filter due to quantization errors, it is often possible to minimize the effect of these errors through an alternate filter realization structure. An alternate structure to the previously discussed direct form realization is the cascade form realization.

The direct form network structures were obtained directly from the system function $H(z)$ written in the form of a ratio of sums. If this ratio is factored into a product of polynomials of the form

$$H(z) = A \prod_{k=1}^{[(N+1)/2]} \frac{1 + B_{1k} z^{-1} + B_{2k} z^{-2}}{1 - a_{1k} z^{-1} - a_{2k} z^{-2}}$$

this product represents a general distribution of poles and zeros and suggests a set of structures consisting of a cascade of first and second-order subsystems. There is considerable freedom in the design of the subsystems, but it is best to realize the systems using a minimum of storage.

The expression of $H(z)$ in this form indicates the presence of poles and zeros in pairs. If poles and zeros

are not present in pairs, one of the coefficients B_{2k} or a_{2k} will be zero as appropriate. An implementation of such a cascade structure with the use of minimum memory can be obtained through a direct form II realization of each second order subsystem using techniques similar to the direct form implementation utilized previously. A cascade realization of a sixth-order system, such as the ASQ-81 system, using a direct form II realization of each second order subsystem would appear as in Figure 4.2 below.

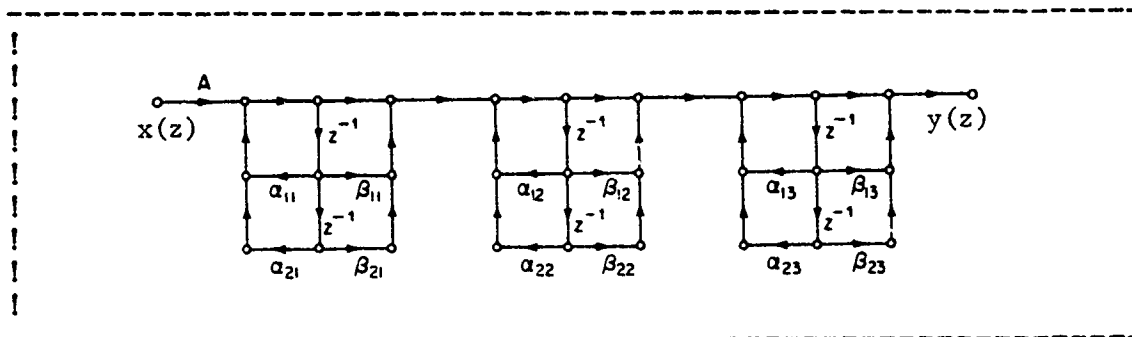


Figure 4.2: Cascade Structure With a Direct Form II Realization of Each Second Order Subsystem. [Ref. 7]

There is, theoretically, considerable flexibility in the manner in which the poles and zeros are paired together and in the order in which the resulting second-order subsystems are cascaded. However, although all such pairings and orderings are equivalent for infinite-precision arithmetic, they may differ considerably in practice owing to finite word length effects of roundoff and truncation.

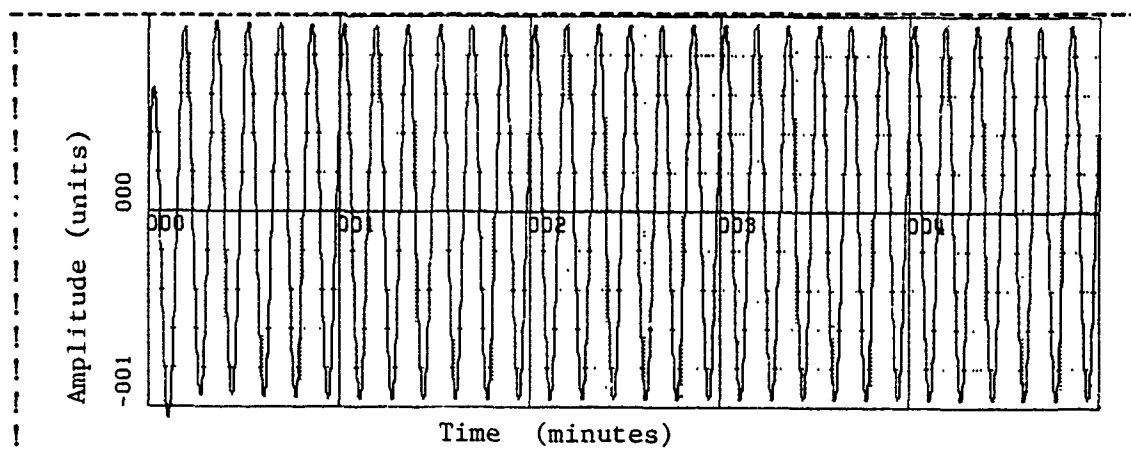


Figure 5.1: Output of First Stage Filter of Digital Filter Computer Program With Sinusoidal Input in Simulation.

Unfortunately, the second stage output of the filter showed an instability within the program design, indicated by the output of the filter being a sinusoid of increasing magnitude, as indicated in Figure 5.2 below.

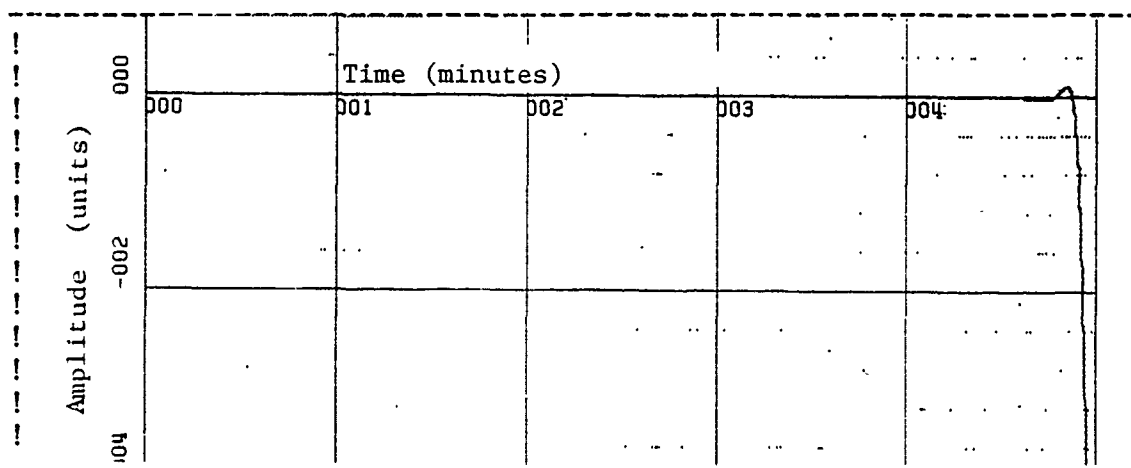


Figure 5.2: Output of Second Stage Filter Design With Input of a Sinusoid.

The stability of the third stage of the filter design was investigated by inputting the sinusoid directly to the third filter, and found to be stable. A check of the derivation of the equations, coefficients, and programming steps of the second (unstable) filter of the design failed to indicate the cause of the instability.

Computation of the poles of the z transfer function, $H(z)$, of the second stage of the filter confirmed the instability of the design. The poles were computed to be: $0.92 \pm 0.1218i$, $1.07 \pm 0.1340i$, 0.8611 , and 1.1564 . Of these six poles, three lie outside the region of convergence for the z -plane, that is, within the unit circle discussed previously in Chapter IV.

The second stage of the filter was therefore redesigned using the cascade form of the direct form realization (direct form II), and tested in simulation. A copy of the software used in the simulation is enclosed in Appendix F.

The output of all three filter stages of the program were stable, as indicated in Figures 5.3 through 5.7 below. The amplitude decrease and phase shift expected were observed. The "damped overshoot" of the second stage output is due to the fact that, for values of the input function prior to time zero in the simulation, utilized in the input-output signal difference equations for the filter, the input signal was set at 0. This resulted in an instantaneous

change of the input signal from 0 to the finite value introduced in the simulation at time 0+. The "overshoot" of the filter is the filter's attempt to "match" this instantaneous jump in magnitude of the input signal. When the input signal to the filter in the simulation is zero at time zero, this overshoot effect does not occur.

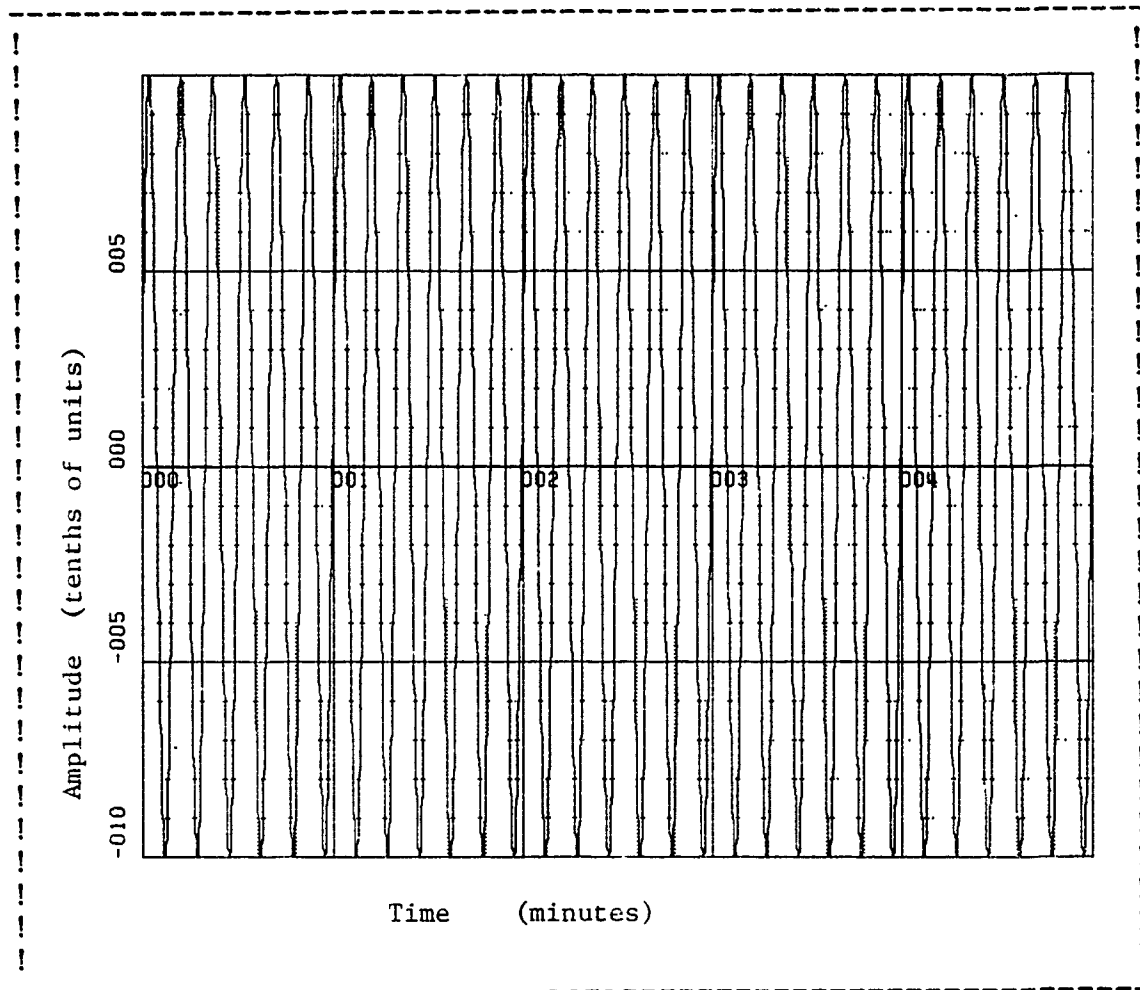


Figure 5.3: Input Signal to Digital Filter Program. A Sinusoid of Frequency 0.1 HZ and Amplitude ± 1 .

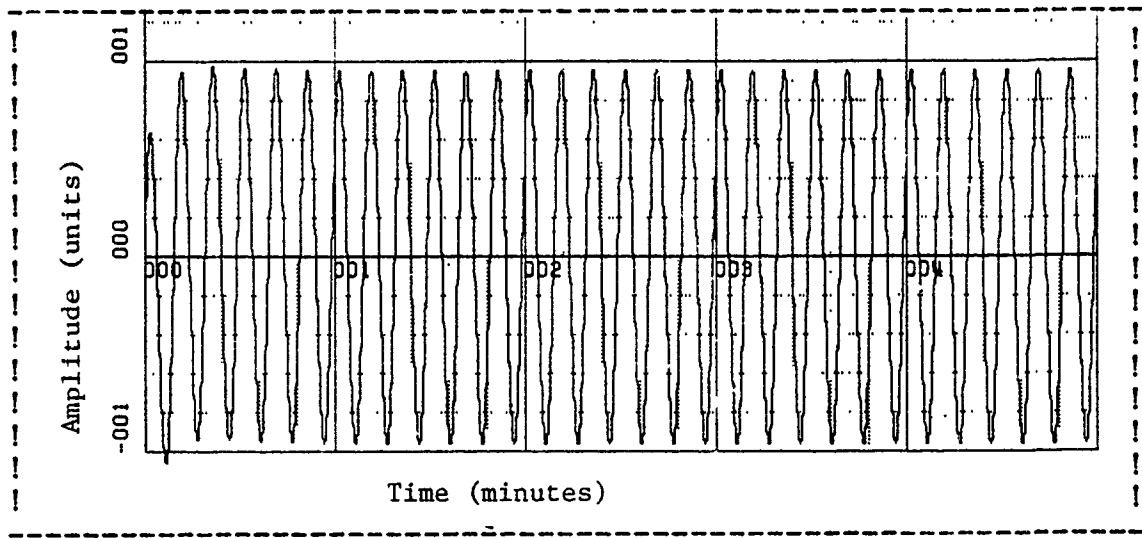


Figure 5.4: Output of First Stage of Digital Filter Program.

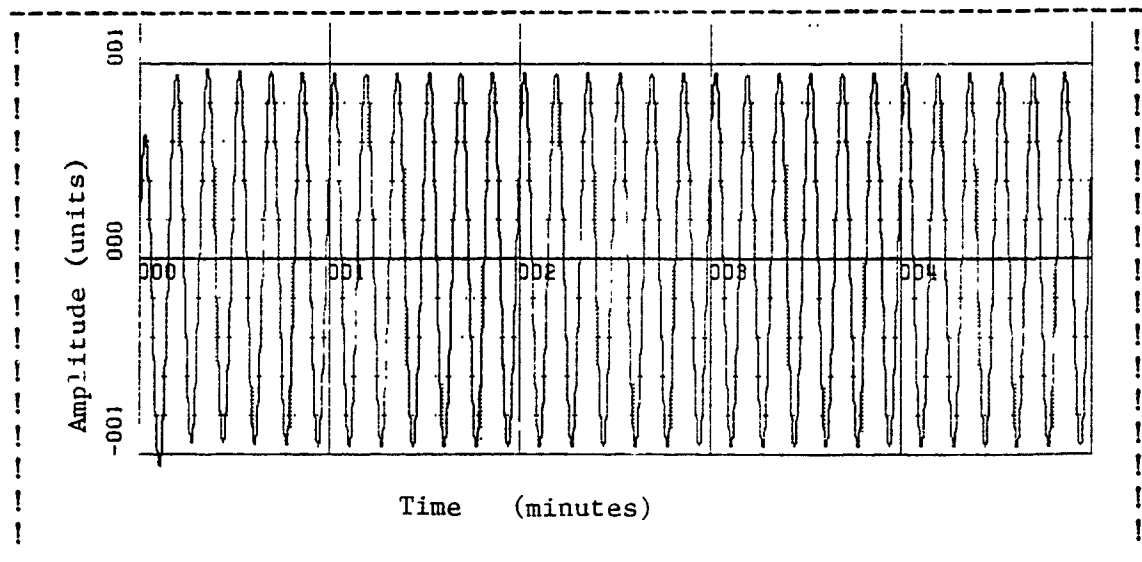


Figure 5.5: Output of Second Stage of Digital Filter Program.

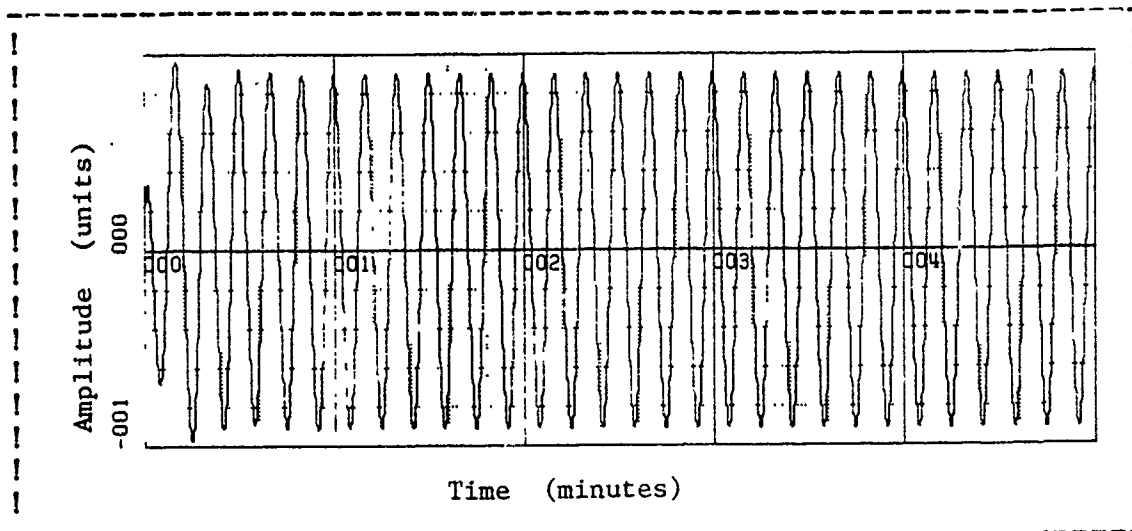


Figure 5.6: Output of Third Stage of Digital Filter Program.

This simulation was run with inputs of sinusoids of various frequencies in order to check the stability of the filter design at frequencies throughout the operating range of the AN/ASQ-81 magnetometer. In all cases, the design was stable, and the expected amplitude changes and phase shifts occurred.

2. Noiselike Inputs

The simulation was also run with inputs consisting of a sinusoid of a frequency which should be passed through the AN/ASQ-81 added to sinusoids of frequencies which should have been filtered by the magnetometer and random noise. The filter performed as expected, with the sinusoid of a passable frequency passed by the filter, and spurious noise and sinusoids attenuated severely. The results of a simulation consisting of a sinusoid of passable frequency, a

filterable sinusoid, and uniformly distributed random noise, all of amplitude ± 1 , are presented in Figures 5.7 through 5.10 below.

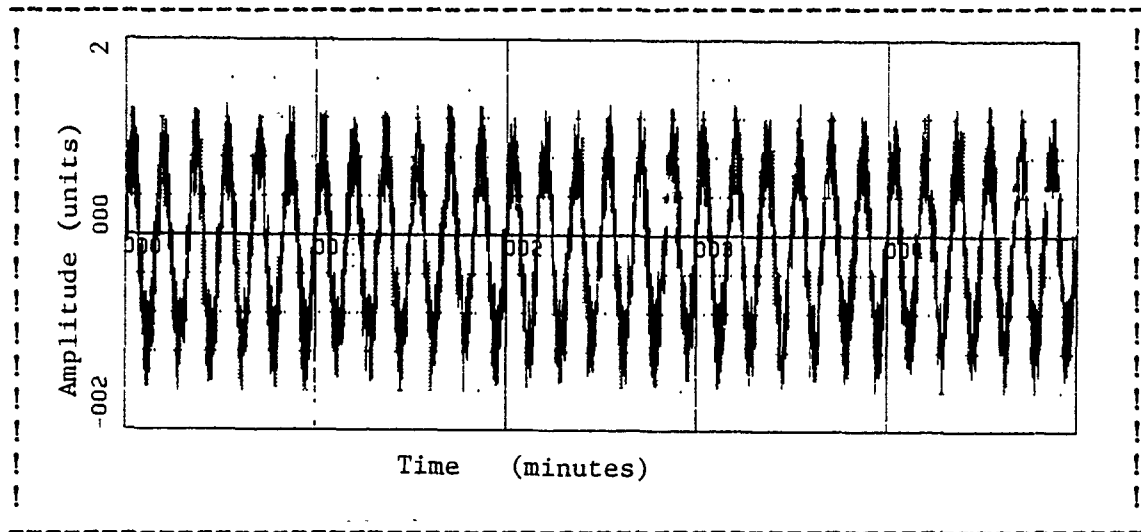


Figure 5.7: Input to Filter - 0.1 HZ Sinusoid, 10 HZ Sinusoid, Uniformly Distributed Random Noise of Amplitude ± 1 .

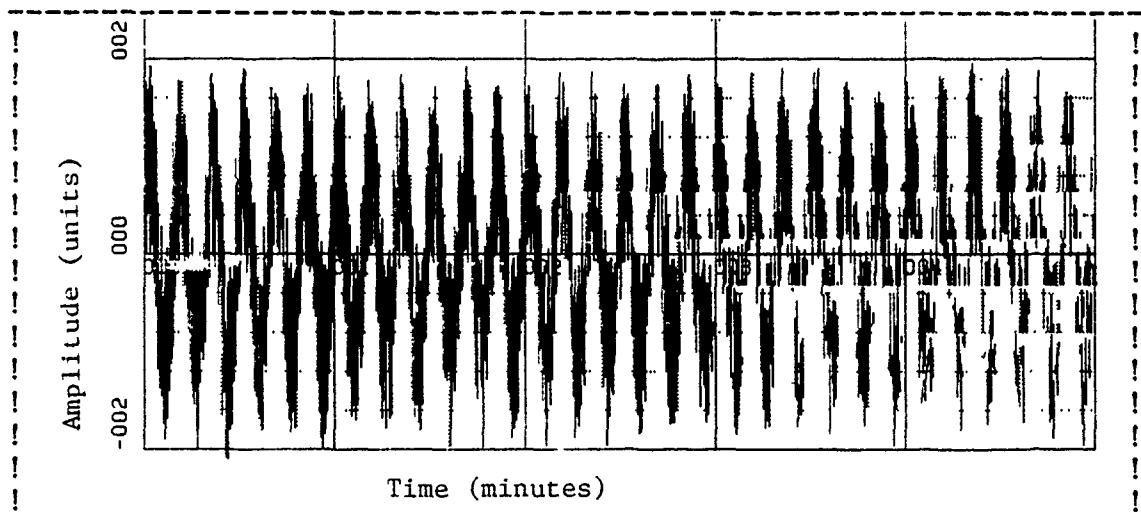


Figure 5.8: Output of First Filter Stage.

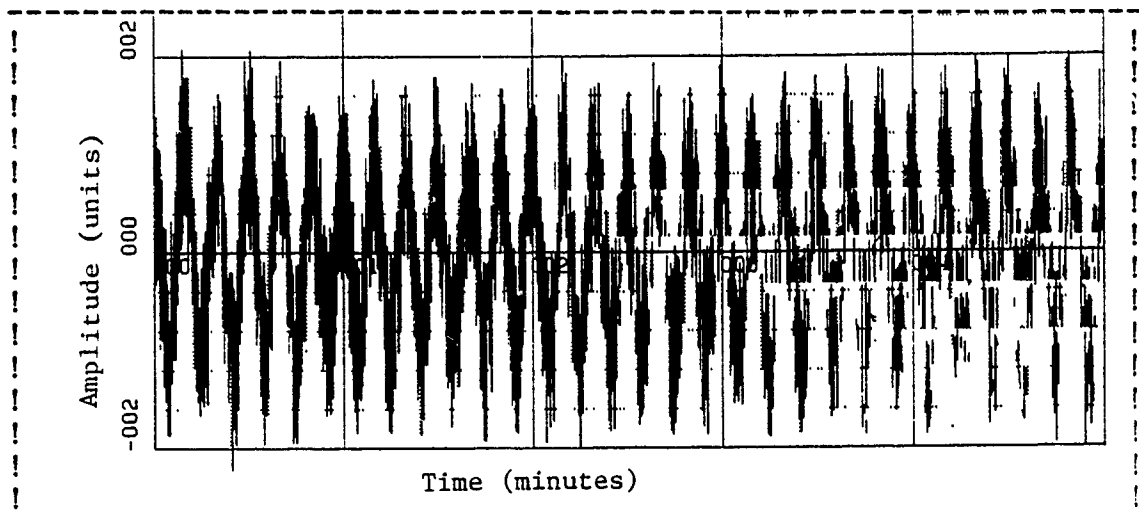


Figure 5.9: Output of Second Filter Stage.

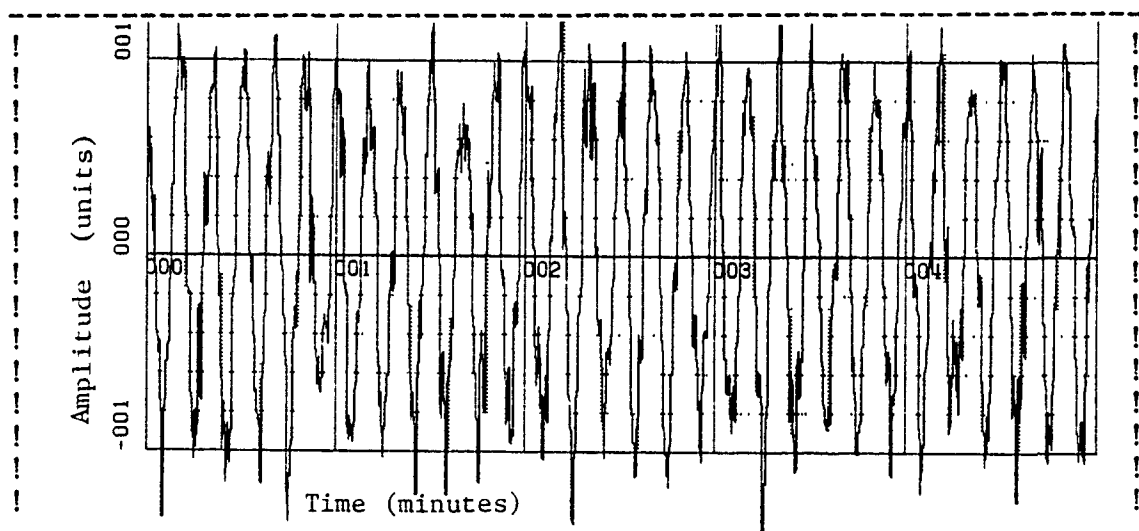


Figure 5.10: Final Filter Stage Output.

As can be seen, the digital filter program succeeds in filtering out random noise and signals of frequency components above the band pass of the magnetometer.

In order to ensure that the digital filter representation of the magnetometer has the same amplitude

versus frequency characteristics of the AN/ASQ-81 magnetometer, a simulation program was written which inputs sinusoids of varying frequencies and computes the Root Mean Square (RMS) value of the filter output and the signal input, then computes the decibel (dB) attenuation of the filter at that frequency. A copy of this program is included in Appendix G. A plot was made of the dB attenuation versus frequency for the filter and compared

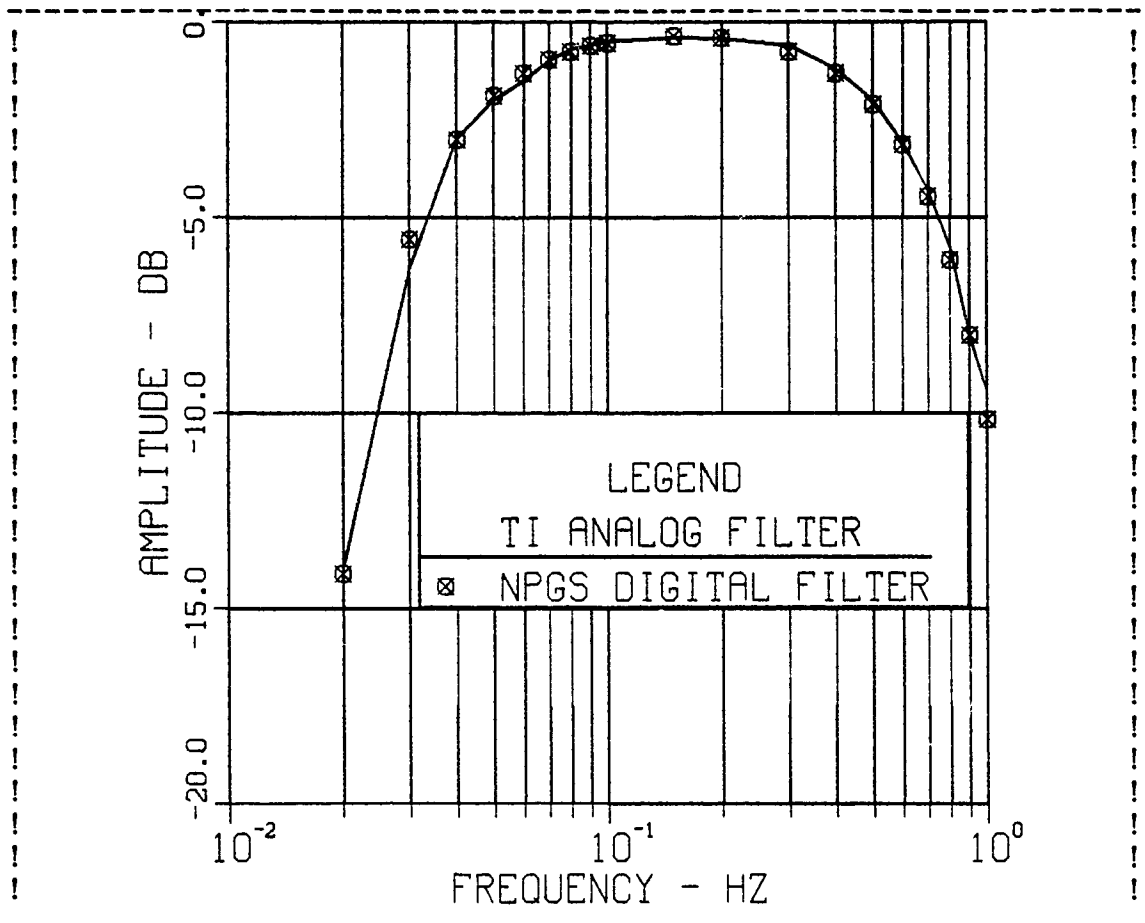


Figure 5.11: Plot of Attenuation Versus Frequency for Sinusoidal Inputs for Digital Filter and Analog Filter.

with the measured frequency performance of the AN/ASQ-81 magnetometer, which was supplied by Texas Instruments, Inc., and does not include the effects of the fixed high pass filter. Consequently, the data shown in Figure 5.11 is a comparison of the data supplied by Texas Instruments and the output of the test program, which also does not include the fixed high pass filter. As can be seen, the performance of the filter is extremely similar to that of the magnetometer itself.

3. Anderson Function Simulations

The next step in the simulation phase was the introduction to the filter of Anderson function simulations. The shape of the signal amplitude of the output of a magnetometer passing through the sphere of influence of a magnetic anomaly (submarine) is a function of the dip angle of the geomagnetic field, the magnetic heading of the track of the magnetometer (or the aircraft), the magnetic heading of the anomaly (submarine) dipole, and the lateral range between the magnetometer (aircraft) and the anomaly. Anderson functions [Ref. 9] are mathematical representations of three basic components of signals which, when taken in various linear combinations, describe the shape of these anomaly signals. The equations for the Anderson functions are:

$$\begin{aligned}
 \text{(First Anderson Function)} \quad f_0 &= \frac{1}{(1 + B)^{2.5/2}} \\
 \text{where} \quad B &= \frac{(\text{velocity}) \times (\text{time})}{\text{range at CPA}}
 \end{aligned}$$

or, a dimensionless parameter defined as the distance traveled along the magnetometer (aircraft) track divided by the slant range at closestpoint of approach (CPA)

$$\begin{aligned}
 \text{(Second Anderson Function)} \quad f_1 &= B \times f_0 \\
 \text{(Third Anderson Function)} \quad f_2 &= B \times f_1 = B^2 \times f_0
 \end{aligned}$$

The Anderson functions were introduced into the filter program in a noise-free signal environment in order to observe the output signal and ensure that it was a "MAD-like" signal. A rigorous determination of the actual output signal would have been extremely difficult to obtain, so a comparison was made with the output of a computer simulation program provided to NPS by Mr. Joe Rice of Texas Instruments. When the sampling rate of the program was adjusted to equal that of the Texas Instruments program, 8 HZ, the two program outputs were observed to be very similar. The Anderson function simulation inputs and outputs of the program are depicted in Figures 5.12 through 5.18. The Texas Instruments program outputs were obtained in the form of time series plots of discontinuous data points, and were therefore not conducive to replotting for comparison.

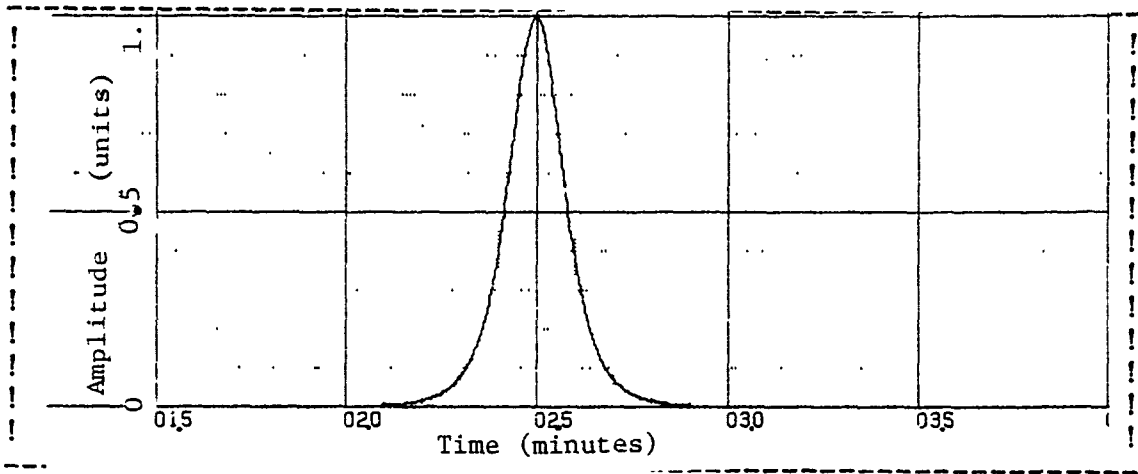


Figure 5.12: First Anderson Function Input. CPA at Time 2.5 Minutes.

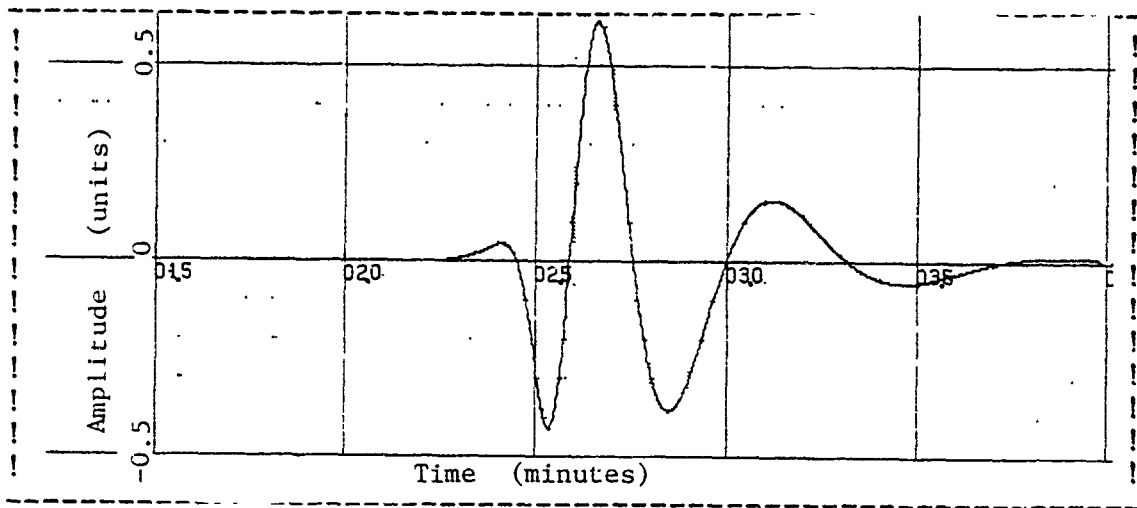


Figure 5.13: Filter Output for First Anderson Function Input.

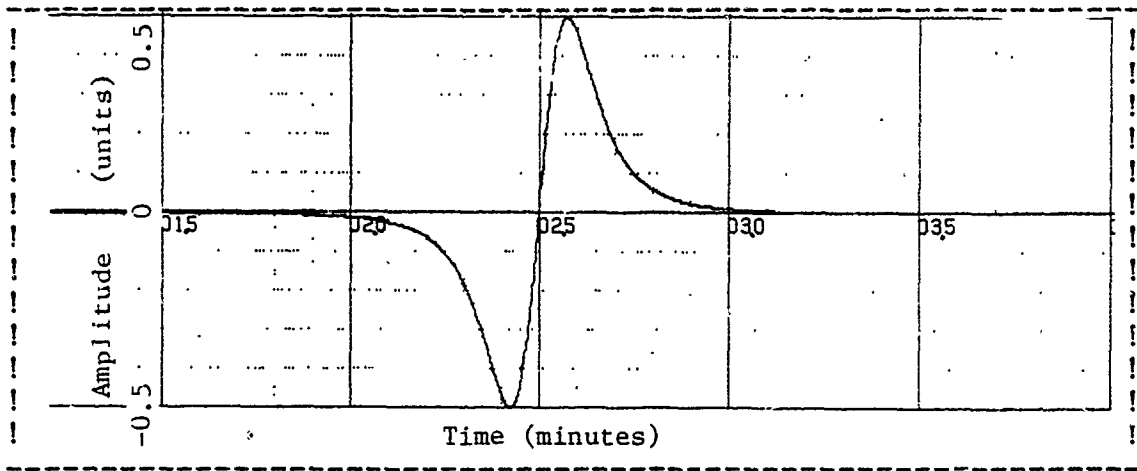


Figure 5.14: Second Anderson Function Input. CPA at Time 2.5 Minutes.

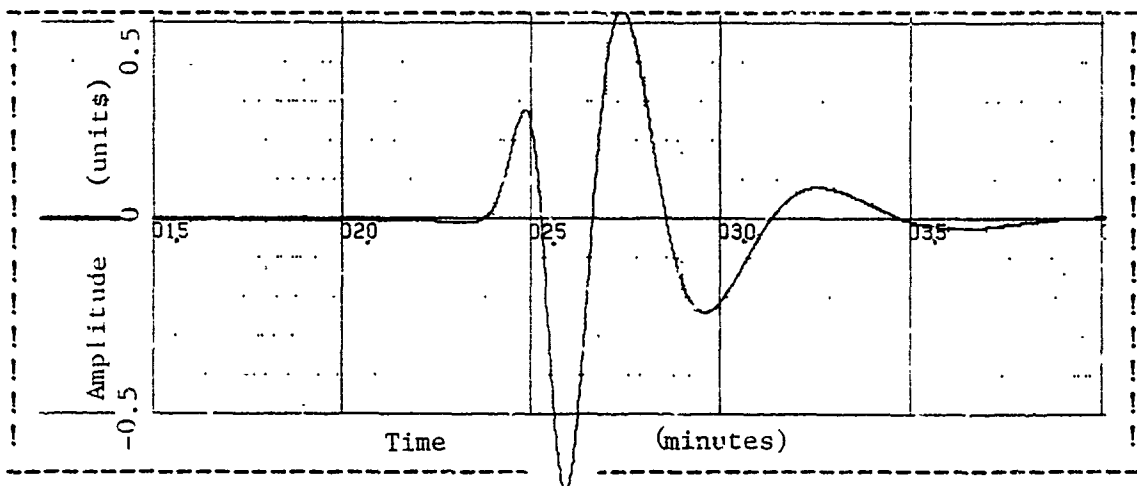


Figure 5.15: Filter Output for Second Anderson Function.

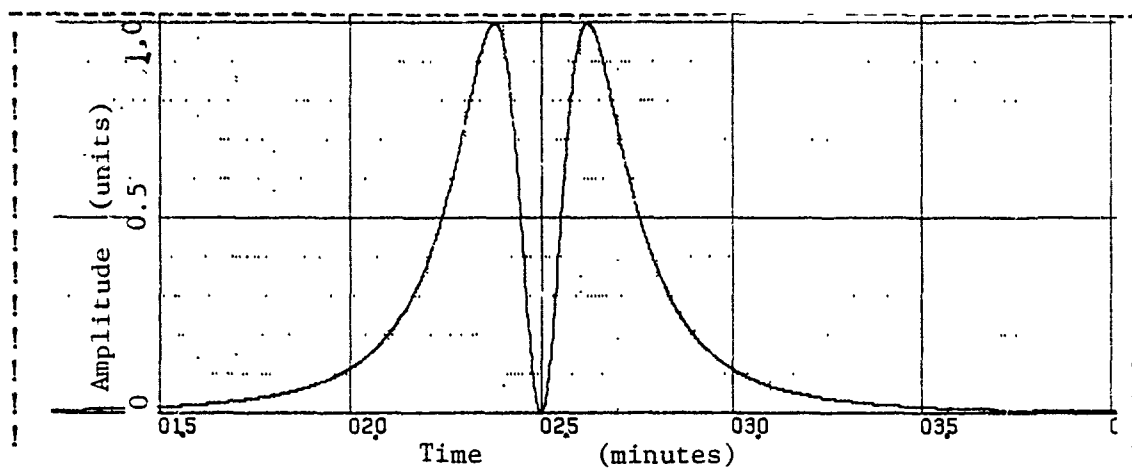


Figure 5.16: Third Anderson Function Input. CPA at Time 2.5 Minutes.

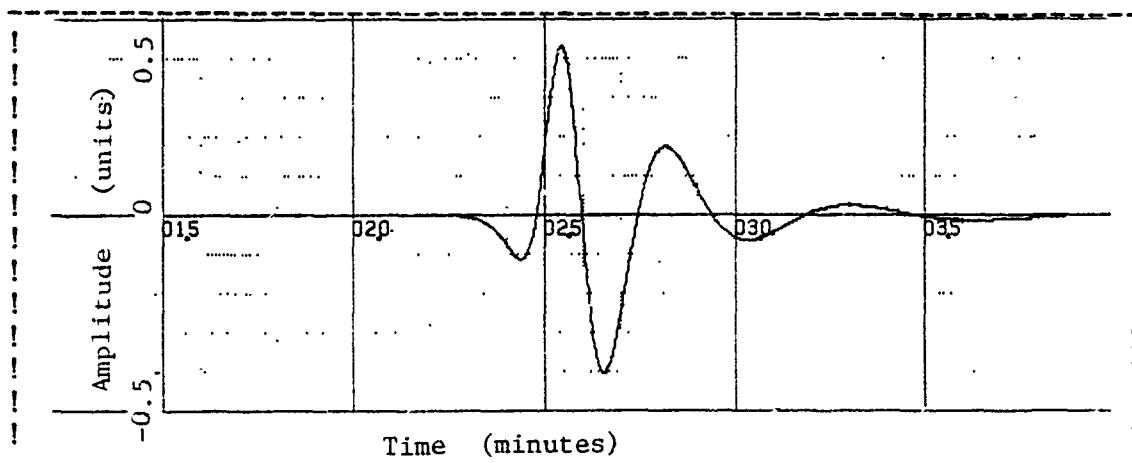


Figure 5.17: Filter Output for Third Anderson Function.

The filter output for all three Anderson function inputs did appear to be "MAD-like" signals, and did closely resemble the simulation output obtained from Texas Instruments, Inc.

4. Impulse Function Response

The response of the filter program was also observed when the input was a unit impulse function. Again, the

output was compared to that of the Texas Instruments' computer program. The outputs of the two programs were observed to be, again, very similar, as can be seen in Figure 5.18, where the response of the NPGS filter is represented by a solid line and that of the Texas Instruments filter by a chain-dash line. The abrupt "jumps"

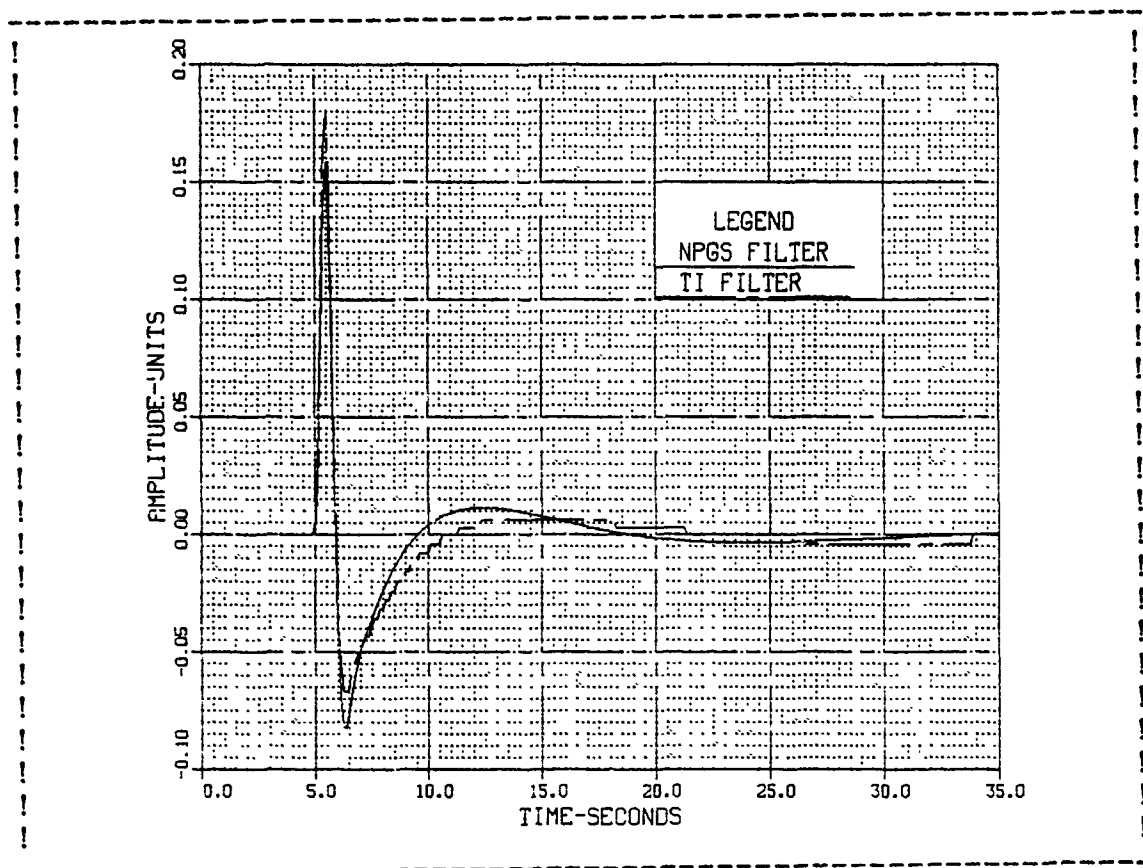


Figure 5.18: Impulse Response of Filters.

of the Texas Instruments response are due to the translation of the output plot supplied to this plot. The plot supplied by Texas Instruments was, again, discontinuous points of poor resolution, and it was necessary to interpolate values

in order to generate Figure 5.18. This resulted in the broken appearance of the plot. Even so, the similarity of the outputs can be observed.

B. EQUIPMENT SETUP

Following the simulation phase of the experiment, actual magnetic field measurements were introduced to the filter in order to test the response of the filter. Magnetic field measurements were made at the La Mesa field test site near the Naval Postgraduate School in Monterey. The output of an AN/ASQ-81 magnetometer, a Schonstedt magnetic field sensor, and the school's coil sensor, oriented along the Earth's magnetic field, were pulse code modulated (PCM) and transmitted via VHF radio to recording devices at the Postgraduate school. The recording of a two hour long data collection period was transferred to digital data tape for use by the school's IBM3033 general purpose mainframe computer.

In the first test of the digital filter program, the output of the Schonstedt sensor, which represents fluctuations of the Earth's total field, was used as the input to the computer program. A comparison of the output of the computer program, with this approximation to the total field fluctuations as input, to the output of the AN/ASQ-81 should provide an indication of the proper functioning of the computer filter program. The results of

the test are shown in Figures 5.19 through 5.21 on the pages following. Figure 5.19, the Schonstedt sensor output, shows several instances of PCM dropouts, that is, occasions where the pulse code modulation signal was not correctly read by the computer for some reason. At such occurrences, the data point value used by the computer is a random number and does not reflect the true value of the data. The problem with these PCM dropouts is that the computer does not recognize them as invalid data points and will use them in computations. This can (and does) cause problems in the computation of Fourier transforms, spectral characteristics, etc. Additionally, this will also impact the proper functioning of the digital filter program which is the subject of this thesis. PCM dropouts are visible at times 6, 8, 142, and 220 through 226 seconds on the plot of the Schonstedt sensor output. An examination of Figure 5.20, the filter program output, reveals the programs attempt to "follow" these PCM dropouts. It should be recalled that previous simulations indicated the filter's tendency to "follow" sudden changes in the input signal, with a relaxation time required for the filter to steady out. This effect is apparent in the output of the filter program at times corresponding to those of the PCM dropouts in the Schonstedt sensor's time series plot. It can be seen that this overshoot tendency resulted in an output significantly different from the actual AN/ASQ-81 output at these times.

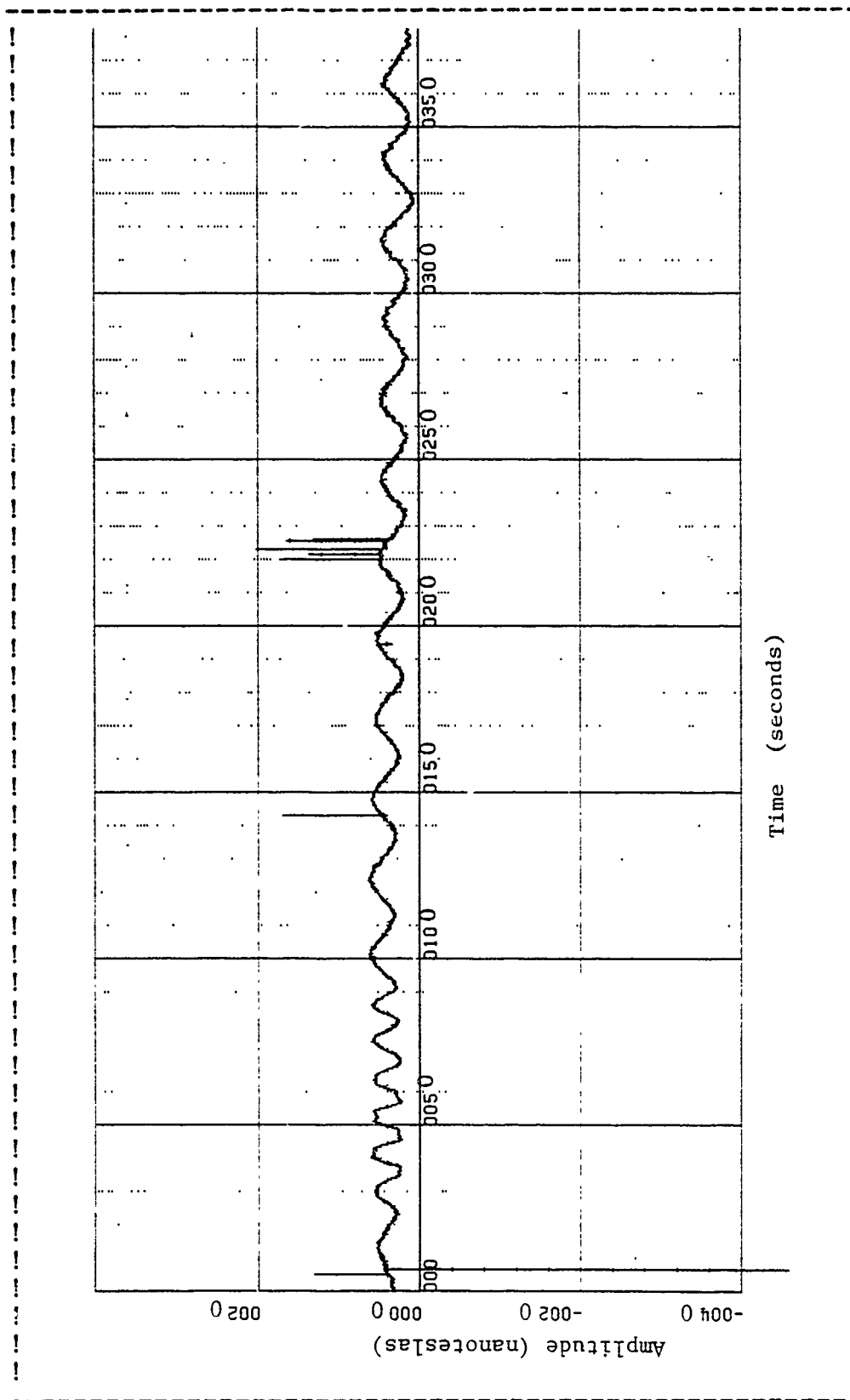


Figure 5.19: Schonstedt Coil Time Series Output

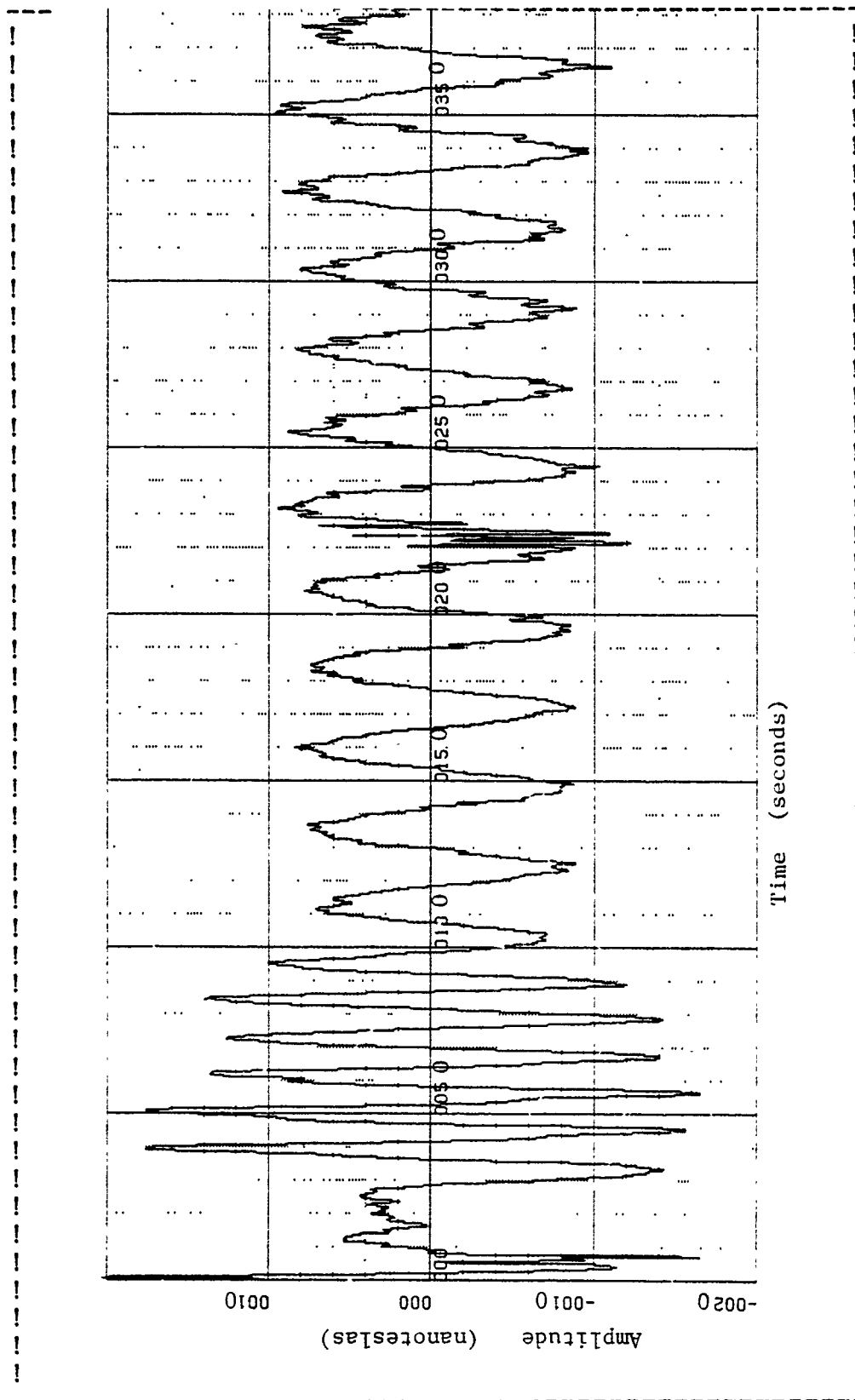


Figure 5.20: Program Time Series Output With Schonstedt Coil as Input

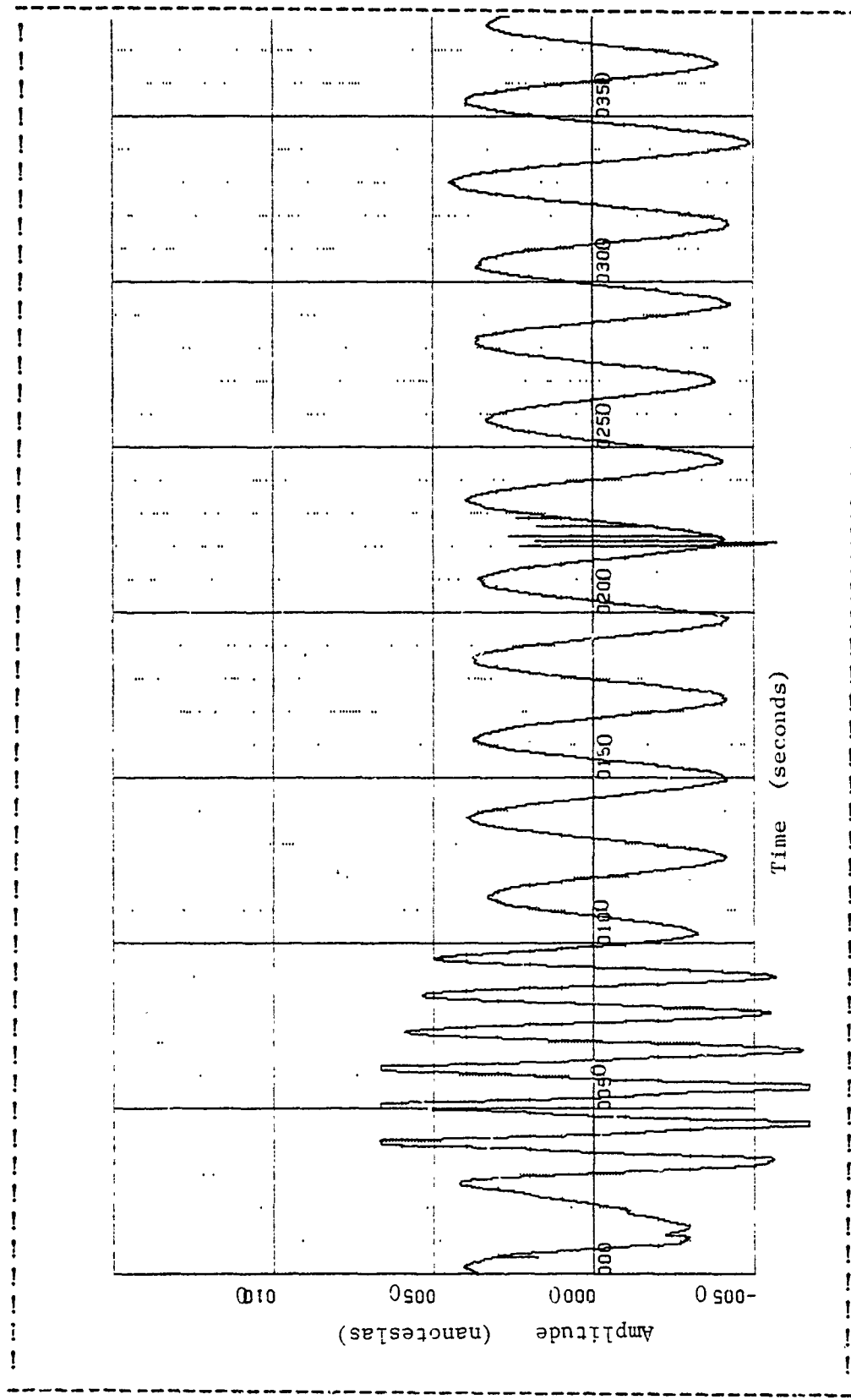


Figure 5.21: ASQ-81 Time Series Output

If the PCM dropout induced differences are neglected, it can be seen that the shape of the output of the filter program is remarkably similar to that of the AN/ASQ-81 magnetometer, although noisier. Note that the output of the AN/ASQ-81 magnetometer exceeded the maximum voltage amplitude which the pre-amplifiers of the data collection system were able to handle and resulted in a truncated signal from time 40 to time 60 seconds. It can still be seen, however, that the filter program output is very similar to the time signal which would have been displayed without this truncation.

It should be noted that the amplitudes of the time series signals of the program output and the AN/ASQ-81 magnetometer differ considerably. In the case of the program output, the peak amplitudes are on the order of 1.4 nanoteslas along the vertical scale, while the peak amplitudes of the output of the AN/ASQ-81 magnetometer are on the order of 0.7 nanoteslas along the vertical scale. This is because the input signal to the filter program is an approximation to the total field difference time series signal, and some amplitude difference could reasonably be expected. The intent of this initial test was to investigate the output time series shape, and an exact correlation was not expected. It is worth noting that the digital filter program will perform its function on any time series signal, regardless of units. This means that a signal may be

operated upon either before or after conversion from whatever units it was originally measured to magnetic field strength units.

Therefore it appears that the digital filter program is functioning properly. When a close approximation to the fluctuations of the total field time series signal is used as the input to the computer program, the output of the program is similar to the time series output of an AN/ASQ-81 magnetometer.

The final stage in the testing process was a conversion of the time series output voltage signal of the coil antenna sensor, which was aligned along the Earth's magnetic field, into a total field fluctuation time series representation for the same time period as before, and then to use this as the input to the digital filter program. A comparison of the resultant time series output of the program with the actual AN/ASQ-81 magnetometer output would validate the proper functioning of the program.

Conversion of the time series antenna sensor output voltage signal into total field fluctuations in nanoteslas was accomplished through the use of a computer program designed by Capt. Kurt Stevens, USAF, a student at the Naval Postgraduate School, as his Master's thesis [Ref 10]. The output voltage time series is stored in an array, then a Fourier transform is performed on the stored data, resulting in the Fourier spectrum of the data. This spectrum is

corrected for the characteristics of the coil antenna sensor to obtain the Fourier spectrum of the total field data. A reverse Fourier transform gives the time series signal for total magnetic field in nanoteslas.

This time series signal was used as the input to the digital filter program and compared with the output of the AN/ASQ-81 magnetometer. Figures 5.22 through 5.24 show the raw coil antenna data, the total field time series data, and the program output time series for a 6 minute period of the test. Figure 5.22 shows the raw coil antenna data series. The number of PCM dropouts should be noted, as these will influence the performance of the filter program. Figure 5.23 shows the computed total field time series. Note that the PCM dropouts evident on the raw time series plot are evident on the computed total field time series plot also, and thus inputted to the filter program as valid data points. Additionally, there are two "jumps" in the plot of total field fluctuation (Figure 5.23) which are also inputted to the filter program as valid data points. These "jumps" are located at 128 and 256 seconds and are caused by the method of processing blocks of data for the conversion to total field fluctuation. A block of 128 seconds of data is processed at a time, and the results of each block are stored in an array. This results in a slight amplitude difference between the last data point of one block and the

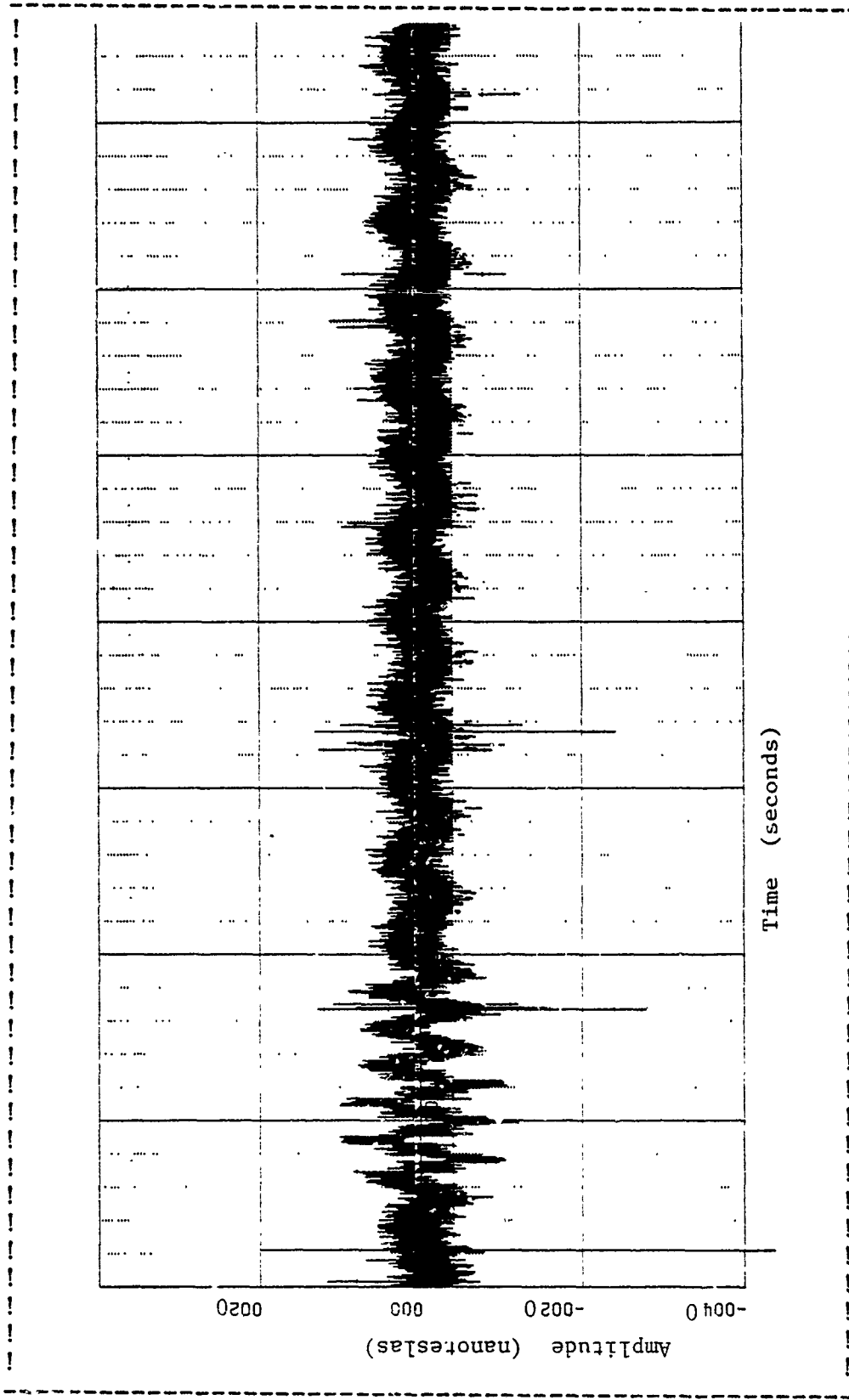


Figure 5.22: Raw Coil Antenna Time Series Output

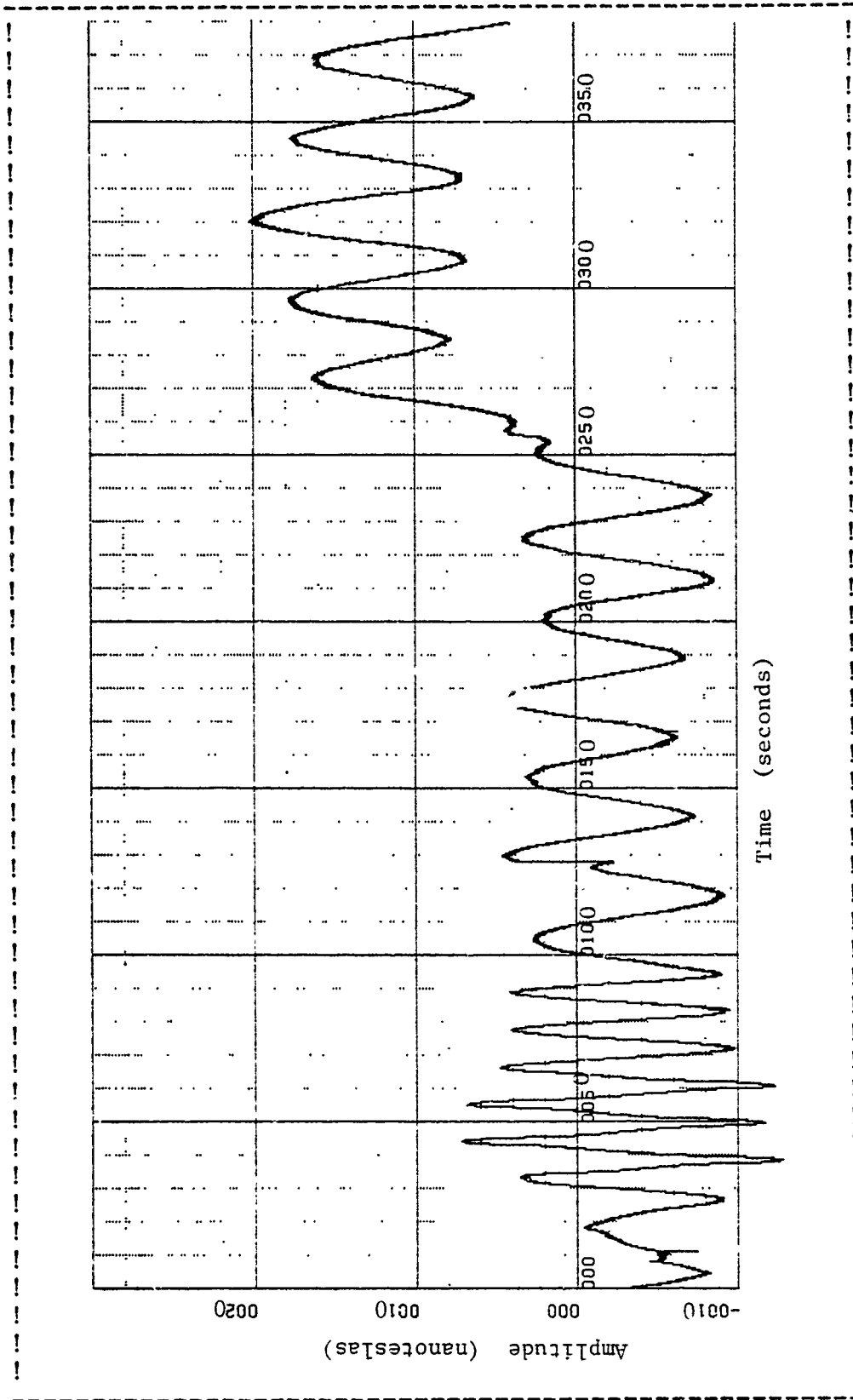


Figure 5.23: Coil Antenna Difference Field Time Series Output

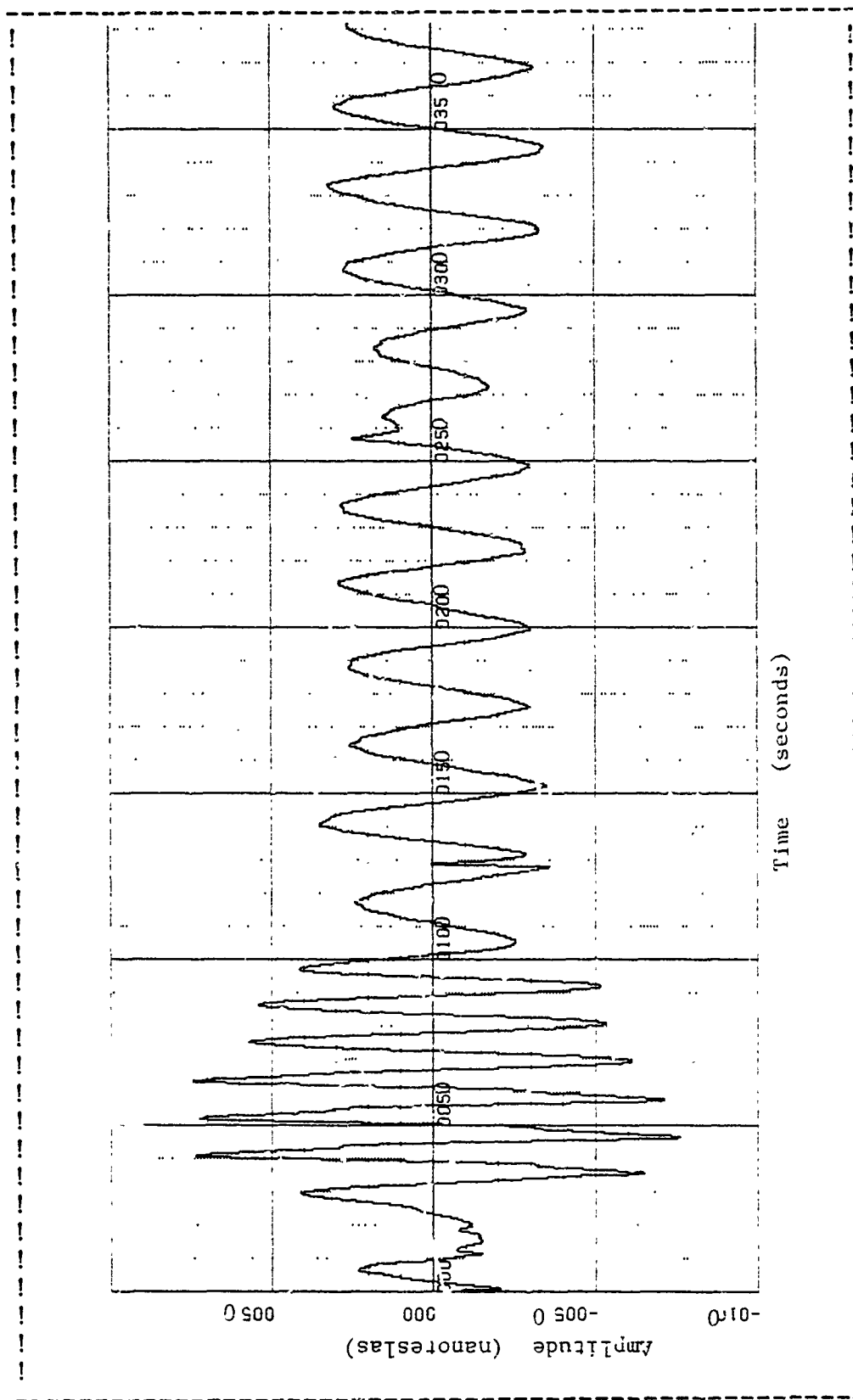


Figure 5.24: Program Time Series Output With Coil Antenna Difference Field Time Series as Input.

first data point of the next block of data. This slight difference is manifested as a signal jump.

A comparison of Figures 5.24 (program output) and 5.21 (AN/ASQ-81 output) show that the filter program gives a time series output very similar to that of the actual magnetometer. The first 20 seconds of the program output is somewhat dissimilar to that of the AN/ASQ-81, due either to the initial "start up" delay of the filter program or to distortion of the total field fluctuation time series. There is a PCM dropout at time 11 seconds which contributed to the distortion.

Following this, however, it can be seen that the program output is very similar to that of the magnetometer, except at 128 and 256 seconds, which show the effects of the false signal jumps caused by the total field fluctuation conversion. There is also a noticeable four to five second time delay between the AN/ASQ-81 output and that of the filter program. As this delay is not evident in a comparison of the AN/ASQ-81 output and that of the filter program with the Schonstedt sensor as the input, it can be inferred that this time delay is caused either by the program which converts the raw coil data to total field fluctuation data, or by a phase (and hence time) change of the voltage signal due to the coil sensor itself. A comparison of the raw coil data in Figure 5.22 to the converted coil data in Figure 5.23 indicates no time shift,

and hence the deduction can be made that there is a time delay inherent within the coil sensor itself.

Other than the differences of the four to five second time delay and the distortions caused by the false signal jumps, the program output is extremely similar to the output of the AN/ASQ-81 magnetometer.

VI. CONCLUSIONS

The intent of this thesis was to design and test a digital filter computer program which would, when given a time series input of fluctuations in the total magnetic field, deliver an output time series representation of the output of an AN/ASQ-81 magnetometer. This purpose has been realized.

The computer program contained in Appendix I has been proven to output a time series signal which is very similar to that of the magnetometer. The major limitations of the output signal are a finite time delay of about five seconds between the AN/ASQ-81 magnetometer signal and the output signal of the program, a sensitivity of the program to false data points such as those caused by PCM dropouts and false signal jumps caused by processing large data blocks, and the inherent limitations of the program caused by its dependence on the use of digital data tapes and the IBM 3033 mainframe computer.

The five second time delay is not considered to be an important limitation to the program, as it was intended as a research tool for programs currently in progress at the Naval Postgraduate School. Instances where this time delay might become important would be in areas of simultaneous comparison of the program output signal with an actual magnetometer, in target location algorithms using time

delays, or in correlation studies between different sensors. In correlation studies using coil sensors, the effects of the time delay would cancel out, as all coil outputs would be similarly delayed. In target location algorithms, the target location errors due to the time delay could be adjusted for simply while in computer simulation, and flight testing could not reasonably be accomplished without the use of an actual magnetometer as the sensor. Lastly, in a comparison of the program output with an actual sensor, the time delay can, again, be compensated for. In short, these limitations are not considered excessive, especially as the apparent cause for the delay is not the filter program.

In the primarily intended purpose of the filter program, magnetic noise studies, the time delay is not considered to be a problem.

The problem of false data points caused by PCM dropouts and signal jumps due to conversion to total field fluctuations is more serious. False data points cause inaccuracies in the output time series and could adversely affect later projects. Unfortunately the PCM dropout problem is one which is endemic to the data collection system presently being used at the postgraduate school, and not to the filter program itself. It is imperative that users of this program are aware of the PCM dropout problem and of the effects it may entail upon their specific

research. A large number of PCM dropouts in a time series could render that series unusable. Similarly the case of the false data jumps caused by conversion to total field fluctuations is not within the filter program. Further investigation of this problem is necessary in order to eliminate it.

The last problem, that of reliance upon the digital data tape/IBM 3033 computer system, is, like the PCM problem, one which is not endemic to the filter program but rather to the data collection system being used. A change of data collection system may, at some future time, remove the reliance upon the PCM/digital tape/IBM 3033 data system (and hence too the data block conversion problem which results in false data jumps), but this is unlikely at this time. Users should be aware of this dependence and of possible effects upon specific research projects.

APPENDIX A

AN/ASQ-81 FILTER TRANSFER FUNCTIONS

Fixed High Pass Transfer Function:

$$H(S) = \frac{80 S^2}{80 S^2 + 20 S + 1}$$

Selectable High Pass Transfer Functions:

A. 0.04 HZ $H(S) =$

$$\frac{40.82834 S^2}{40.82834 S^2 + 12.52096 S + 1} \times \frac{45.28317 S^2}{45.28317 S^2 + 11.00999 S + 1}$$

$$\times \frac{57.576688 S^2}{57.576688 S^2 + 7.41498 S + 1}$$

B. 0.06 HZ $H(S) =$

$$\frac{18.14591 S^2}{18.14591 S^2 + 8.34727 S + 1} \times \frac{20.12587 S^2}{20.12587 S^2 + 7.33999 S + 1}$$

$$\times \frac{25.58964 S^2}{25.58964 S^2 + 4.94332 S + 1}$$

C. 0.08 HZ $H(S) =$

$$\frac{10.20708 S^2}{10.20708 S^2 + 6.26045 S + 1} \times \frac{11.32080 S^2}{11.32080 S^2 + 5.50500 S + 1}$$

$$\times \frac{14.39417 S^2}{14.39417 S^2 + 3.70749 S + 1}$$

$$\begin{aligned}
 \text{D. } & \underline{0.10 \text{ HZ}} \quad H(S) = \\
 & \frac{6.53253 S^2}{6.53253 S^2 + 5.00836 S + 1} \times \frac{7.24531 S^2}{7.24531 S^2 + 4.40400 S + 1} \\
 & \times \frac{9.21227 S^2}{9.21227 S^2 + 2.96599 S + 1}
 \end{aligned}$$

Selectable Low Pass Transfer Functions

$$\begin{aligned}
 \text{A. } & \underline{0.2 \text{ HZ}} \quad H(S) = \\
 & \frac{1}{0.3143 S^2 + 1.0741 S + 1} \times \frac{1}{0.2501 S^2 + 0.6209 S + 1}
 \end{aligned}$$

$$\begin{aligned}
 \text{B. } & \underline{0.4 \text{ HZ}} \quad H(S) = \\
 & \frac{1}{0.07858 S^2 + 0.53706 S + 1} \times \frac{1}{0.06252 S^2 + 0.31044 S + 1}
 \end{aligned}$$

$$\begin{aligned}
 \text{C. } & \underline{0.6 \text{ HZ}} \quad H(S) = \\
 & \frac{1}{0.03492 S^2 + 0.35804 S + 1} \times \frac{1}{0.02779 S^2 + 0.20696 S + 1}
 \end{aligned}$$

APPENDIX B

AN/ASQ-81 Z TRANSFORM FILTER TRANSFER FUNCTIONS FOR DIRECT FORM I REALIZATION

For fixed high pass filter:

$$H(Z) = \frac{BFHP0 + BFHP1*Z^{-1} + BFHP2*Z^{-2}}{1 - AFHP1*Z^{-1} - AFHP2*Z^{-2}}$$

where BFHP0, BFHP1, BFHP2, AFHP1, AFHP2 are constants tabulated in Appendix D.

For selectable high pass filter:

$$H(Z) = \frac{BSHP0 + BSHP1*Z^{-1} + BSHP2*Z^{-2} + BSHP3*Z^{-3} + BSHP4*Z^{-4} + BSHP5*Z^{-5} + BSHP6*Z^{-6}}{1 - ASHP1*Z^{-1} - ASHP2*Z^{-2} - ASHP3*Z^{-3} - ASHP4*Z^{-4} - ASHP5*Z^{-5} - ASHP6*Z^{-6}}$$

where, for low frequency cutoff of 0.04 HZ:

BSHP0 =	0.99471378		
BSHP1 =	-5.9682827	ASHP1 =	5.9894021
BSHP2 =	14.920707	ASHP2 =	-14.947051
BSHP3 =	-19.894276	ASHP3 =	19.894225
BSHP4 =	14.920707	ASHP4 =	-14.894327
BSHP5 =	-5.9682817	ASHP5 =	5.9472141
BSHP6 =	0.99471372	ASHP6 =	-0.98945296

For low frequency cutoff of 0.06 HZ:

BSHP0 =	0.9920813		
BSHP1 =	-5.9524928	ASHP1 =	5.9841070
BSHP2 =	14.881232	ASHP2 =	-14.920650
BSHP3 =	-19.841643	ASHP3 =	19.841528
BSHP4 =	14.881232	ASHP4 =	-14.841757
BSHP5 =	-5.9524927	ASHP5 =	5.9209919
BSHP6 =	0.99208212	ASHP6 =	-0.98422128

For low frequency cutoff of 0.08 HZ:

BSHP0 =	0.98945806		
BSHP1 =	-5.9367483	ASHP1 =	5.9788144
BSHP2 =	14.841871	ASHP2 =	-14.894276
BSHP3 =	-19.789161	ASHP3 =	19.788959
BSHP4 =	14.841871	ASHP4 =	-14.789365
BSHP5 =	-5.9367476	ASHP5 =	5.8948841
BSHP6 =	0.98945802	ASHP6 =	-0.97901720

For low frequency cutoff of 0.1 HZ:

BSHP0 =	0.98684156		
BSHP1 =	-5.9210493	ASHP1 =	5.9735244
BSHP2 =	14.802623	ASHP2 =	-14.867941
BSHP3 =	-19.736831	ASHP3 =	19.736516
BSHP4 =	14.802623	ASHP4 =	-14.737149
BSHP5 =	-5.9210491	ASHP5 =	5.8688889
BSHP6 =	0.9868415	ASHP6 =	-0.97384065

For selectable low pass filter:

$$H(Z) = \frac{BSLP_0 + BSLP_1*Z^{-1} + BSLP_2*Z^{-2} + BSLP_3*Z^{-3} + BSLP_4*Z^{-4}}{1 - ASLP_1*Z^{-1} - ASLP_2*Z^{-2} - ASLP_3*Z^{-3} - ASLP_4*Z^{-4}}$$

where BSLP₀, BSLP₁, BSLP₂, BSLP₃, BSLP₄, ASLP₁, ASLP₂, ASLP₃, ASLP₄ are constants tabulated in Appendix D.

APPENDIX C

AN/ASQ-81 Z TRANSFORM FILTER TRANSFER FUNCTIONS DIRECT FORM II REALIZATION

For fixed high pass filter:

$$H(Z) = \frac{BFHP0 + BFHP1*Z^{-1} + BFHP2*Z^{-2}}{1 - AFHP1*Z^{-1} - AFHP2*Z^{-2}}$$

where BFHP0, BFHP1, BFHP2, AFHP1, AFHP2 are constants tabulated in Appendix D.

For selectable high pass filter:

$$H(Z) = ASHP1 \times \frac{1 - 2*Z^{-1} + Z^{-2}}{1 - ASHP3*Z^{-1} - ASHP2*Z^{-2}} \times \frac{1 - 2*Z^{-1} + Z^{-2}}{1 - ASHP4*Z^{-1} - ASHP5*Z^{-2}} \times \frac{1 - 2*Z^{-1} + Z^{-2}}{1 - ASHP6*Z^{-1} - ASHP7*Z^{-2}}$$

where ASHP1, ASHP2, ASHP3, ASHP4, ASHP5, ASHP6, ASHP7 are constants and tabulated in Appendix D.

For selectable low pass filter:

$$H(Z) = \frac{BSLP0 + BSLP1*Z^{-1} + BSLP2*Z^{-2} + BSLP3*Z^{-3} + BSLP4*Z^{-4}}{1 - ASLP1*Z^{-1} - ASLP2*Z^{-2} - ASLP3*Z^{-3} - ASLP4*Z^{-4}}$$

where BSLP0, BSLP1, BSLP2, BSLP3, BSLP4, ASLP1, ASLP2, ASLP3, ASLP4 are constants tabulated in Appendix D.

APPENDIX D

Z TRANSFORM REALIZATION DIFFERENCE EQUATIONS

With reference to Figures 3.2 and 4.2, the following difference equations are used to model the AN/ASQ-81 magnetometer filter transfer functions. The input to the fixed high pass filter is called SIG(I), where I is the current data sample. The output of the fixed high pass filter, which is the input to the selectable high pass filter, is YO(I), and the output of the selectable high pass filter, the input to the selectable low pass filter, is called YPO(I). The output of the filter is called ASQ(I). (I-1) denotes a time delay of one sample, and so forth, and the symbol * denotes multiplication.

For the fixed high pass filter:

$$YO(I) = BFHPO * SIG(I) + BFHP1 * SIG(I-1) + BFHP2 * SIG(I-2) + AFHP1 * YO(I-1) + AFHP2 * YO(I-2)$$

where:

$$BFHPO = 0.9980499222938581$$

$$BFHP1 = -1.9960998445877161 \quad AFHP1 = 1.9960983216843922$$

$$BFHP2 = 0.998049922238581 \quad AFHP2 = -0.9961013674910398$$

For the selectable high pass filters:

$$XI(I) = ASHP1 * YO(I) + ASHP2 * XI(I-2) + ASHP3 * XI(I-3)$$

$$XII(I) = XI(I) + XI(I-2) - 2 * XI(I-1)$$

$$XIII(I) = XII(I) + ASHP4 * XIII(I-1) + ASHP5 * XIII(I-2)$$

$$XIV(I) = XIII(I) - 2 * XIII(I-1) + XIII(I-2)$$

$$XV(I) = XIV(I) + ASHP6 * XV(I-1) + ASHP7 * XV(I-2)$$

$$YPO(I) = XV(I) - 2 * XV(I-1) + XV(I-2)$$

For the low frequency cutoff at 0.04 HZ:

$$ASHP1 = 0.994713789347288 \quad ASHP2 = -0.9952196910157882$$

$$ASHP3 = 1.9952137256322473 \quad ASHP4 = 1.9962028201103847$$

$$ASHP5 = -0.9962082013015601 \quad ASHP6 = 1.9979855321466768$$

$$ASHP7 = -0.9979897681491607$$

For the low frequency cutoff at 0.06 HZ:

$$ASHP1 = 0.9920821277199393 \quad ASHP2 = -0.9928381306174365$$

$$ASHP3 = 1.9928247245317958 \quad ASHP4 = 1.9943056083414792$$

$$ASHP5 = -0.9943177045263504 \quad ASHP6 = 1.9969766455640039$$

$$ASHP7 = -0.9969861717656565$$

For the low frequency cutoff at 0.08 HZ:

$$ASHP1 = 0.9894580558875787 \quad ASHP2 = -0.9904622611337722$$

$$ASHP3 = 1.9904384565912725 \quad ASHP4 = 1.9924092959984783$$

$$ASHP5 = -0.9924307799269113 \quad ASHP6 = 1.9959666590811389$$

$$ASHP7 = -0.9959835860201267$$

For the low frequency cutoff at 0.10 HZ:

$$ASHP1 = 0.9869415560096681 \quad ASHP2 = -0.9880929619779491$$

$$ASHP3 = 1.9880549117849344 \quad ASHP4 = 1.9905139074397893$$

$$ASHP5 = -0.9905474442556225 \quad ASHP6 = 1.9949555824611562$$

$$ASHP7 = -0.9949820174650785$$

For the selectable low pass filters:

$$ASQ(I) = ASLP1 * ASQ(I-1) + ASLP2 * ASQ(I-2) + ASLP3 * ASQ(I-3)$$

$$+ ASLP4 * ASQ(I-4) + BSLP0 * YPO(I) + BSLP1 * YPO(I-1)$$

$$+ BSLP2 * YPO(I-2) + BSLP3 * YPO(I-3) + BSLP4 * YPO(I-4)$$

For the high frequency cutoff at 0.2 HZ:

BSLP0 = 0.0000000452616229
BSLP1 = 0.0000001810464917 ASLP1 = 3.9082436339591027
BSLP2 = 0.0000002715697375 ASLP2 = -5.7285022156249328
BSLP3 = 0.0000001810464917 ASLP3 = 3.7321935213310065
BSLP4 = 0.0000000452616229 ASLP4 = -0.9119356638511430

For the high frequency cutoff at 0.4 HZ:

BSLP0 = 0.0000006918001209
BSLP1 = 0.0000027672004837 ASLP1 = 3.8173771378993420
BSLP2 = 0.0000041508007256 ASLP2 = -5.4670046844062743
BSLP3 = 0.0000027672004837 ASLP3 = 3.4812554457127576
BSLP4 = 0.0000006918001209 ASLP4 = -0.8316389680077603

For the high frequency cutoff at 0.6 HZ:

BSLP0 = 0.0000033463317975
BSLP1 = 0.0000133853271900 ASLP1 = 3.7274299052305002
BSLP2 = 0.0000200779907850 ASLP2 = -5.2152772583906819
BSLP3 = 0.0000133853271900 ASLP3 = 3.2462216641520829
BSLP4 = 0.0000033463317975 ASLP4 = -0.7584278523006615

APPENDIX E

DIGITAL SOFTWARE FOR SIMULATION - DIRECT FORM (SINUSOIDS AS INPUT)

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 APP002480

```

//HUEYE JOB (1457,1106),',',CLASS=B
// EXEC FRTXCLGP
//FORT.SYSIN DD *
C C C C C C C C C C
      MGEN3
THIS PROGRAM IS DESIGNED TO TEST THE ACTION OF THE PRELIMINARY
DIGITAL FILTER PROGRAM FOR THE ASQ-81 BY INTRODUCING A SINUSOID
AS THE INPUT SIGNAL TO THE FILTER
C C C C C C C C C C
      SET UP ARRAYS. SIG() IS THE SIGNAL, ASQ() IS THE PROGRAM
      OUTPUT, TRU() IS THE SIGNAL WITHIN THE FREQUENCY RANGE OF THE
      PROGRAM
      DIMENSION SIG(3000),ASQ(3000),TRU(3000),TIME(3000)
      DIMENSION YO(3000),YPO(3000)
      REAL*8 DSEEDP1,AFHP2,BFHP0,BFHP1,BFHP2,A,B,C,D,E,F
      REAL*8 AI,BI,CI,DI,EI,FI,GI,HI,IJ,KI,LI
      REAL*8 AA,BB,CC,DD,EE,FF,AAI,BBI,CCI,DDI,EEI,FFI,GGI,HHI,III
      REAL*8 JJI,KKI,LLI
      REAL*8 ASHP41,ASHP42,ASHP43,ASHP44,ASHP45,ASHP46
      REAL*8 BSHP41,BSHP42,BSHP43,BSHP44,BSHP45,BSHP46
      REAL*8 ASLP61,ASLP62,ASLP63,ASLP64
      REAL*8 BSLP61,BSLP62,BSLP63,BSLP64
      REAL*8 TITL A(12),HUEYE
      $8#
      REAL*8 TITL B(12),HUEYE      ',',OUTPUT S,',',IGNAL      ',',
      $8#
      REAL*8 TITL C(12),HUEYE      ',',YPRI SIG,',',NAL      ',',
      $8#
      REAL LABEL/,
      DATA PI/3.141592954/
      DOUBLE PRECISION DSEED
      DEFINE AND COMPUTE ALL COEFFICIENTS
      TEN SAMPLES PER SECOND
      T=1./10.
      COEFFICIENTS FOR FIXED HIGH PASS FILTER
      AFHP1=-((T**2/160.-2.)/(1.+T/8.+T**2/320.))
      AFHP2=-((1.-T/8.+T**2/320.)/(1.+T/8.+T**2/320.))
      BFHP0=-((1.)/(1.+T/8.+T**2/320.))
      BFHP1=-((2.)/(1.+T/8.+T**2/320.))
      BFHP2=-((1.)/(1.+T/8.+T**2/320.))
      COEFFICIENTS FOR SELECTABLE HIGH PASS FILTER
      IN THIS CASE, F(LOWER)=0.04 HZ
  
```

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APP00920
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APP00940
APP00950
APP00960

A=12.52096/40.82834
B=11.00999/45.28317
C=1.7/45.28317
D=1.5/57.57668
E=1.1/A*1/2.+B*(1**2)/4.
F1=1.2.-A*1/2.+B*(1**2)/4.
G1=1.-C*1/2.+D*(1**2)/2.
H1=1.-C*1/2.+D*(1**2)/4.
I1=1.-E*1/2.+F*(1**2)/2.
I1=1.-E*1/2.+F*(1**2)/4.

CODE IS "ASHP41" MEANS "A1 COEFFICIENT FOR THE SELECTABLE HIGH
PASS FILTER WITH LOWER LIMIT 0.04 HZ"

ASHP41=-(G1*(A1*E1+B1*D1))+(H1*A1*D1)/(G1*A1*D1)
ASHP42=-(G1*(A1*F1+B1*E1+C1*D1))+I1*(A1*A1*D1)/
\$(G1*A1*D1)
ASHP43=-(G1*(B1*F1+C1*E1))+H1*(A1*F1+B1*E1+C1*D1)+I1*(A1*E1+B1*D1)
\$/((G1*A1*D1)
ASHP44=-(G1*CI*F1+HI*(B1*F1+C1*E1))+I1*(A1*F1+B1*E1+C1*D1))/(G1*
A1*D1)
ASHP45=-(H1*CI*F1+I1*(B1*F1+C1*E1))/(G1*A1*D1)
ASHP46=-(I1*CI*F1)/(G1*A1*D1)
BSHP40=1./((G1*A1*D1)
BSHP41=-6./((G1*A1*D1)
BSHP42=15./((G1*A1*D1)
BSHP43=-20./((G1*A1*D1)
BSHP44=15./((G1*A1*D1)
BSHP45=-6./((G1*A1*D1)
BSHP46=1./((G1*A1*D1)

COEFFICIENTS FOR SELECTABLE LOW PASS FILTER WITH UPPER FREQ.
OF 0.6 HZ

AA=1./0.03452
BB=0.35804/0.03492
CC=1./0.03492
DD=1./0.02779
EE=0.20696/0.02779
FF=1./0.02779
AA1=A*A*1/4.
BB1=B*B*1/4.

C

CCCC

CCCC

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 APP01400
 APP01410
 APP01420
 APP01430
 APP01440

```

CC1=AA1 (T**2)/4.
DEE1=DD1
FFF1=(1.2.+BB*T/2.+CC*(T**2)/4.)
GG1=(1.2.-BB*T/2.+CC*(T**2)/4.)
HH1=(1.2.+EEF*(T**2)/2.)
JJ1=(1.2.-EE*T/2.+FF*HI*(T**2)/4.)
KK1=(1.2.-EE*GG1+HH1+II*JJ1)/(GG1*JJ1)
LL1=(1.2.-EE*GG1+HH1+II*JJ1)/(GG1*JJ1)
ASLP62=(GG1*LL1+II*KK1)/(GG1*JJ1)
ASLP63=(HH1*LL1+II*GG1*JJ1)
ASLP64=(II*LL1)/(GG1*JJ1)
BSLP60=(AA1*DEE1+BB1*DD1)/(GG1*JJ1)
BSLP61=(AA1*FFF1+BB1*DD1)/(GG1*JJ1)
BSLP62=(AA1*FFF1+BB1*DD1)/(GG1*JJ1)
BSLP63=(BB1*FFF1+CC1*GG1*JJ1)
BSLP64=(CC1*FFF1)/(GG1*JJ1)

```

FINISHED COMPUTING COEFFICIENTS, INITIALIZE STORAGE REGISTERS

```

DO 200 J=1,3000
TRU(J)=0.
YPO(J)=0.
ASQ(J)=0.
SIG(J)=0.
200 CONTINUE

```

STORAGE REGISTERS SET TO 0;
 SET UP EQUATIONS FOR FILTER

```

DO 100 I=1,3000
I1=I-1
I2=I-2
I3=I-3
I4=I-4
I5=I-5
I6=I-6
IF(I1) I1=I
IF(I2) I2=I
IF(I3) I3=I
IF(I4) I4=I
IF(I5) I5=I
IF(I6) I6=I
AND I=GUBFS(DSEED)

```

CC

CC

C

```

C C C THIS NOISE STATEMENT ADDS NOISE OF +/- 1 TO THE SIGNAL
      IN ADDITION TO A SINUSOID OF F=10 HZ
      ANOISE=2.*(ANOI-0.5)
      SIG(I)=TRU(I)+SIN(2.*PI*FLOAI(I)+PHI2)+ANOISE
      TIME(I)=FLOAI(I)/600.
      YO(I)=BFHPO*SIG(I)+BFHP1*SIG(I1)+BFHP2*SIG(I2)+AFHP1*YO(I1)
      $+AFHP2*YO(I2)

C C C C C THE NEXT COMMENTED STEP WAS USED IN TROUBLESHOOTING BY INPUTTING
      THE SIGNAL AT VARIOUS STAGES OF THE FILTER
      YO(I)=SIG(I)
      YP1=ASHP41*YO(I1)+ASHP42*YO(I2)+ASHP43*YO(I3)+ASHP44*YO(I4)
      YP2=ASHP45*YO(I5)+ASHP46*YO(I6)+BSHP40*YO(I1)+BSHP41*YO(I1)
      YP3=BSHP44*YO(I4)+BSHP45*YO(I5)+BSHP46*YO(I6)+BSHP42*YO(I2)
      $+BSHP43*YO(I3)
      YPO(I)=YP1+YP2+YP3

C C C C C THE NEXT COMMENTED STEP WAS USED FOR TROUBLESHOOTING BY INPUTTING
      THE SIGNAL AT VARIOUS STAGES OF THE FILTER
      YPO(I)=SIG(I)
      GP1=ASLPP61*ASQ(I1)+ASLPP62*ASQ(I2)+ASLPP63*ASQ(I3)+ASLPP64*ASQ(I4)
      GP2=BSLPP60*YPO(I1)+BSLPP61*YPO(I2)+BSLPP62*YPO(I3)
      $+BSLPP63*YPO(I4)
      ASQ(I)=GP1+GP2

C C C C C 100 CONTINUE

C C C C C COMPUTATIONS FINISHED AND ANSWERS STORED IN ARRAYS, PLOT OUTPUT
      CALL SUBROUTINE DRAW FOR FIRST GRAPH, A TIME SERIES
      REPRESENTATION OF THE INPUT SIGNAL TO THE PROGRAM
      ONLY ONE PLOT ON THIS GRAPH, X AXIS WILL BE MAGNITUDE AND
      LABELLED "MAGNITUDE" ON A LINEAR SCALE
      Y AXIS WILL BE TIME AND LABELLED "MINUTES" ON A LINEAR SCALE
      CALL DRAW(3000,TIME,YD,0,0,LABEL,JITLA,0,0,0,0,5,4,1,LAST)
      END OF FIRST PLOT, PLOT SECOND PLOT
      SECOND PLOT WILL BE A TIME SERIES REPRESENTATION OF THE ASQ81
      OUTPUT AS COMPUTED
      PLOT WILL HAVE X AXIS LABELLED "MAGNITUDE", Y AXIS LABELLED
      "MINUTES", BOTH ON A LINEAR SCALE

```

APP01930
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APP02040
APP02050

```
C CALL DRAW(3000, TIME, ASQ, 0, 0, LABEL, TITLB, 0, 0, 0, 0, 0, 0, 5, 4, 1, LAST)
C THIRD PLOT WILL BE A PLOT OF THE 'TRUE' SIGNAL VERSUS TIME
C WITH SIGNAL ON THE X AXIS AND TIME ON THE Y AXIS
C CALL DRAW(3000, TIME, YPO, 0, 0, LABEL, TITLC, 0, 0, 0, 0, 0, 5, 4, 1, LAST)
C FINISHED PLOTTING
C STOP
C END
C /*
```

APPENDIX F
DIGITAL SOFTWARE FOR SIMULATION - CASCADE FORM (SINUSOIDS AS INPUT)

```

//HUETE JOB (1457,1106), , , CLASS=B
//EXEC FRTXCLGP
//FORT.SYSIN DD *
CCCCCCCCCCCC
    MGN5 FORTRAN
THIS PROGRAM IS DESIGNED TO TEST THE ACTION OF THE PRELIMINARY
DIGITAL FILTER PROGRAM FOR THE ASQ-81 BY INTRODUCING SIMULATED
MAGNETIC SIGNALS INTO THE SYSTEM THROUGH THE USE OF SINUSOIDS
OF VARYING FREQUENCY, BOTH WITHIN AND OUTSIDE THE FREQUENCY
RANGE OF THE FILTER, WITH RANDOM NOISE ADDED
SET UP ARRAYS. SIG() IS THE SIGNAL, ASQ() IS THE PROGRAM
OUTPUT, TRU() IS THE SIGNAL WITHIN THE FREQUENCY RANGE OF THE
PROGRAM
DIMENSION SIG(3000), ASQ(3000), TRU(3000), TIME(3000)
DIMENSION YQ(3000), YPO(3000)
DIMENSION XI(3000), XII(3000), XIII(3000), XIV(3000), XV(3000)
REAL*8 DSEEC
REAL*8 T, AFHP1, AFHP2, BFHP0, BFHP1, BFHP2, A, B, C, D, E, F
REAL*8 AI, BI, CI, DI, EI, FI, GI, HI, I, J, K, L, LI
REAL*8 AA, BB, CC, DD, EE, FF, AA1, BB1, CC1, DD1, EE1, FF1, GG1, HH1, I11
REAL*8 JJ1, KK1, LLL
REAL*8 ASHP41, ASHP42, ASHP43, ASHP44, ASHP45, ASHP46, ASHP47
REAL*8 ASLP61, ASLP62, ASLP63, ASLP64
REAL*8 BSLP60, BSLP61, BSLP62, BSLP63, BSLP64
REAL*8 TITLA(12), HUETE
$8#
REAL*8 TITLB(12), HUETE
$8#
REAL*8 TITLC(12), HUETE
$8#
REAL*8 TITLD(12), HUETE
$8#
REAL*8 TITLE(12), HUETE
$8#
REAL LABEL, /
DATA PI/3.141592954/
DOUBLE PRECISION DSEED
DEFINE AND COMPUTE ALL COEFFICIENTS
TEN SAMPLES PER SECOND
T=1./10.
COEFFICIENTS FOR FIXED HIGH PASS FILTER
AFHP1=-((T**2/160.-2.)/(1.+T/8.+T**2/320.))
AFHP2=-((1.-T/8.+T**2/320.)/(1.+T/8.+T**2/320.))
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APP02090
APP02100
APP02110
APP02120
APP02130
APP02140
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APP02160
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APP02550

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APP02560
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 APP02980
 APP02990
 APP03000
 APP03010
 APP03020
 APP03030

BFHP0=(1./ (1.+T/8.+T**2/320.))
 BFHP1=- (2./ (1.+T/8.+T**2/320.))
 BFHP2=(1./ (1.+T/8.+T**2/320.))

CCC

COEFFICIENTS FOR SELECTABLE HIGH PASS FILTER
 IN THIS CASE, F(LOWER)=0.04 HZ

A=12.52096/40.82834
 B=1./40.82834
 C=11.00999/45.28317
 D=1./45.28317
 E=7.41498/57.57668
 F=1./57.57668
 A1=1.+A*T/2.+B*(T**2)/4.
 B1=-2.+B*T/2.+C*(T**2)/4.
 C1=1.+C*T/2.+D*(T**2)/4.
 E1=-2.+D*T/2.+E*(T**2)/4.
 F1=1.+E*T/2.+F*(T**2)/4.
 G1=-2.+F*T/2.+G*(T**2)/4.
 H1=1.+G*T/2.+H*(T**2)/4.

CCCC

CODE IS "ASHP41" MEANS "A1 COEFFICIENT FOR THE SELECTABLE HIGH
 PASS FILTER WITH LOWER LIMIT 0.04 HZ"

ASHP41=1./ (A1/D1*G1)
 ASHP42=- (C1/A1)
 ASHP43=- (B1/A1)
 ASHP44=- (E1/D1)
 ASHP45=- (F1/D1)
 ASHP46=- (H1/G1)
 ASHP47=- (I1/G1)

CCCC

COEFFICIENTS FOR SELECTABLE LOW PASS FILTER WITH UPPER FREQ.
 OF 0.6 HZ

AA=1./0.03492
 BB=0.35804/0.03492
 CC=1./0.02779
 EE=0.20696/0.02779
 FF=1./0.02779
 AA1=AA*AA1
 BB1=BB*AA1
 CC1=CC*AA1
 DD1=DD*AA1
 EE1=EE*AA1

APP03040
 APP03050
 APP03060
 APP03070
 APP03080
 APP03090
 APP03100
 APP03110
 APP03120
 APP03130
 APP03140
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 APP03170
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 APP03200
 APP03210
 APP03220
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 APP03250
 APP03260
 APP03270
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 APP03320
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 APP03380
 APP03390
 APP03400
 APP03410
 APP03420
 APP03430
 APP03440
 APP03450
 APP03460
 APP03470
 APP03480
 APP03490
 APP03500
 APP03510

```

FF1=DD1 +BB*I/2 +CC*(T**2)/4.0)
GG1={-2.+CC*I/2 +CC*(T**2)/4.0)
HH1={1.-BB*I/2 +CC*(T**2)/4.0)
II1={1.+EEF*(T**2)/4.0)
JJ1={1.-EEF*(T**2)/4.0)
KK1={1.-EEF*(T**2)/4.0)
LL1P61={GG1*KK1+HH1*JJ1)/(GG1*JJ1)
ASLP62={GG1*LL1+HH1*KK1)/(GG1*JJ1)
ASLP63={HH1*LL1+II*KK1)/(GG1*JJ1)
ASLP64={II*DD1)/(GG1*JJ1)
BSLP61={AA1*EEI+BB1*DEE)/(GG1*JJ1)
BSLP62={AA1*EFF+BB1*EEE)/(GG1*JJ1)
BSLP63={BB1*FFF+CC1*EEI)/(GG1*JJ1)
BSLP64={CC1*FFF)/(GG1*JJ1)

```

CC C FINISHED COMPUTING COEFFICIENTS, INITIALIZE STORAGE REGISTERS

```

DO 200 J=1,3000
TRU(J)=0.
Y0(J)=0.
YPO(J)=0.
YASQ(J)=0.
SIG(J)=0.
CONTINUE

```

200

CC C STORAGE REGISTERS SET TO 0, EQUATIONS FOR SIMULATED SIGNAL

```

DSEED = 1456
PHI1=GGUBFS(DSEED)*2.*PI
PHI2=GGUBFS(DSEED)*2.*PI
DO 100 I=1,3000
I1=I-1
I2=I-2
I3=I-3
I4=I-4
I5=I-5
I6=I-6
IF(I1) I1=I
IF(I2) I2=I
IF(I3) I3=I
IF(I4) I4=I
IF(I5) I5=I
IF(I6) I6=I
TRU(I)=SIN(0.02*PI*FLOAT(I)+PHI1)
ANDI=GGUBFS(DSEED)

```

C

```

APP03520
APP03530
APP03540
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APP03590
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APP03650
APP03660
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APP03680
APP03690
APP03700
APP03710
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APP03870
APP03880
APP03890
APP03900
APP03910
APP03920
APP03930
APP03940
APP03950
APP03960
APP03970
APP03980
APP03990

```

```

C C C
THIS NOISE STATEMENT ADDS NOISE OF +/- 0.25 TO THE SIGNAL
IN ADDITION TO A SINUSSOID OF F=10 HZ OF MAG. +/- 0.5
ANOISE=0.5*(ANO1-0.5)
SIG(I)=TRU(I)+0.5*SIN(2.*PI*FLOAT(I)+PHI2)+ANOISE
TIME(I)=FLOAT(I)/600.
YO(I)=8FHPO*SIG(I)+BFHPI*SIG(I2)+BFHP2*SIG(I2)+AFHPI*YO(I1)
$+AFHP2*YO(I2)
XI(I)=ASHP41*YO(I)+ASHP42*X1(I2)+ASHP43*X1(I1)
XI(I1)=X1(I1)+X1(I2)-2.*X1(I1)
XI(I2)=X1(I1)+ASHP44*X1(I1)+ASHP45*X1(I2)
XIV(I)=X1(I1)+ASHP46*X1(I1)+ASHP47*XV(I2)
XV(I)=XIV(I)+XV(I2)-2.*XV(I1)
YPO(I)=XV(I1)+ASLP60*ASQ(I1)+ASLP63*ASQ(I2)+ASLP64*ASQ(I4)
GP1=BSLPP60*YPO(I1)+BSLPP61*YPO(I1)+BSLPP62*YPO(I2)
$+BSLPP63*YPO(I3)+BSLPP64*YPO(I4)
ASQ(I)=GP1+GP2
100 CONTINUE
COMPUTATIONS FINISHED AND ANSWERS STORED IN ARRAYS, PLOT OUTPUT
CALL SUBROUTINE DRAW FOR FIRST GRAPH, A TIME SERIES
REPRESENTATION OF THE INPUT SIGNAL TO THE PROGRAM
ONLY ONE PLOT ON THIS GRAPH, X AXIS WILL BE MAGNITUDE AND
LABELLED "MAGNITUDE" ON A LINEAR SCALE
Y AXIS WILL BE TIME AND LABELLED "MINUTES" ON A LINEAR SCALE
CALL DRAW(3000, TIME, YO, 0, 0, LABEL, ITIL, 0, 0, 0, 0, 0, 0, 5, 4, 1, LAST)
END OF FIRST PLOT, PLOT SECOND PLOT
SECOND PLOT WILL BE A TIME SERIES REPRESENTATION OF THE ASQ81
OUTPUT AS COMPUTED
PLOT WILL HAVE X AXIS LABELLED "MAGNITUDE", Y AXIS LABELLED
"MINUTES", BOTH ON A LINEAR SCALE
CALL DRAW(3000, TIME, ASQ, 0, 0, LABEL, ITIL, 0, 0, 0, 0, 0, 0, 5, 4, 1, LAST)
THIRD PLOT WILL BE A PLOT OF THE 'TRUE' SIGNAL VERSUS TIME
WITH SIGNAL ON THE X AXIS AND TIME ON THE Y AXIS
CALL DRAW(3000, TIME, YPG, 0, 0, LABEL, TITLE, 0, 0, 0, 0, 0, 0, 5, 4, 1, LAST)
C C C C C C C C C C C C C C C C C C C C C C C C C C C C C C C C C C C C C

```

APP04000
APP04010
APP04020
APP04030
APP04040
APP04050
APP04060
APP04070

CALL DRAW(3000, TIME, SIG, 0, 0, LABEL, TITLA, 0, 0, 0, 0, 0, 0, 0, 5, 4, 1, LAST)
CALL DRAW(3000, TIME, TRU, 0, 0, LABEL, TITLC, 0, 0, 0, 0, 0, 0, 0, 5, 4, 1, LAST)

FINISHED PLOTTING

STOP
END

C
C
/*

APPENDIX G

DIGITAL SOFTWARE FOR COMPUTATION OF SYSTEM AMPLITUDE VERSUS FREQUENCY

APP04100
APP04110
APP04120
APP04130
APP04140
APP04150
APP04160
APP04170
APP04180
APP04190
APP04200
APP04210
APP04220
APP04230
APP04240
APP04250
APP04260
APP04270
APP04280
APP04290
APP04300
APP04310
APP04320
APP04330
APP04340
APP04350
APP04360
APP04370
APP04380
APP04390
APP04400
APP04410
APP04420
APP04430
APP04440
APP04450
APP04460
APP04470
APP04480
APP04490
APP04500
APP04510
APP04520
APP04530
APP04540
APP04550
APP04560
APP04570

```
//HUETE JOB (1457,1106), ' ', CLASS=B
// EXEC FRTXCLGP
// FORT.SYSIN DD *
CCCCCCCCCCCC
      THIS PROGRAM IS DESIGNED TO INPUT VARIOUS FREQUENCIES INTO THE
      DIGITAL FILTER PROGRAM FOR THE ASQ-81 AND OBTAIN THE DB LOSS
      CHARACTERISTIC FOR COMPARISON WITH MEASURED DB LOSSES FOR THE
      ASQ 81 MAGNETOMETER. A SINGLE FREQUENCY SIGNAL WILL BE INPUTTED
      AND THE RMS OUTPUT DIVIDED BY THE RMS INPUT TO DETERMINE
      ATTENUATION.
      SET UP ARRAYS. SIG() IS THE SIGNAL, ASQ() IS THE PROGRAM
      OUTPUT, TRU() IS THE SIGNAL WITHIN THE FREQUENCY RANGE OF THE
      PROGRAM.
      MGN4 FORTRAN
      THIS PROGRAM IS DESIGNED TO INPUT VARIOUS FREQUENCIES INTO THE
      DIGITAL FILTER PROGRAM FOR THE ASQ-81 AND OBTAIN THE DB LOSS
      CHARACTERISTIC FOR COMPARISON WITH MEASURED DB LOSSES FOR THE
      ASQ 81 MAGNETOMETER. A SINGLE FREQUENCY SIGNAL WILL BE INPUTTED
      AND THE RMS OUTPUT DIVIDED BY THE RMS INPUT TO DETERMINE
      ATTENUATION.
      SET UP ARRAYS. SIG() IS THE SIGNAL, ASQ() IS THE PROGRAM
      OUTPUT, TRU() IS THE SIGNAL WITHIN THE FREQUENCY RANGE OF THE
      PROGRAM.
      DIMENSION SIG(3000), ASQ(3000), TRU(3000), TIME(3000)
      DIMENSION YG(3000), VPO(3000), FREQ(20)
      DIMENSION XI(3000), XII(3000), XIV(3000), XV(3000)
      REAL*8 DSEED
      REAL*8 T, AFHP1, AFHP2, BFHP0, BFHP1, BFHP2, A, B, C, D, E, F
      REAL*8 AI, BI, CI, DI, EI, FI, GI, HI, IJ, JI, KI, LI
      REAL*8 AA, BB, CC, DD, EE, FF, AA1, BB1, CC1, DD1, EE1, FF1, GG1, HH1, I11
      REAL*8 J11, KK1, L11
      REAL*8 ASHP41, ASHP42, ASHP43, ASHP44, ASHP45, ASHP46, ASHP47
      REAL*8 ASLP61, ASLP62, ASLP63, ASLP64
      REAL*8 BSLP60, BSLP61, BSLP62, BSLP63, BSLP64
      DATA PI/3.141592954/
      DOUBLE PRECISION DSEED, SUMSQ, SMSQT, RATIO
      DEFINE AND COMPUTE ALL COEFFICIENTS
      TEN SAMPLES PER SECOND
      T=1./10.
      COEFFICIENTS FOR FIXED HIGH PASS FILTER
      AFHP1 = ((T**2/160.-2.)/(1.+T/8.+T**2/320.))
      AFHP2 = ((1.-T/8.+T**2/320.)/(1.+T/8.+T**2/320.))
      BFHP0 = (1.)/(1.+T/8.+T**2/320.))
      BFHP1 = ((2.)/(1.+T/8.+T**2/320.))
      BFHP2 = (1.)/(1.+T/8.+T**2/320.))
      COEFFICIENTS FOR SELECTABLE HIGH PASS FILTER
      IN THIS CASE, F(LOWER)=0.04 HZ
      A=12.52096/40.82834
      B=1.740.82834
      C=11.00599/45.28317
      D=1.745.28317
CCCC
```

APP04580
 APP04590
 APP04600
 APP04610
 APP04620
 APP04630
 APP04640
 APP04650
 APP04660
 APP04670
 APP04680
 APP04690
 APP04700
 APP04710
 APP04720
 APP04730
 APP04740
 APP04750
 APP04760
 APP04770
 APP04780
 APP04790
 APP04800
 APP04810
 APP04820
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 APP04940
 APP04950
 APP04960
 APP04970
 APP04980
 APP04990
 APP05000
 APP05010
 APP05020
 APP05030
 APP05040
 APP05050

E=7.41498/57.5766E
 F=1./57.57668
 A1=1.+A*T/2.+B*(T**2)/4.
 B1=-2.+A*T/2.+B*(T**2)/4.
 C1=1.+C*T/2.+D*(T**2)/4.
 D1=-2.+C*T/2.+D*(T**2)/4.
 E1=1.+E*T/2.+F*(T**2)/4.
 F1=-2.+E*T/2.+F*(T**2)/4.
 G1=1.+G*T/2.+H*(T**2)/4.
 H1=-2.+G*T/2.+H*(T**2)/4.
 I1=1.+I*T/2.+J*(T**2)/4.

CODE IS "ASHP41" MEANS "A1 COEFFICIENT FOR THE SELECTABLE HIGH
 PASS FILTER WITH LOWER LIMIT 0.04 HZ"

CCCC

ASHP41=1./((A1/D1)*G1)
 ASHP42=-((C1/A1)
 ASHP43=-((B1/A1)
 ASHP44=-((E1/D1)
 ASHP45=-((F1/D1)
 ASHP46=-((H1/G1)
 ASHP47=-((I1/G1)

COEFFICIENTS FOR SELECTABLE LOW PASS FILTER WITH UPPER FREQ.
 OF 0.6 HZ

CCCC

AA=1./0.03492
 BB=0.35804/C.03492
 CC=1./0.03492
 DD=1./0.02779
 EE=0.20696/0.02779
 FF=1./0.02779
 AA1=AA*AA1
 BB1=2.*1
 CC1=AD*DD1
 DD1=DD*DD1
 EE1=DD1
 GG1=(1.-BB*T/2.+CC*(T**2)/2.+CC*(T**2)/4.)
 HH1=(1.-BB*T/2.+CC*(T**2)/2.+CC*(T**2)/4.)
 II1=(1.-EE*T/2.+FF*(T**2)/2.+FF*(T**2)/4.)
 KK1=(1.-EE*T/2.+FF*(T**2)/2.+FF*(T**2)/4.)
 LL1=(1.-GG1*KK1+HH1*KK1)/(GG1*JJ1)
 ASLP61=-((GG1*LL1+HH1*KK1)/(GG1*JJ1)
 ASLP62=-((HH1*LL1+II1*KK1)/(GG1*JJ1)
 ASLP63=-((II1*LL1)/(GG1*JJ1)
 ASLP64=-((II1*LL1)/(GG1*JJ1)

```

APP05060
APP05070
APP05080
APP05090
APP05100
APP05110
APP05120
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APP05290
APP05300
APP05310
APP05320
APP05330
APP05340
APP05350
APP05360
APP05370
APP05380
APP05390
APP05400
APP05410
APP05420
APP05430
APP05440
APP05450
APP05460
APP05470
APP05480
APP05490
APP05500
APP05510
APP05520
APP05530

```

```

BSLP60=(AA1*DD1)/(GG1*JJ1)
BSLP61=(AA1*EE1+BB1*DD1)/(GG1*JJ1)
BSLP62=(AA1*EE1+BB1*EE1+CC1*DD1)/(GG1*JJ1)
BSLP63=(BB1*FF1+CC1*EE1)/(GG1*JJ1)
BSLP64=(CC1*FF1)/(GG1*JJ1)

```

FINISHED COMPUTING COEFFICIENTS, INITIALIZE STORAGE REGISTERS

```

DD 200 J=1,2000
TRU(J)=0.
YD(J)=0.
YPO(J)=0.
ASQ(J)=0.
SIG(J)=0.
CONTINUE

```

200

STORAGE REGISTERS SET TO 0, EQUATIONS FOR SIMULATED SIGNAL

```

DSEED = 1456.
PHI1=GGURFS(DSEED)*2.*PI
PHI2=GGURFS(DSEED)*2.*PI
FREEQ(1)=0.01
FREEQ(2)=0.02
FREEQ(3)=0.03
FREEQ(4)=0.04
FREEQ(5)=0.05
FREEQ(6)=0.06
FREEQ(7)=0.07
FREEQ(8)=0.08
FREEQ(9)=0.09
FREEQ(10)=0.10
FREEQ(11)=0.20
FREEQ(12)=0.30
FREEQ(13)=0.40
FREEQ(14)=0.50
FREEQ(15)=0.60
FREEQ(16)=0.70
FREEQ(17)=0.80
FREEQ(18)=0.90
FREEQ(19)=1.0
FREEQ(20)=1.15
DD 300 I=1,200
DD 100 I=1,3000
I1=I-1
I2=I-2
I3=I-3
I4=I-4
I5=I-5

```

200
CC

APP05540
 APP05550
 APP05560
 APP05570
 APP05580
 APP05590
 APP05600
 APP05610
 APP05620
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 APP05680
 APP05690
 APP05700
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 APP05720
 APP05730
 APP05740
 APP05750
 APP05760
 APP05770
 APP05780
 APP05790
 APP05800
 APP05810
 APP05820
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 APP05880
 APP05890
 APP05900
 APP05910
 APP05920
 APP05930
 APP05940
 APP05950
 APP05960
 APP05970
 APP05980
 APP06000
 APP06010

```

I6=I-6
LI(1) LI(2) LI(3) LI(4) LI(5) LI(6)
IF(LI(1)) I1=1
IF(LI(2)) I2=1
IF(LI(3)) I3=1
IF(LI(4)) I4=1
IF(LI(5)) I5=1
IF(LI(6)) I6=1
TRU(I1)=TRU(I)
SIG(I1)=SIG(I)
TIME(I1)=FLOAT(I1)/600.
PI*FREQ(I1)*FLOAT(I1)

```

THE FIRST STAGE OF THE FILTER PROGRAM IS COMMENTED OUT BECAUSE IN THIS VERSION OF THE PROGRAM THE FIXED HIGH PASS FILTER IS NOT INCLUDED SO AS TO ENABLE COMPARISON WITH DATA FURNISHED BY TEXAS INSTRUMENTS, INC. BY REMOVING THE COMMENT CHARACTERS, AND COMMENTING OUT THE STEP FOLLOWING THEM (YO(I)=SIG(I)), THE PROGRAM CAN BE MADE TO INCLUDE THE FIXED HIGH PASS FILTER

```

YO(I1)=BFHP0*SIG(I1)+BFHP1*SIG(I2)+BFHP2*SIG(I3)+AFHP1*YO(I1)
+AFHP2*YO(I2)
YO(I2)=SIG(I1)
XI(I1)=ASHP4+1*YO(I1)+ASHP42*XI(I2)+ASHP43*XI(I3)
XI(I2)=-2.*XI(I1)+ASHP44*XI(I2)+ASHP45*XI(I3)
XI(I3)=XI(I1)+ASHP46*XI(I2)+ASHP47*XI(I3)
XIV(I1)=XIV(I2)+XV(I1)
XV(I1)=XV(I2)+XV(I3)
GP1=ASLP61*ASQ(I1)+ASLP62*ASQ(I2)+ASLP63*ASQ(I3)+ASLP64*ASQ(I4)
GP2=BSLP60*YPO(I1)+BSLP61*YPO(I2)+BSLP62*YPO(I3)+BSLP63*YPO(I4)
+BSLP64*YPO(I5)
ASQ(I1)=GP1+GP2

```

100 CONTINUE
 THE FOLLOWING SECTION COMPUTES THE AVERAGE VALUES OF THE OUTPUT AND CONVERTS TO DB ATTENUATION

```

SUMSQ=0.0
SUMSQ=0.0
DD 301 J,J=2000,3000
SUMSQ=(ASQ(J,J)**2)
SUMSQ=(TRU(J,J)**2)
CONTINUE
RATIO=SUMSQ/SMSQT
DBLOSS=10.*LOG10(RATIO)
WRITE(6,40)IFREQ(I1),DBLOSS
FORMAT(IX,FREQUENCY = ,F10.2, DB LOSS = , F10.5)

```

CCCCCCCCCCCC

C

CCC

301

4001

APP06020
APP06030
APP06040
APP06050
APP06060
APP06070
APP06080

CC FINISHED PLCTING
300 CONTINUE
STOP
END
/*

APPENDIX H
DIGITAL SOFTWARE FOR SIMULATION (ANDERSON FUNCTIONS AS INPUT)

APP06110
APP06120
APP06130
APP06140
APP06150
APP06160
APP06170
APP06180
APP06190
APP06200
APP06210
APP06220
APP06230
APP06240
APP06250
APP06260
APP06270
APP06280
APP06290
APP06300
APP06310
APP06320
APP06330
APP06340
APP06350
APP06360
APP06370
APP06380
APP06390
APP06400
APP06410
APP06420
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APP06440
APP06450
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APP06470
APP06480
APP06490
APP06500
APP06510
APP06520
APP06530
APP06540
APP06550
APP06560
APP06570
APP06580

```
//HUETE JOB (1457,1106), , , CLASS=B
//EXEC FRIXCCLGP
//FORT.SYSIN DD *
          MGN6 FORTRAN
THIS PROGRAM IS DESIGNED TO TEST THE ACTION OF THE PRELIMINARY
DIGITAL FILTER PROGRAM FOR THE ASQ-81 BY INTRODUCING SIMULATED
SUBMARINE SIGNALS INTO THE SYSTEM THROUGH THE USE OF ANDERSON
FUNCTIONS OF VARYING RANGES AND SPEEDS.

SET UP ARRAYS. SIG(I) IS THE SIGNAL, ASQ(I) IS THE PROGRAM OF THE
OUTPUT. TRU(I) IS THE SIGNAL WITHIN THE FREQUENCY RANGE OF THE
PROGRAM
DIMENSION SIG(3000), ASQ(3000), TRU(3000), TIME(3000)
DIMENSION YD(3000), YPD(3000)
DIMENSION XI(3000), XII(3000), XIII(3000), XIV(3000), XV(3000)
REAL*8 T, AFHP1, AFHP2, BFHP0, BFHP1, BFHP2, A, B, C, D, E, F
REAL*8 AI, BI, CI, DI, EI, FI, GI, HI, IJ, JI, KI, LI
REAL*8 AA, BB, CC, DD, EE, FF, AA, BB, CC, DD, EE, FF, GG, HH, II, JJ
REAL*8 ASHP41, ASHP42, ASHP43, ASHP44, ASHP45, ASHP46, ASHP47
REAL*8 ASLP61, ASLP62, ASLP63, ASLP64
REAL*8 BSLP60, BSLP61, BSLP62, BSLP63, BSLP64
REAL*8 TITL A(12), HUETE
REAL*8 TITL B(12), HUETE
REAL*8 TITL C(12), HUETE
REAL*8 TITL D(12), HUETE
REAL*8 TITL E(12), HUETE
REAL LABEL, /
DATA PI/3.141592954/
DOUBLE PRECISION DSEED, BETA, NORM
DEFINE AND COMPUTE ALL COEFFICIENTS
TEN SAMPLES PER SECOND
T=0.125
COEFFICIENTS FOR FIXED HIGH PASS FILTER
AFHP1=-((I**2/160.-2.)/I.+T/8.+T**2/320.)
BFHP2=-((I.-T/8.+T**2/320.)/I.+T/8.+T**2/320.)
BFHP0=(1./I.+T/8.+T**2/320.)
BFHP1=-((2./I.+T/8.+T**2/320.))
```

UUUU UUU

APP06590
 APP06600
 APP06610
 APP06620
 APP06630
 APP06640
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 APP06670
 APP06680
 APP06690
 APP06700
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 APP06960
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 APP06980
 APP06990
 APP07000
 APP07010
 APP07020
 APP07030
 APP07040
 APP07050
 APP07060

BFHP2=(1./(1.+T/8.+T**2/320.))
 COEFFICIENTS FOR SELECTABLE HIGH PASS FILTER
 IN THIS CASE, FLOWER=0.04 HZ

A=12.52096/40.82834
 B=1./40.82834
 C=11.00999/45.28517
 D=1./45.28317
 E=7.41459/57.57668
 F=1./57.27668
 AI=1.+AB*(T/2.+B*(T**2)/4.
 BI=-2.+AB*(T**2)/4.
 CI=1.-A*T/2.+B*(T**2)/4.
 DI=-2.+C*T/2.+D*(T**2)/4.
 EI=1.-C*T/2.+D*(T**2)/4.
 FI=1.+E*T/2.+F*(T**2)/4.
 HI=-2.+E*T/2.+F*(T**2)/4.
 I1=1.-E*T/2.+F*(T**2)/4.

CODE IS "ASHP41" MEANS "A1 COEFFICIENT FOR THE SELECTABLE HIGH
 PASS FILTER WITH LOWER LIMIT 0.04 HZ"

ASHP41=1./(A1*D1*G1)
 ASHP42=-C1/A1
 ASHP43=-B1/A1
 ASHP44=-E1/D1
 ASHP45=-F1/D1
 ASHP46=-H1/G1
 ASHP47=-I1/G1

COEFFICIENTS FOR SELECTABLE LOW PASS FILTER WITH UPPER FREQ.
 OF 0.6 HZ

AA=1./0.03492
 BB=0.35804/C.03492
 CC=1./0.03492
 DD=1./0.02779
 EE=0.20696/C.02779
 FF=1./0.02779
 AA1=A*A*AA
 BB1=B*AA
 CC1=AA*(T**2)/4.
 DD1=DD*DD1
 EE1=2.*DD1
 GG1=(1.+BB*T/2.+CC*(T**2)/4.)

CCCC

CCCC

CCCC

```

APP07070
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APP07540

```

```

HH1=(-2.+CC*(T**2)/2.+BB*T/2.+CC*(T**2)/4.)
II1=(1.+EEFF*(T**2)/2.+FF*(T**2)/4.)
JJ1=(1.-EEFF*(T**2)/2.+FF*(T**2)/4.)
KK1=(1.-EEFF*(T**2)/2.+FF*(T**2)/4.)
LL1=(1.-EEFF*(T**2)/2.+FF*(T**2)/4.)
ASLP61=(GG1*KK1+HH1*JJ1)/(GG1*JJ1)
ASLP62=(GG1*LL1+HH1*KK1+II1*JJ1)/(GG1*JJ1)
ASLP63=(HH1*LL1+II1*KK1)/(GG1*JJ1)
ASLP64=(II1*DD1)/(GG1*JJ1)
BSLP60=(AA1*DD1)/(GG1*JJ1)
BSLP61=(AA1*EE1+BB1*DD1)/(GG1*JJ1)
BSLP62=(AA1*FF1+BB1*EE1+CC1*DD1)/(GG1*JJ1)
BSLP63=(BB1*FF1+CC1*EE1)/(GG1*JJ1)
BSLP64=(CC1*FF1)/(GG1*JJ1)

```

FINISHED COMPUTING COEFFICIENTS, INITIALIZE STORAGE REGISTERS

```

DO 200 J=1,3000
TRU(J)=0.
YPO(J)=0.
ASQ(J)=0.
SIG(J)=0.
CONTINUE

```

STORAGE REGISTERS SET TO 0, EQUATIONS FOR SIMULATED SIGNAL

```

DO 100 I=1,2400
I1=I-1
I2=I-2
I3=I-3
I4=I-4
I5=I-5
I6=I-6
IF(I1.LT.1)I1=1
IF(I2.LT.1)I2=1
IF(I3.LT.1)I3=1
IF(I4.LT.1)I4=1
IF(I5.LT.1)I5=1
IF(I6.LT.1)I6=1

```

THIS SIGNAL STATEMENT INPUTS A 180 KNOTS AIRCRAFT AT A CPA RANGE OF 400 FEET. THIS IS TO TEST THE OPERATION OF THE SELCE TABLE LOW PASS FILTER TO SECOND ANDERSON FUNCTION 8 HZ FILTER

```

TIME(I)=FLOAT(I)/480.
BETA=18000.*(TIME(I)-2.5)/400.

```


APP07550
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 APP08020

```

BETP=DSQRT((BETA**2)+1.)
THE FACTOR "NORM" IS A NORMALIZATION FACTOR TO MAKE THE INPUT
SIGNAL +/- AMPLITUDE 1
NORM=1.7469281

THIS SIGNAL IS THE FIRST ANDERSON FUNCTION. TO OBTAIN THE SECOND
ANDERSON FUNCTION, MULTIPLY BY BETA, AND AGAIN TO OBTAIN THE
THIRD ANDERSON FUNCTION
SIG(I)=NORM*(1./BETP)**5)
YO(I)=BFHP0*SIG(I)+BFHP1*SIG(I)+BFHP2*SIG(I)+AFHP1*YO(I)
$+AFHP2*YO(I)
XI(I)=ASHP41*YO(I)+ASHP42*XI(I)+ASHP43*XI(I)
XI(I)=XI(I)+ASHP44*XI(I)+ASHP45*XI(I)
XIV(I)=XI(I)+ASHP46*XI(I)+ASHP47*XI(I)
XV(I)=XIV(I)+ASHP48*XI(I)+ASHP49*XI(I)
YPO(I)=ASLP60*YPO(I)+ASLP61*YPO(I)+ASLP62*YPO(I)
GP2=BSLP63*YPO(I)+BSLP64*YPO(I)
$+ASLP65*YPO(I)+GP1+GP2

100 CONTINUE

COMPUTATIONS FINISHED AND ANSWERS STORED IN ARRAYS. PLOT OUTPUT
CALL SUBROUTINE DRAW FOR FIRST GRAPH, A TIME SERIES
REPRESENTATION OF THE INPUT SIGNAL TO THE PROGRAM

ONLY ONE PLOT ON THIS GRAPH, X AXIS WILL BE MAGNITUDE AND
LABELLED "MAGNITUDE" ON A LINEAR SCALE
Y AXIS WILL BE TIME AND LABELLED "MINUTES" ON A LINEAR SCALE
CALL DRAW(2400,TIME,YO,0,0,LABEL,TITLD,0,0,0,0,0,0,4,1, LAST)
END OF FIRST PLOT, PLOT SECOND PLOT
SECOND PLOT WILL BE A TIME SERIES REPRESENTATION OF THE ASQ81
OUTPUT AS COMPUTED
PLOT WILL HAVE X AXIS LABELLED "MAGNITUDE", Y AXIS LABELLED
"MINUTES", BOTH ON A LINEAR SCALE
  
```

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 00 000000000 000000000

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APP08150

CALL DRAW(2400, TIME, ASQ, 0, 0, LABEL, TITLB, 0, 0, 0, 0, 0, 10, 4, 1, LAST)
THIRD PLOT WILL BE A PLOT OF THE 'TRUE' SIGNAL VERSUS TIME
WITH SIGNAL ON THE X AXIS AND TIME ON THE Y AXIS
CALL DRAW(2400, TIME, YPO, 0, 0, LABEL, TITL, 0, 0, 0, 0, 10, 4, 1, LAST)
CALL DRAW(2400, TIME, SIG, 0, 0, LABEL, TITLA, 0, 0, 0, 0, 10, 4, 1, LAST)
FINISHED PLOTTING
STOP
END

C
C
C
C
C
/*

APPENDIX I
DIGITAL FILTERING SOFTWARE

APP08180
 APP08190
 APP08200
 APP08210
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 APP08640
 APP08650

```

//HUETE JOB (1457,0165), 'HUETE SMC 2740', CLASS=G
//*MAIN FRINCLGP, PARM=LKED='LIST,MAP,XREF',REGION.GO=2048K
//EXEC SYSIN DD
//FORT. INTR#2 IN(16)
C   CARRAY *8 X(8192), XXP(8192)
    C COMPLEX *8 Z(8192), YV(8192)
    C REAL *4 ZZ(8192), YV(8192)
    C THE ABOVE COMPLEX *8 ARRAYS ARE USED TO ORDER INPUT DATA AND
    C INITIALLY REPRESENT VOLTAGE - TIME SERIES INFORMATION.
    C
    C THE NEXT THREE LINES ARE ARRAYS NEEDED FOR DATA TAPE READING AND
    C CONVERSION TO TOTAL FIELD FLUCTUATION TIME SERIES
    C
    C DIMENSION TIME(8192), FREQ(8192), WORK(24576), FRQ2(8192)
    C DIMENSION ZX1(8192), ZY1(8192)
    C DIMENSION ZZX1(24576), ZZY1(24576), ZZV1(24576)
    C
    C THE FOLLOWING LINES CONTAIN ARRAYS NEEDED FOR SIGNAL INPUT TO THE
    C FILTER, SIGNAL PROCESSING WITHIN THE FILTER, AND COEFFICIENTS
    C USED BY THE FILTER PROGRAM
    C
    C DIMENSION TIME2(24576), OUTFD(24576), CLFD(24576)
    C REAL *8 AH(4), BH(4), CH(4), DH(4), EH(4), FH(4)
    C REAL *8 AL(3), BL(3), CL(3), DL(3), EL(3), FL(3), FRQ(4), FRQL(3)
    C REAL *8 T1, AFHP1, AFHP2, BFHP0, BFHP1, BFHP2, SHP1, SHP2, SHP3, SHP4, ASHP5, ASHP6, ASHP7,
    C REAL *8 I1, J1, K1, L1, ASLP1, ASLP2, ASLP3, ASLP4, ASLP5, ASLP6, ASLP7, ASLP8, BSHP1, BSHP2, BSHP3, BSHP4,
    C REAL *8 ASLP1, ASLP2, ASLP3, ASLP4, ASLP5, ASLP6, ASLP7, ASLP8, BSHP1, BSHP2, BSHP3, BSHP4,
    C REAL *8 SIG1, SIG2, SIG3, YP01, YP02, YP03, YP04, YP05, YP06, YP07, YP08, YP09, YP10, YP11, YP12, YP13, YP14,
    C REAL *8 XVP1, XVP2, XVP3, XVP4, XVP5, XVP6, XVP7, XVP8, XVP9, XVP10, XVP11, XVP12, XVP13, XVP14,
    C REAL *8 XVP1, XVP2, XVP3, XVP4, XVP5, XVP6, XVP7, XVP8, XVP9, XVP10, XVP11, XVP12, XVP13, XVP14,
    C THE ARRAYS REPRESENT FREQUENCY DOMAIN (FF TRANSFORMED)
    C MAGNITUDE DATA AND ARE EVENTUALLY CONVERTED TO POWER SPECTRAL
    C DENSITY INFORMATION. ZX1, ZY1, ZV1, AND ZII REPRESENT MAGNITUDE
    C VALUES.
    C
    C THE NEXT LINES CONTAIN CONSTANTS AND ARRAYS USED IN PLOTTING
    C THE OUTPUT
    C
    C INTEGER K, I4, I5, Q
    C REAL SUMX, SUMY, SUMZ, AVE1
    C REAL CONSTX, CONSTY, CONSTZ, AVE2
    C INTEGER *4 ITB(12)/12*0/, RTB(28)/28*0.0/
    C REAL *4 LAB(4)
    C REAL *8 TITLE(12)
    C REAL *8 TITLE(1), RTB(5)
  
```

```

APP08660
APP08670
APP08680
APP08690
APP08700
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APP09120
APP09130

```

SET VARIABLES EQUAL TO ZERO

```

DATA XX/8192*10.0.0.//
DATA ZZ/16384*0.0.//
DATA TT/8192*0.0.//
DATA TIME,FREQ/16384*0.0.//
K=0
I4=1
I5=1
CONSTX=0.0
SUMX=0.0
SUMY=0.0
SUMZ=0.0
AWEIG=0.0
XORIGP=0.0
XMAXP=0.0

```

SET STORAGE REGISTERS TO ZERO. STORAGE REGISTERS ARE USED VICE
 INTERMEDIATE OUTPUT ARRAYS IN ORDER TO CUT DOWN THE AMOUNT OF
 ARRAY STORAGE REQUIRED BY THE PROGRAM AND TO RETAIN "MEMORY"
 OF THE PREVIOUS VALUES FOR COMPUTATIONAL USE IN ORDER TO ELIMINATE
 THE "START UP" LAG OF THE OUTPUT VALUES

```

SIG1=0.0
Y01=0.0
Y02=0.0
Y03=0.0
Y04=0.0
Y05=0.0
Y06=0.0
Y07=0.0
Y08=0.0
Y09=0.0
Y10=0.0
Y11=0.0
Y12=0.0
Y13=0.0
Y14=0.0
Y15=0.0
Y16=0.0
Y17=0.0
Y18=0.0
Y19=0.0
Y20=0.0
Y21=0.0
Y22=0.0
Y23=0.0
Y24=0.0
Y25=0.0
Y26=0.0
Y27=0.0
Y28=0.0
Y29=0.0
Y30=0.0
Y31=0.0
Y32=0.0
Y33=0.0
Y34=0.0
Y35=0.0
Y36=0.0
Y37=0.0
Y38=0.0
Y39=0.0
Y40=0.0
Y41=0.0
Y42=0.0
Y43=0.0
Y44=0.0
Y45=0.0
Y46=0.0
Y47=0.0
Y48=0.0
Y49=0.0
Y50=0.0
Y51=0.0
Y52=0.0
Y53=0.0
Y54=0.0
Y55=0.0
Y56=0.0
Y57=0.0
Y58=0.0
Y59=0.0
Y60=0.0
Y61=0.0
Y62=0.0
Y63=0.0
Y64=0.0
Y65=0.0
Y66=0.0
Y67=0.0
Y68=0.0
Y69=0.0
Y70=0.0
Y71=0.0
Y72=0.0
Y73=0.0
Y74=0.0
Y75=0.0
Y76=0.0
Y77=0.0
Y78=0.0
Y79=0.0
Y80=0.0
Y81=0.0
Y82=0.0
Y83=0.0
Y84=0.0
Y85=0.0
Y86=0.0
Y87=0.0
Y88=0.0
Y89=0.0
Y90=0.0
Y91=0.0
Y92=0.0
Y93=0.0
Y94=0.0
Y95=0.0
Y96=0.0
Y97=0.0
Y98=0.0
Y99=0.0
Y100=0.0

```

THE FOLLOWING SEVERAL STEPS WOULD BE USED IF THE INPUT TO THE
 FILTER PROGRAM WERE THREE MUTUALLY PERPENDICULAR COIL SENSORS.
 SINCE THE INPUT IS A SINGLE COIL SENSOR ORIENTED ALONG THE
 EARLY FIELD, THESE STEPS ARE NOT NECESSARY, BUT ARE RETAINED
 AS REFERENCE

CC

CCCCC

CCCCC

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 APP09590
 APP09600
 APP09610

```

TWOPI=6.2831853
COS60=COS(TWOPI/6.)
COS30=COS(TWOPI/12.)
D=16.75*TWOPI/360.
COSD=COS(D)
COSDI=COS(D)
COSTIS=THE DECLINATION OR MAGNETIC VARIATION AT THE MAGNETOMETER
SITE.
SET ARRAYS TO ZERO
DO 31 XI(INI)=1,24576
ZZYI(INI)=0.0
ZZVI(INI)=0.0
TIMZ(INI)=0.0
CONTINUE
31 CONTINUE NEXT FIVE LINES SERVE AS A TIME DELAY IN STARTING THE
DATA ANALYSIS
DEC=10
ITL=10
JJ=1,ITL
CALL RDE(20,IN,200,IREC,IRR)
CONTINUE=8192
NR=1
FNR=FLOAT(NR)
DO 200 IM=1,NR
XDRIGP=XMAXP
DO 70 IL=1,3
THE DO LOOP ENDING WITH STATEMENT 70 ENABLES THE PROGRAM TO
PROCESS A LARGE AMOUNT OF DATA BY REPEATING THE PROCESS IN
BLOCKS. THE DATA POINTS FROM EACH RUN THROUGH THE DO LOOP ARE
ADDED TOGETHER AND EVENTUALLY AVERAGED BY THE NUMBER OF RUNS
THROUGH THE DO LOOP. NUMBER OF DATA SEQUENCES TO BE AVERAGED.
NR, REFERENCE CURRENTLY EQUALS 24576 DATA POINTS OR THREE SETS
OF 128 SECONDS OF DATA.
THE DO LOOP ENDING WITH 60 READS THE DATA FROM THE PCM FRAME
STRIPS OUT THE SYNC CODE, AND SORTS OUT THE DATA BY COIL
CHANNEL
DO 60 JJ=1,IFRAME
CALL RD(20,IN,1000,IREC,IRR)
XX(JJ)=IN(2)
YY(JJ)=IN(3)
ZZ(JJ)=IN(4)
CONTINUE
60 CONTINUE

```

APP09620
 APP09630
 APP09640
 APP09650
 APP09660
 APP09670
 APP09680
 APP09690
 APP09700
 APP09710
 APP09720
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 APP09750
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 APP09830
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 APP09980
 APP09990
 APP10000
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 APP10060
 APP10070
 APP10080
 APP10090

```

200 WRITE(6,200)IRR,IREC
    FORMAT(10X,'I6,I6,5X,'I6',/1)
    THE FOLLOWING SECTION GENERATES THE TIME AND FREQUENCY FORM
    ARRAYS AND NORMALIZES THE INPUT PCM DATA TO VOLTAGE FORM
    IN PREPARATION FOR FAST FOURIER TRANSFORM TO THE FREQUENCY
    DOMAIN.
    N=8192
    FN=FLOAT(N)
    DELTAT=1./64.
    DELTAF=1./((FN*DELTAT)
    DO 20 J=1,N
      TAT*FLOAT(J)
      TIMEQ(J)=DELTAF*FLOAT(J)
      FRQ(J)=(XX(J)-2048.)#5./2048.
      XX(J)=REAL(XX(J))
      XXP(J)=XX(J)
      YY(J)=(YY(J)-2048.)#5./2048.
      ZZ(J)=(ZZ(J)-2048.)#5./2048.
    IN THIS USE OF THE PROGRAM, DATA, 'YY', IS THE ASQ-81 DATA
    'XX' IS THE COIL ANTENNA COIL DATA, AND 'IF' IS THE
    'ZZ' IS THE SCHEDULED VECTOR, 'YY' IS THE
    TOTAL GEOMETRICALLY PERPENDICULAR COIL SENSORS ARE USED, THIS
    IF THREE MUTUALLY PERPENDICULAR COIL SENSORS ARE USED, THIS
    WILL NOT BE TRUE.
20 CONTINUE
    DO 21 J=1,N
      FRQZ(J)=ALOG10(FREQ(J))
    CONTINUE
    THE NEXT FOUR STATEMENTS PERFORM AN FFT ON THE INPUT
    TIME SERIES DATA. SEE THE WRITEUP ON 'FOUR' FOR
    FURTHER INFORMATION.
    CALL FFFT(XX,N,1,0,WORK)
    THE NEXT BLOCK OF STATEMENTS APPLY THE SYSTEM (VOLTAGE TO
    B-FIELD) TRANSFER FUNCTION TO THE TRANSFORMED FREQUENCY
    DOMAIN DATA. THIS BLOCK ENDS AT STATEMENT 9.
    THE TRANSFER FUNCTION CONVERTS VOLTS TO NANOTESLAS (GAMMAS).
    #**WARNING** THIS TRANSFER FUNCTION YIELDS AN INACCURATE
    PHASE. USE A DIFFERENT TRANSFER FUNCTION IF PHASE INFORMATION
    IS NEEDED.
    DO 9 L=1,N
      FRQ=FRQ*(L)
      IF (FRQ.LE.2.5) GO TO 1
      XX(L)=XX(L)/28.
      GO TO 8
    IF (FRQ.LE.15) GO TO 2
    IF (L)=XX(L)/(105.5-3.14*FRQ)
  
```

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CCCCCCCC

CC CCCCCC

APP1 0100
 APP1 0110
 APP1 0120
 APP1 0130
 APP1 0140
 APP1 0150
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 APP1 0190
 APP1 0200
 APP1 0210
 APP1 0220
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 APP1 0410
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 APP1 0430
 APP1 0440
 APP1 0450
 APP1 0460
 APP1 0470
 APP1 0480
 APP1 0490
 APP1 0500
 APP1 0510
 APP1 0520
 APP1 0530
 APP1 0540
 APP1 0550
 APP1 0560
 APP1 0570

```

    GO TO 8
    2 IF (FRQ.LE.10.)GO TO 3
      XX(L)=XX(L)/(5.958*FRQ-30.97)
      GO TO 8
    3 IF (FRQ.LE.7.5)GO TO 4
      XX(L)=XX(L)/(3.492*FRQ-6.31)
      GO TO 8
    4 IF (FRQ.LE.5.)GO TO 5
      XX(L)=XX(L)/(2.6311*FRQ+0.14667)
      GO TO 8
    5 IF (FRQ.LE.3.)GO TO 6
      XX(L)=XX(L)/(2.6311*FRQ+0.14667)
      GO TO 8
    6 XX(L)=XX(L)/(2.72*FRQ)
      GO TO 8
    8 CONTINUE
    9 CALL FORT(XX,N,1,1,1,WORK)
      DO 57 J=1,N
        XX(J)=XX(J)/FN
    57 CONTINUE
      WRITE(6,600)(XX(I),I=1,100)
      FORMAT(1X,F20.4,4X,F20.4)
      THE FOLLOWING BLOCK TAKES THE MAGNITUDE OF THE COMPLEX VALUES
      DO 56 I=1,N
        ZX(I)=CABS(XX(I))
      CONTINUE
      IF (K.NE.0) GO TO 36
      DO 66 IS=8048,8192
        SUMX=ZXI(IS)+SUMX
      CONTINUE
      CONSTX=SUMX/144.
      DO 67 IS=1,8192
        ZXI(I4)=ZXI(IS)
        I4=I4+1
      CONTINUE
    36 CONTINUE
      SUMX=0
      DO 68 IS=1,144
        SUMX=ZXI(IS)+SUMX
      CONTINUE
      AVE=SUMX/144.
      DO 69 IS=1,8192
        ZXI(I4)=ZXI(IS)+(CONSTX-AVE)
        I4=I4+1
      CONTINUE
    37 CONTINUE
  
```

```

APP1 0580
APP1 0590
APP1 0600
APP1 0610
APP1 0620
APP1 0630
APP1 0640
APP1 0650
APP1 0660
APP1 0670
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APP1 0690
APP1 0700
APP1 0710
APP1 0720
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APP1 0740
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APP1 0770
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APP1 0940
APP1 0950
APP1 0960
APP1 0970
APP1 0980
APP1 0990
APP1 1000
APP1 1010
APP1 1020
APP1 1030
APP1 1040
APP1 1050

```

```

DO 91 I3=1, 8192
ZZY1(I5)=ZY(I3)*10.5
ZZV1(I5)=ZZ(I3)*10.
CLFLD(I5)=XXP(I3)
TIME2(I5)=(DELTA*FLOAT(I3))+128.0*FLOAT(KJ)+XORIGP
I5=I5+1
91 CONTINUE
70 K=K+1
CONTINUE

REMOVE DC VALUE OF OUTPUT TIME SERIES DATA IN ORDER TO PLOT
FLUCTUATIONS

SUMTX=0.0
DO 223 KJ=1,24576
SUMTX=SUMTX+CLFLD(KJ)
SUMTT=SUMTT+ZZX1(KJ)
CONTINUE
223 AVG=SUMTT/24576.
AVX=SUMTX/24576.
DO 222 JK=1,24576
CLFLD(JK)=CLFLD(JK)-AVX
ZZX1(JK)=ZZX1(JK)-AVG
222 CONTINUE

THIS NEXT SECTION IS USED TO SMOOTH THE DATA CURVES
IT IS NOT NORMALLY USED IN ORDER TO PREVENT BIASING
SERIES DATA, BUT MAY BE USED AT USER'S DISCRETION. IF USED, NOTE
THAT THE PROGRAM OUTPUT WILL NOT BE AS EXACT AS POSSIBLE
INPUT TIME

DO 73 L2=1,2
Q=0
DO 74 I5=1,65318
SUMMX=0.0
SUMMY=0.0
SUMMZ=0.0
DO 75 J=1,144
SUMMX=ZZX1(Q+J)+SUMX
SUMMY=ZZY1(Q+J)+SUMY
SUMMZ=ZZV1(Q+J)+SUMZ
CONTINUE
75 ZZX1(I5)=SUMMX/144.
ZZY1(I5)=SUMMY/144.
ZZV1(I5)=SUMMZ/144.
Q=Q+1
CONTINUE
74 CONTINUE

```

```

CCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCCC

```



```

CCCCCCCCCCCC
REAL*8 AH(4),BH(4),CH(4),DH(4),EH(4),FH(4)
REAL*8 AL(3),BL(3),CL(3),DL(3),EL(3),FL(3)
DIMENSION FRQH(4),FRQL(3)
DEFINE AND COMPUTE ALL COEFFICIENTS
UNDER THE PRESENT DATA COLLECTION SYSTEM, 64 SAMPLES ARE TAKEN
PER SECOND. IF ANOTHER DATA COLLECTION SYSTEM IS USED, T MUST
BE ADJUSTED TO THE SAMPLE PERIOD, I.E., 1/SAMPLE RATE
T=1./64.
COEFFICIENTS FOR FIXED HIGH PASS FILTER
AFHP1=-({T*2/160.-2./1.(1.+T/8.+T*2/320.)})
AFHP2=-({(1.-T/8.+T*2/320.)/(1.+T/8.+T*2/320.)})
BFHP0=(1./1.+T/8.+T*2/320.)
BFHP1=-({2./1.(1.+T/8.+T*2/320.)})
BFHP2=(1./1.(1.+T/8.+T*2/320.)})
WRITE(16,1002)AFHP1,AFHP2,BFHP0,BFHP1,BFHP2
FORMAT(1X,'FIXED FILTER,AFHP1=,'F19.16,',AFHP2=,'F19.16,',BFHP0=,'F19.16',BFHP1=,'F19.16',BFHP2=,'F19.16',)
COEFFICIENTS FOR SELECTABLE HIGH PASS FILTERS
THE FOLLOWING ARRAY VALUES ARE FIXED COEFFICIENTS FOR THE VARIOUS
FREQUENCY SELECTIONS POSSIBLE ON THE AN/ASQ-81
FRQH(1)=0.004
FRQH(2)=0.006
FRQH(3)=0.008
FRQH(4)=0.010
AH(1)=12.52096/40.82834
BH(1)=1./40.82834
CH(1)=1./40.599745.28317
DH(1)=1./45.28317
EH(1)=7.41498757668
FH(1)=1./57.57668
AH(2)=8.34727/18.14591
BH(2)=1./18.14591
CH(2)=7.33959/20.12587
DH(2)=1./20.12587
EH(2)=1./23.2725.58964
FH(2)=1./25.58964
AH(3)=6.22645/10.20708
BH(3)=1./10.20708
APP111060
APP111070
APP111080
APP111090
APP111100
APP111110
APP111120
APP111130
APP111140
APP111150
APP111160
APP111170
APP111180
APP111190
APP111200
APP111210
APP111220
APP111230
APP111240
APP111250
APP111260
APP111270
APP111280
APP111290
APP111300
APP111310
APP111320
APP111330
APP111340
APP111350
APP111360
APP111370
APP111380
APP111390
APP111400
APP111410
APP111420
APP111430
APP111440
APP111450
APP111460
APP111470
APP111480
APP111490
APP111500
APP111510
APP111520
APP111530

```

```

CH(3) = 5.50500/11.32080
DH(3) = 1.71132080
EH(3) = 3.70749/14.39417
FH(3) = 1.71439417
AH(4) = 5.00836/6.53253
BH(4) = 1.760400/7.24531
CH(4) = 4.40400/7.24531
DH(4) = 1.7724531
EH(4) = 2.96599/9.21227
FH(4) = 1.7921227

```

CCCCCCC C

```

SELECT THE HIGH PASS FILTER SETTING
FOR THE LOW FREQUENCY CUTOFF AT 0.04 HZ, SET I=1
FOR THE LOW FREQUENCY CUTOFF AT 0.06 HZ, SET I=3
FOR THE LOW FREQUENCY CUTOFF AT 0.08 HZ, SET I=3
FOR THE LOW FREQUENCY CUTOFF AT 0.10 HZ, SET I=4

```

```

I = 1
A1 = 1. + AH(I) * T/2. + BH(I) * (T**2) / 4.
B1 = -2. + BH(I) * (T**2) / 2.
C1 = 1. - AH(I) * T/2. + BH(I) * (T**2) / 4.
D1 = 1. + CH(I) * T/2. + DH(I) * (T**2) / 4.
E1 = -2. + CH(I) * (T**2) / 2.
F1 = 1. - CH(I) * T/2. + DH(I) * (T**2) / 4.
G1 = 1. + EH(I) * T/2. + FH(I) * (T**2) / 4.
H1 = -2. + EH(I) * (T**2) / 2.
I1 = 1. - EH(I) * T/2. + FH(I) * (T**2) / 4.

```

CCCC

```

CODE IS "ASHP1" MEANS "A1 COEFFICIENT FOR THE SELECTABLE HIGH
PASS FILTER"

```

```

ASHP1 = 1. / (A1 * D1 * G1)
ASHP2 = - (C1 / A1)
ASHP3 = - (B1 / A1)
ASHP4 = - (E1 / D1)
ASHP5 = - (F1 / D1)
ASHP6 = - (H1 / G1)
ASHP7 = - (I1 / G1)
WRITE(6,100) FREQH(I), ASHP1, ASHP2, ASHP3, ASHP4, ASHP5, ASHP6, ASHP7
FORMAT(1X,FREQ=,F5.3,ASHP1=,F19.16,ASHP2=,F19.16,ASHP3=,
F19.16,ASHP4=,F19.16,ASHP5=,F19.16,ASHP6=,F19.16,
ASHP7=,F19.16)

```

CCCCCCC

```

COEFFICIENTS FOR SELECTABLE LOW PASS FILTERS

```

```

FRQL(1) = 0.2
FRQL(2) = 0.4

```

```

APPI 1540
APPI 1550
APPI 1560
APPI 1570
APPI 1580
APPI 1590
APPI 1600
APPI 1610
APPI 1620
APPI 1630
APPI 1640
APPI 1650
APPI 1660
APPI 1670
APPI 1680
APPI 1690
APPI 1700
APPI 1710
APPI 1720
APPI 1730
APPI 1740
APPI 1750
APPI 1760
APPI 1770
APPI 1780
APPI 1790
APPI 1800
APPI 1810
APPI 1820
APPI 1830
APPI 1840
APPI 1850
APPI 1860
APPI 1870
APPI 1880
APPI 1890
APPI 1900
APPI 1910
APPI 1920
APPI 1930
APPI 1940
APPI 1950
APPI 1960
APPI 1970
APPI 1980
APPI 1990
APPI 2000
APPI 2010

```

```

FRQL(3)=0.6 C3492
AL(3)=1./0.358 04/0.03492
CL(3)=1./0. C3492
DL(3)=1./0.02779
FL(3)=1./0.206 96/0.02779
AL(1)=1./0.3143
CL(1)=1./0.3143
DL(1)=1./0.2501 2501
FL(1)=1./0.2501
AL(2)=1./0.07858
CL(2)=1./0.537 06/0.07858
DL(2)=1./0.06252
FL(2)=1./0.310 44/0.06252

```

```

SELECT LOW PASS FILTER SETTING AT 0.2 HZ; SET J=1
FOR THE HIGH FREQUENCY CUTOFF AT 0.4 HZ; SET J=2
FOR THE HIGH FREQUENCY CUTOFF AT 0.6 HZ; SET J=3

```

J=3

```

AI=AL(J)*(T**2)/4.
BI=A1
CI=AI
DI=DL(J)*(T**2)/4.
FI=DI
GI=(1.2.+BL(J))*T/2.+CL(J)*(T**2)/4.)
HI=(1.2.+BL(J))*T/2.+CL(J)*(T**2)/4.)
JI=(1.2.+BL(J))*T/2.+FL(J)*(T**2)/4.)
KI=(1.2.+FL(J))*T/2.+FL(J)*(T**2)/4.)
LISLP1=(GI*KI+HI*KI)/(GI*JI)
ASLP2=(HI*LI+HI*KI)/(GI*JI)
ASLP3=(HI*LI+HI*KI)/(GI*JI)
BSLP0=(AI*DEI+BI*EI)/(GI*JI)
BSLP1=(AI*DEI+BI*EI)/(GI*JI)
BSLP2=(AI*FFI+BI*EI)/(GI*JI)
BSLP3=(BI*FFI+CI*EI)/(GI*JI)

```

```

APPI 2020
APPI 2030
APPI 2040
APPI 2050
APPI 2060
APPI 2070
APPI 2080
APPI 2090
APPI 2100
APPI 2110
APPI 2120
APPI 2130
APPI 2140
APPI 2150
APPI 2160
APPI 2170
APPI 2180
APPI 2190
APPI 2200
APPI 2210
APPI 2220
APPI 2230
APPI 2240
APPI 2250
APPI 2260
APPI 2270
APPI 2280
APPI 2290
APPI 2300
APPI 2310
APPI 2320
APPI 2330
APPI 2340
APPI 2350
APPI 2360
APPI 2370
APPI 2380
APPI 2390
APPI 2400
APPI 2410
APPI 2420
APPI 2430
APPI 2440
APPI 2450
APPI 2460
APPI 2470
APPI 2480
APPI 2490

```

CCCCCCC C

```

BSLP4=(C1*F1)/(G1*J1)
WRITE(6,1001)FRQL(J),ASLP1,ASLP2,ASLP3,ASLP4,BSLP0,BSLP1,BSLP2,
$BSLP3,BSLP4
$FORMAT(1,X,F19.16,F19.16,/,BSLP0=,F19.16,BSLP1=,F19.16,
$,BSLP2=,F19.16,BSLP3=,F19.16,BSLP4=,F19.16)
DO 100 I=1,24576
SIG=ZFXI(I)
YO=BFHPI*SIG+BFHP2*SIG2+AFHP1*YO1+AFHP2*YO2
XI=AHP1*YO+AHP2*XI2+AHP3*XI1
XI1=XI+XI2-2*XI
XI11=XI1+ASHP4*XI11+ASHP5*XI112
XI1V=XI11-2*XI111+AHP6*XI1V1+AHP7*XI1V2
XV=XI1V+XV2-2*XV1
GPI=ASLP1*OUTFD1+ASLP2*OUTFD2+ASLP3*OUTFD3+ASLP4*OUTFD4
GP2=BSLP0*YPO+BSLP1*YPO1+BSLP2*YPO2+BSLP3*YPO3+BSLP4*YPO4
OUTFLD(I)=GPI+GP2
FINISHED COMPUTING THIS STEP'S VALUES FOR AMPLITUDES
INCREMENT STORAGE REGISTERS
SIG2=SIG1
SIG1=SIG
YO2=YO1
YO1=YO
XI2=XI1
XI11=XI1
XI112=XI11
XV1=XV
YPO4=YPO3
YPO3=YPO2
YPO2=YPO1
YPO1=YPO
OUTFD4=OUTFD3
OUTFD3=OUTFD2
OUTFD2=OUTFD1
OUTFD1=OUTFLD(I)
FINISHED INCREMENTING STORAGE REGISTERS
100 CONTINUE
XMAXP=TIME2(16384)
VERSATEC PLOT OF B - FIELD SPECTRA

```

```

APPI 2500
APPI 2510
APPI 2520
APPI 2530
APPI 2540
APPI 2550
APPI 2560
APPI 2570
APPI 2580
APPI 2590
APPI 2600
APPI 2610
APPI 2620
APPI 2630
APPI 2640
APPI 2650
APPI 2660
APPI 2670
APPI 2680
APPI 2690
APPI 2700
APPI 2710
APPI 2720
APPI 2730
APPI 2740
APPI 2750
APPI 2760
APPI 2770
APPI 2780
APPI 2790
APPI 2800
APPI 2810
APPI 2820
APPI 2830
APPI 2840
APPI 2850
APPI 2860
APPI 2870
APPI 2880
APPI 2890
APPI 2900
APPI 2910
APPI 2920
APPI 2930
APPI 2940
APPI 2950
APPI 2960
APPI 2970

```

```

C      NPIS=1020./CELTAT +1.
C      NPIS=24576
C      NPIS, NPTS, DETERMINES NUMBER OF POINTS NECESSARY IN ORDER FOR
C      THE RANGE TO BE PLOTTED.
C      FOR THE SECS RANGE TO BE PLOTTED.
C      FOR THE FOLLOWING, ITB, AND RTB, VALUES REVIEW THE WRITE-UP
C      FOR THE SUBROUTINE PROCEDURE 'DRAWP'.
      ITB(3)=8
      ITB(4)=4
      ITB(7)=1
      ITB(12)=0
      RTB(1)=0.0
      RTB(2)=0.0
      RTB(3)=ALAB(1)
      READ(5,3000)ITILE
C      DRAW THE COIL ANTENNA TOTAL FIELD DATA SERIES
      CALL DRAWP(NPTS,TIME2,ZZX1,ITB,RTB)
      RTB(3)=ALAB(2)
      READ(5,3000)ITILE
C      DRAW THE ASQ81 TOTAL FIELD DATA SERIES
      CALL DRAWP(NPTS,TIME2,ZZY1,ITB,RTB)
      RTB(3)=ALAB(3)
      READ(5,3000)ITILE
C      DRAW THE SCHONSTEDT COIL FIELD DATA SERIES
      CALL DRAWP(NPTS,TIME2,ZZV1,ITB,RTB)
      RTB(3)=ALAB(4)
      READ(5,3000)ITILE
C      DRAW THE PROGRAM OUTPUT TOTAL FIELD DATA SERIES
      CALL DRAWP(NPTS,TIME2,OUTFLD,ITB,RTB)
C      DRAW THE RAW COIL TIME SERIES DATA
      RTB(3)=ALAB(4)
      READ(5,3000)ITILE
      CALL DRAWP(NPTS,TIME2,CLFLD,ITB,RTB)
      CONTINUE
      FORMAT('I6A8)
      200
      3000
      STOP
      END
      SUBROUTINE RD(IUN,IO,IRS,IREC,IKQ)
C

```

```

APP12980
APP12990
APP13000
APP13010
APP13020
APP13030
APP13040
APP13050
APP13060
APP13070
APP13080
APP13090
APP13100
APP13110
APP13120
APP13130
APP13140
APP13150
APP13160
APP13170
APP13180
APP13190
APP13200
APP13210
APP13220
APP13230
APP13240
APP13250
APP13260
APP13270
APP13280
APP13290
APP13300
APP13310
APP13320
APP13330
APP13340
APP13350
APP13360
APP13370
APP13380
APP13390
APP13400
APP13410
APP13420
APP13430
APP13440
APP13450

```

APPI 3460
 APPI 3470
 APPI 3480
 APPI 3490
 APPI 3500
 APPI 3510
 APPI 3520
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 APPI 3550
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 APPI 3570
 APPI 3580
 APPI 3590
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 APPI 3610
 APPI 3620
 APPI 3630
 APPI 3640
 APPI 3650
 APPI 3660
 APPI 3670
 APPI 3680
 APPI 3690
 APPI 3700
 APPI 3710
 APPI 3720
 APPI 3730
 APPI 3740
 APPI 3750
 APPI 3760
 APPI 3770
 APPI 3780
 APPI 3790
 APPI 3800
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 APPI 3880
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 APPI 3920
 APPI 3930

```

THIS PROCEDURE FURNISHED BY DR. TIM STANTON,
DEPARTMENT OF OCEANOGRAPHY.

READ DATA FROM IUN, ALLIGN , CHECK & RETURN

IUN=TAPE NUMBER, EG 20
IO=INTEGER#2 ARRAY, I6 LONG, (VALUES 0-4095, SUBTRACT 2048)*5
/2028. GIVES VOLTAGE
IRS= NUMBER OF RESINCS ALLOWED (ERRORS)
IREC= COUNTER OF RECORDS (FRAMES OF DATA)
      BLOCK 512 BITS,
      800 BPI TAPE UNLABELED
IRQ= NUMBER OF ACTUAL RESINCS (ERRORS)

INTEGER * 2 IO(16),IP(16)
DATA IRR /0/
IF ( IREC.EQ.0) IS=0
IF (IS.NE.0) GO TO 50
IF READ (IUN,20,END=900) IP
IS=IS+1
IF (IS.LT. 17) GO TO 50
IREC=IREC+1
ICH=IMASK(IP(15),3,0)+1
WRITE (6,5) ICH,IS,IUN,IREC
FORMAT ( ' RESYNCHING ICH,IS,IUN,IREC ',4I8)
IF ( ICH.NE.1) GO TO 40
DO 100 I=1,16
O(I)=ISHIFT(IP(15),4)
IF=IMASK(IP(15),3,0)+1
IFR=(ICR+1) GO TO 80
WRITE (6,70) IUN,IREC I,ICH,IER
FORMAT ( ' UNIT ',13, ' RECORD ',16, 'CHAN & DATA CH ',2I4,
, ERRORS ', 17)
IS=IS+1
IF (IS.LT. 17) GO TO 100
IREC=IREC+1
ICONT INUE
  
```

CCCCCCCCCCCC
 20
 40
 50
 C 55
 C
 70
 80
 100
 C

APPI 3940
 APPI 3950
 APPI 3960
 APPI 3970
 APPI 3980
 APPI 3990
 APPI 4000
 APPI 4010
 APPI 4020
 APPI 4030
 APPI 4040
 APPI 4050
 APPI 4060
 APPI 4070
 APPI 4080
 APPI 4090
 APPI 4100
 APPI 4110
 APPI 4120
 APPI 4130
 APPI 4140
 APPI 4150
 APPI 4160
 APPI 4170
 APPI 4180
 APPI 4190
 APPI 4200
 APPI 4210
 APPI 4220
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 APPI 4270
 APPI 4280
 APPI 4290
 APPI 4300
 APPI 4310
 APPI 4320
 APPI 4330
 APPI 4340
 APPI 4350
 APPI 4360
 APPI 4370
 APPI 4380
 APPI 4390
 APPI 4400
 APPI 4410

```

110 IF ( IER.EQ.0) GO TO 150
    IRR=IRR+1
    IF (IRR.LT.IRS) GO TO 120
    IF ITET (6,1,10)
    FORMAT (':') STOPPED IN SUB RD BECAUSE OF IRR.GT.,I6,' AT L110.'
    IRR=IRR
    STOP
120 CONTINUE
    WRITE (6,130) IREC,IRR
    FORMAT (':') RESYNC AT FRAME ',I6,' WITH TOTAL ERRORS ',I7)
    IRR=0
    GO TO 50
130 CONTINUE
    RETURN
150 WRITE (6,910) IUN,IREC
    FORMAT (':') END OF UNIT ',I3,' AT REC ',I7)
    STOP
    END
C
C
C
FUNCTION ISHIFT (IN,NPLC)
  RETURNS SHIFTED VALUE OF I*2 WORD IN
  -VE LEFT,+VE RIGHT SHIFT
C
C
INTEGER * 2 IN
IP=IN
IP.LT.0) IP=IP+65536
IF (NPLC.LT.0) GO TO 30
ISHIFT=IP/(2**IABS(NPLC))
RETURN
ISHIFT=IP*(2**IABS(NPLC))
IF (ISHIFT.GT.65535) ISHIFT=MOD(ISHIFT,65536)
RETURN
FUNCTION IMASK (IN,IBL,IBR)
  MASK I*2 WORD IN OUTSIDE BITS IBL & IBR
C
C
INTEGER * 2 IN,IO
IO=IN
IF (IBR.EQ.0) GO TO 50
IT=ISHIFT(IN,IBR)
IO=IT
IP=ISHIFT(IO,IBL-15-IBR)
IO=IP
IMASK=ISHIFT(IO,15-IBL)
RETURN
END
SUBROUTINE FOURT
C
  
```

APPI 4420
APPI 4430
APPI 4440
APPI 4450
APPI 4460
APPI 4470
APPI 4480
APPI 4490
APPI 4500
APPI 4510
APPI 4520
APPI 4530
APPI 4540
APPI 4550
APPI 4560
APPI 4570
APPI 4580
APPI 4590
APPI 4600
APPI 4610
APPI 4620
APPI 4630
APPI 4640
APPI 4650
APPI 4660
APPI 4670
APPI 4680
APPI 4690
APPI 4700
APPI 4710
APPI 4720
APPI 4730
APPI 4740
APPI 4750
APPI 4760
APPI 4770
APPI 4780
APPI 4790
APPI 4800
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APPI 4820
APPI 4830
APPI 4840
APPI 4850
APPI 4860
APPI 4870
APPI 4880
APPI 4890

PURPOSE

SUBROUTINE FOURT COMPUTES THE FORWARD AND INVERSE FOURIER TRANSFORM OF THE CONTENTS OF THE COOLEY-TUKEY FAST DATA A SINGLE-DIMENSIONED ARRAY OF LENGTH L. THE JTH COMPONENT OF THE TRANSFORM IS GIVEN BY $SUM(DATA(K)*W**((K-1)*(J-1)))$ WHERE THE SUM IS TAKEN OVER K, 1 .LE. K .LE. L, AND $W=EXP(ISIGN*2*PI*SQRT(-1)/L)$

THE VALUE OF ISIGN DEPENDS UPON WHETHER A FORWARD OR INVERSE TRANSFORM IS TO BE PERFORMED. FOURT MAY ALSO BE USED ON A MULTI-DIMENSIONAL ARRAY, IN WHICH CASE A FOURIER TRANSFORM IS PERFORMED ALONG EACH DIMENSION IN TURN.

CALLING SEQUENCE

CALL FOURT(DATA,NN,NDIM,ISIGN,IFORM,WORK)

DESCRIPTION OF ARGUMENTS

DATA COMPLEX*8 MULTI-DIMENSIONAL ARRAY CONTAINING THE DATA TO BE TRANSFORMED. ON OUTPUT DATA CONTAINS THE TRANSFORM, NORMAL FORTRAN ORDERING IS EXPECTED, THE FIRST SUBSCRIPT CHANGING THE FASTEST.

NN INTEGER*4 ARRAY CONTAINING THE DIMENSIONS OF THE ARRAY DATA.

NDIM NUMBER OF DIMENSIONS OF THE ARRAY DATA = NUMBER OF ELEMENTS IN THE ARRAY NN.

ISIGN INTEGER INDICATING WHETHER FORWARD OR INVERSE TRANSFORM IS TO BE PERFORMED.
ISIGN=-1 FOR FORWARD TRANSFORM.
ISIGN=1 FOR INVERSE TRANSFORM.
NOTE: THESE DEFINITIONS ARE NOT STANDARDIZED. IN PARTICULAR, THE DEFINITIONS OF FORWARD AND INVERSE TRANSFORM ARE REVERSED IN THE IMSL FFT ROUTINES.

IFORM AN INTEGER INDICATING WHETHER OR NOT DATA CONTAINS ONLY PURELY REAL VALUES.
IFORM=0 IF DATA IS PURELY REAL
IFORM=1 OTHERWISE.
IF IFORM IS SET TO 0, ALL THE IMAGINARY PARTS OF THE ELEMENTS IN DATA MUST BE SET TO 0.0.

APPI 4900
 APPI 4910
 APPI 4920
 APPI 4930
 APPI 4940
 APPI 4950
 APPI 4960
 APPI 4970
 APPI 4980
 APPI 4990
 APPI 5000
 APPI 5010
 APPI 5020
 APPI 5030
 APPI 5040
 APPI 5050
 APPI 5060
 APPI 5070
 APPI 5080
 APPI 5090
 APPI 5100
 APPI 5110
 APPI 5120
 APPI 5130
 APPI 5140
 APPI 5150
 APPI 5160
 APPI 5170
 APPI 5180
 APPI 5190
 APPI 5200
 APPI 5210
 APPI 5220
 APPI 5230
 APPI 5240
 APPI 5250
 APPI 5260
 APPI 5270
 APPI 5280
 APPI 5290
 APPI 5300
 APPI 5310
 APPI 5320
 APPI 5330
 APPI 5340
 APPI 5350
 APPI 5370

WORK A 1-DIMENSIONAL REAL*4 ARRAY USED FOR WORKING STORAGE.
 ITS LENGTH SHOULD BE TWICE THE LARGEST ARRAY OF DIMENSION
 NN(I), I=1,2 IF .INDIM, WHICH IS NOT A POWER OF TWO, IN
 PARTIALLY, IF ALL NN(I) ARE POWERS OF TWO, NO WORK SPACE
 IS NEEDED AND WORK MAY BE REPLACED BY ZERO IN THE CALLING
 SEQUENCE.

REMARKS

IF AN INVERSE TRANSFORM (ISIGN=+1) IS PERFORMED UPON AN ARRAY
 OF TRANSFORMED (ISIGN=-1) DATA, THE ORIGINAL DATA WILL REAP-
 PEAR, MULTIPLIED BY NN(1)*NN(2)*...*NN(NDIM).

FOR A MULTI-DIMENSIONAL ARRAY THE (J1, J2, ..., JNDIM)
 COMPONENT OF THE TRANSFORM IS GIVEN BY ((J1-1))*
 SUM(DATA(I1, I2, ..., I, INDIM))*W1M**((INDIM-1))*
 W2**((I2-1))*((J2-1))*...*WNDIM**((INDIM-1))*
 HERE THE SUM RANGE*2*PI*SQRT((-1)/NN(I)), ETC.

THE ARRAY OF INPUT DATA MUST BE IN COMPLEX FORMAT. THE DATA
 HOWEVER, IS ALL REAL. RUNNING TIME IS CUT UP TO FORTY PER-
 CENT. (FOR FASTEST TRANSFORM OF REAL DATA, NN(I) SHOULD BE E-
 VEN. THE TRANSFORM VALUES ARE ALWAYS COMPLEX AND ARE RETURNED
 IN THE ORIGINAL ARRAYS OF DATA, REPLACING THE INPUT DATA. THE
 LENGTH OF EACH DIMENSION OF THE DATA ARRAY MAY BE ANY INTEGER.
 THE PROGRAM RUNS FASTER ON COMPOSERS RICH IN PRIMES,
 AND IS PARTICULARLY FAST ON NUMBERS RICH IN FACTORS OF TWO.

TIME IS IN FACT GIVEN BY THE FOLLOWING FORMULA. LET N NOT BE
 THE TOTAL NUMBER OF POINTS (REAL OR COMPLEX) IN THE DATA ARRAY.
 THAT IS, NOT=NN(1)*NN(2)*...*NN(K2)*5**K3. LET SUM2 BE THE
 FACTORS OF TWO IN N. THAT IS, SUM2 = 2**K2. LET SUMF =
 SUMF BE THE SUM OF ALL OTHER FACTORS OF N. THAT IS, SUMF =
 3**K3*5**K5*. DATA IS TAKEN BY A MULTI-DIMENSIONAL TRANSFORM ON
 THESE N NOT. DATA IS POINT ADD TIME = (T1+T2*SUM2+T3*SUMF). T = 3000+
 CD3300 (FLOATING POINT MICROSECONDS). T = 3000+
 NDOT*(600+40*SUM2+175*SUMF) MICROSECONDS ON COMPLEX DATA.

THE SAVINGS OFFERED BY THIS PROGRAM CAN BE DRAMATIC. A ONE-DI-
 MENSIONAL ARRAY 4000 IN LENGTH WILL BE TRANSFORMED IN 4000*(600+
 40*(2+2+2+2)+175*(5+5+5)) = 14.5 SECONDS VERSUS ABOUT 4000*
 4000*175 = 280 SECONDS FOR THE STRAIGHTFORWARD TECHNIQUE.

THE FAST FOURIER TRANSFORM PLACES THREE RESTRICTIONS UPON THE
 DATA.



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1. THE NUMBER OF INPUT DATA AND THE NUMBER OF TRANSFORM VALUES MUST BE THE SAME.
2. THE INPUT DATA AND THE TRANSFORM VALUES MUST REPRESENT EQUISPACED POINTS IN THESE RESPECTIVE DOMAINS OF TIME AND FREQUENCY. CALLING DELTAF AND DELTAF, IT MUST BE TRUE THAT DELTAF=2*PI/(NN(I)*DELTAF). OF COURSE, DELTAF NEED NOT BE THE SAME INPUT DIMENSION. TRANSFORM OUTPUT REPRESENTS AT LEAST ONE CYCLE OF PERIODIC FUNCTIONS.

THERE ARE NO ERROR MESSAGES OR ERROR HALTS IN THIS PROGRAM. THE PROGRAM RETURNS IMMEDIATELY IF NDIM OR ANY NN(I) IS LESS THAN ONE.

FOR MOST APPLICATIONS FOURT, IF COMPILED UNDER FORTRAN H, IS COMPARABLE IN SPEED AND ACCURACY TO THE IMSL FFT SUBROUTINES. WITH CERTAIN PATHOLOGICAL ILL-CONDITIONED DATA THE ACCURACY OF FOURT MAY BE SERIOUSLY DEGRADED, BUT THE SAME CAN PROBABLY BE SAID OF ANY EXTANT FFT ROUTINE. WORK SPACE REQUIRED BY FOURT MAY BE GREATER OR LESS THAN THAT REQUIRED BY THE IMSL ROUTINES, GENERAL EASIER TO USE THAN THE FOURT IS MORE FLEXIBLE AND IN GENERAL EASIER TO USE THAN THE IMSL ROUTINES. FOURT ALONE PROVIDES THE CAPABILITY OF TRANSFORMING A MULTI-DIMENSIONAL ARRAY WITH A SINGLE CALL.

THIS IS THE FASTEST AND MOST VERSATILE VERSION OF THE FFT KNOWN TO THE AUTHOR. A PROGRAM CALLED FOUR2 IS AVAILABLE THAT ALSO PERFORMS THE FAST FOURIER TRANSFORM AND IS WRITTEN IN USASIBASIC FORTRAN. IT IS ABOUT ONE THIRD AS LONG AND REQUIRES THE DIMENSIONS OF THE INPUT ARRAY (WHICH MUST BE COMPLEX) TO BE POWERS OF TWO. ANOTHER PROGRAM, CALLED FOUR1, IS ONE TENTH AS LONG AND RUNS TWO THIRDS AS FAST ON A ONE-DIMENSIONAL COMPLEX ARRAY WHOSE LENGTH IS A POWER OF TWO.

REFERENCE--
 IEEE AUDIO TRANSACTIONS (JUNE 1967), SPECIAL ISSUE ON THE FFT.

EXAMPLE 1. THREE-DIMENSIONAL FORWARD FOURIER TRANSFORM OF A COMPLEX ARRAY DIMENSIONED 32 BY 25 BY 13 IN FORTRAN IV.
 DIMENSION DATA(32,25,13),WORK(50),NN(3)
 COMPLEX DATA
 DATA NN/32,25,13/
 DO I=1,32
 DO J=1,25
 DO K=1,13
 DATA(I,J,K)=COMPLEX VALUE
 CALL FOURT(DATA,NN,3,-1,I,WORK)

```

EXAMPLE 2. ONE-DIMENSIONAL FORWARD TRANSFORM OF A REAL ARRAY OF
LENGTH 64 IN FORTRAN II
DIMENSION DATA(2,64)
DO 2 I=1,64 REAL PART
DATA(1,I)=0
DATA(2,I)=0
CALL FOURT(DATA,64,1,-1,0,0)
PROGRAMMER

PROGRAM BY NORMAN BRENNER FROM THE BASIC PROGRAM BY CHARLES
RADER JUNE 1967. THE IDEA FOR THE DIGIT REVERSAL WAS
SUGGESTED BY RALPH ALTER.
DOCUMENTATION REVISED BY JOANNE BOGART, AUGUST 1979, NPS.

SUBROUTINE FOURT(DATA,NN,NDIM,ISIGN,IFORM,WORK)
DIMENSION DATA(1),NN(1),IFACT(32),WORK(1)
DATA IWOPI/6.2831853071796/,RTHLF/0.70710678118655/
IF(NDIM-1)920,1,1
NTOT=2
DO 2 I=1,NDIM
IF(NN(I)0)920,2
NTOT=NTOT*NN(I)
MAIN LOOP FOR EACH DIMENSION
NP1=2
DO 910 I=1,NDIM
N=NN(I)
NP2=NP1*N
IF(N-1)920,900,5
IS N A POWER OF TWO AND IF NOT, WHAT ARE ITS FACTORS
M=N
NTWO=NP1
IF=1
IDIV=2
IQUOT=M/IDIV
IREM=N-IDIV*IQUOT
IF(IREM)20,12,20
NTWO=NTWO+NTWO
IFACT(IF)=IDIV
IF=IF+1
M=IQUOT
GO TO 10
IDIV=3

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30  INQN2=IF IDIV
    IQUOT=M/IDIV#IQUOT
    IREM=M-IDIV#IQUOT
31  IF(IREM)40,31,31
32  IF(FACT(I,F)=IDIV
    M=IF+1
    GO TO 30
40  IDIV=IDIV+2
    GO TO 30
50  INQN2=IF
    IF(IREM)60,51,60
51  NTWO=NTWO+NTWO
    GO TO 70
60  IF(FACT(I,F)=M

```

SEPARATE FOUR CASES---
 1. COMPLEX TRANSFORM OR REAL TRANSFORM FOR THE 4TH, 9TH, ETC.
 DIMENSIONS.
 2. REAL TRANSFORM FOR THE 2ND OR 3RD DIMENSION. METHOD---
 TRANSFORM HALF THE DATA, SUPPLYING THE OTHER HALF BY CON-
 JUGATE SYMMETRY.
 3. REAL TRANSFORM FOR THE 1ST DIMENSION, N ODD. METHOD---
 SET THE IMAGINARY PARTS TO ZERO.
 4. REAL TRANSFORM FOR THE 1ST DIMENSION, N EVEN. METHOD---
 TRANSFORM A COMPLEXED ARRAY OF LENGTH N/2 WHOSE REAL PARTS
 ARE THE EVEN NUMBERED REAL VALUES AND WHOSE IMAGINARY
 PARTS ARE THE ODD NUMBERED REAL VALUES. SEPARATE AND SUP-
 PLY THE SECOND HALF BY CONJUGATE SYMMETRY.

```

70  ICASE=1
    IF(MIN=NPI
    IIRNG=NP1-4)71,100,100
    IF(IFORM)72,72,100
71  ICASE=2
    IIRNG=NP0*(1+NPREV/2)
72  IF(IIDIM-1)73,73,100
    ICASE=3
73  IIRNG=NP1
    IF(NTWO=NP1)100,100,74
    ICASE=4
74  IF(MIN=2
    NTWO=NTWO/2
    NP2=NP2/2
    NTOT=NTOT/2

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80      I=1      J=1,NTOT
      DATA(J)=DATA(I)
      I=I+2
      SHUFFLE DATA BY BIT REVERSAL, SINCE N=2**K. AS THE SHUFFLING
      CAN BE DONE BY SIMPLE INTERCHANGE, NO WORKING ARRAY IS NEEDED
      IF (NTWO-NP2)200,110,110
      NP2HF=NP2/2
      J=1
      DO 150 I2=1,NP2,NP1
      IF (J-I2)120,130,130
      I1 MAX=I2+NP1-2
      DO 125 I1=I2,11 MAX,2
      DO I25 I3=I1,NTOT,NP2
      J3=J+I3-12
      TEMPR=DATA(I3)
      TEMP1=DATA(I3+1)
      DATA(I3)=DATA(J3)
      DATA(I3+1)=TEMPR
      DATA(J3)=TEMP1
      DATA(NP2HF)
      M=NP2HF
      IF (J-M)150,150,145
      J=J-M
      M=M/2
      IF (M-NP1)150,140,140
      J=J+M
      GO TO 300
      SHUFFLE DATA BY DIGIT REVERSAL FOR GENERAL NG ARRAY IS NEEDED
      NWORK=2*N
      DO 270 I1=1,NP1,2
      DO 270 I3=I1,NTOT,NP2
      J=I3
      DO 260 I=1,NWORK,2
      IF (ICASE-3)210,220,210
      IF (K(I)=DATA(J))
      WORK(I+1)=DATA(J+I)
      GO TO 230
      WORK(I)=DATA(J)
      WORK(I+1)=0.
      IF P2=NP2
      IF P1=IFP1
      IF P1=IFP1
      J=J+I
  
```

```

250 IF (J-I3-IFP2)260,250,250
    JFP2=IFP1
260 IF=IF+1
    IF=IFP2-NP1)260,260,240
    CONTINUE
    I2MAX=I3+NP2-NP1
    I=1
    DO 270 I2=I3,I2MAX,NP1
        DATA(I2)=WORK(I)
        DATA(I2+1)=WORK(I+1)
        I=I+2
270 C
C
C
C
C
300 MAIN LOOP FOR FACTORS OF TWO. PERFORM FOURIER TRANSFORMS OF
305 LENGTH FOUR, WITH ONE OF LENGTH TWO IF NEEDED. THE TWIDDLE FAC-
310 TOR W=EXP(I*SIGN*2*PI*SQR((-1)**M/(4*MMAX))). CHECK FOR W=ISIGN*
320 SQR((-1)
330 IF (NTWO-NP1)600,600,305
    NP1TW=NP1+NP1
    IPAR=NTWO/NP1
    IF (IPAR-2)350,330,320
    IPAR=IPAR/4
    GO TO 310
    DO 340 I1=1,I1RNG,2
        DO 350 K1=1,INTOT,NP1TW
            K2=K1+NP1
            TEMPR=DATA(K2)
            TEMP1=DATA(K1)
            DATA(K2)=DATA(K1)-TEMPR
            DATA(K1)=DATA(K1)+TEMPR
            DATA(K1+1)=DATA(K1+1)+TEMP1
            DATA(K1+1)=TEMP1
            MMAX=NP1
        IF (MMAX-NTWO/2)370,600,600
        LMAX=MAX0(NP1TW,MMAX/2)
        DO 570 L=NP1,LMAX,NP1TW
            M=L
            IF (MMAX-NP1)420,420,380
            IF (ISIGN)400,390,390
            THETA=THETA
            WR=COS(THETA)
            W1=SIGN(WR-W1,W1)
            W2 I=2.*WR*W1
            W3 I=W2R+W1+W2I*WR
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350
360
370
380
390
400
410

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APP17300
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420 DO 530 I1=1, I1RNG, 2
 KM IN=I1+IPAR*MM
 IF (MMAX-NPI)430,430,440
 430 KM IN=IPAR*MMAX
 440 KDI EP=4*KDI F
 450 IF (KSTEP-NI*WO)460,460,530
 460 DO 520 K1=KMIN, NTO, KSTEP
 K2=K1+KDIF
 K3=K2+KDIF
 K4=K3+KDIF
 470 IF (MMAX-NPI)470,47 C,480
 U1R=DATA(K1)+DATA(K2)
 U2R=DATA(K3)+DATA(K4)
 U3R=DATA(K1)+DATA(K2)
 U4R=DATA(K3)+DATA(K4)
 471 IF (ISIGN)471,472,472
 U4I=DATA(K3)+DATA(K4)
 U4I=DATA(K3)-DATA(K4)
 472 U4I=DATA(K3)-DATA(K4)
 U4I=DATA(K3)-DATA(K4)
 480 G0 TO 510
 T2I=W2R*DATA(K2)+W2I*DATA(K2)
 T3I=W3R*DATA(K3)+W3I*DATA(K3)
 T4I=W4R*DATA(K4)+W4I*DATA(K4)
 U1I=DATA(K1)+T2I
 U2I=DATA(K1)+T3I
 U3I=DATA(K1)+T4I
 IF (ISIGN)490,500,500
 490 U4I=DATA(K1)+T2I
 U4I=DATA(K1)+T3I
 500 G0 TO 431
 510 U4I=DATA(K1)+T4I
 DATA(K1)=U1R+U2I
 DATA(K2)=U3R+U4I
 DATA(K3)=U1R-U2R

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520 DATA(K3+1)=U11-U2I
DATA(K4)=U3R-U4R
DATA(K4+1)=U3I-U4I
K0IF=KSTEP
KMIN=4*(KMIN-11)+11
GO TO 450
CONTINUE
M=MLMAX
IF(M-MMAX)540,540,570
IF(ISIGN)550,560,560
TEMPR=WR
WR=(WR+WII)*RTHLF
WI=(WI-TEMPR)*RTHLF
GO TO 410
TEMPR=WR
WR=(WR-WRI)*RTHLF
WI=(TE+WI)*RTHLF
GO TO 410
CONTINUE
IPAR=3-IPAR
MMAX=MMAX+MMAX
GO TO 360

530
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C C C C C
600 MAIN LOOP FOR FACTORS NOT EQUAL TO TWO. APPLY THE TWIDDLE FAC-
605 TOR W=EXP(I SIGN #2*PI*SQRT(-1))*(J1-1)*((IFP1+IFP2))
610 THEN PERFORM A FOURIER TRANSFORM OF LENGTH IFACT(IF), MAKING USE
615 OF CONJUGATE SYMMETRIES.
IF(NTWO-NP2)605,700,700
IFPI=NTWO
IF=INON2
NP1HF=IFACT(IF)*IFP1
J1MIN=NP1+1
IF(J1MIN-IFPI)615,615,640
DO 635 J1=J1MIN,IFPI,NP1
THETA=-TWOP1*FLOAT(J1-1)/FLOAT(IFP2)
IF(ISIGN)625,620,620
THETPR=COS(THETA)
WSTPI=SIN(THETA)
WR=WSTPI
WI=WSTPI+IFP1
J2MAX=J1+IFP2-IFP1
DO 635 J2=J2MIN,J2MAX,IFP1
I1MAX=J2+I1RNG-2
I1=I1J2,I1MAX,2
DD 630 I1=I1J2,I1MAX,2

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630      J3=I1,NTOT,IFP2
        TEMPR=DATA(J3)
        DATA(J3)=DATA(J3)*WR-DATA(J3+1)*WI
        DATA(J3+1)=TEMPR*WI+DATA(J3+1)*WR
        TEMPR=WR
        WI=WR*WSTPR-WI*WSTPI
        WTI=TEMPR*WSTPI+WI*WSTPR
        IF(ISIGN)650,645,645
        WTI=WTI-COS(THETA)
        WSTPR=IFPI*(I+IFACT(I)/2)
        DO 695      I1=I1,IRNG,2
        J2 MAX= I3+J2RNG-IFP1
        DO 690      J2=I3,J2MAX,IFP1
        J1 MAX= J2+IFP1-NP1
        DO 680      J1=J2,J1MAX,NP1
        J3 MAX= J1+NP2-IFP2
        DO 680      J3=J1,J3MAX,IFP2
        JMIN=J3-J2+I3
        JMAX=JMIN+IFP2-IFP1
        I=I+(J3-I3)/NP1HF
        IF(J2-I3)655,665
        SUMR=0.
        SUMI=0.
        DO 660      J=JMIN,JMAX,IFP1
        SUMR=SUMR+DATA(J)
        SUMI=SUMI+DATA(J+1)
        WORK(I)=SUMR
        WORK(I+1)=SUMI
        GO TO 680
        ICONJ=I+(IFP2-2*J2+I3+J3)/NP1HF
        J=JMAX DATA(J)
        SUMI=DATA(J+1)
        OLD DSR=0.
        J=J-IFP1
        TEMPR=SUMR
        SUMR=TWOWR*SUMR-OLD DSR+DATA(J)
        TEMPI=SUMI
        SUMI=TWOWR*SUMI-OLD DSI+DATA(J+1)
        OLD DSR=TEMPR
        OLD DSI=TEMPI
        J=J-IFP1
        IF(J-JMIN)675,675,670
  
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675 TEMPR=WR*SUMR-OLDSR+DATA(J)
    TEMPI=WI*SUMI
    WORK(I)=TEMPR-TEMPI
    WORK(I*CONJ)=TEMPR+TEMPI
    TEMPR=WR*SUMR-OLDSR+DATA(J+1)
    TEMPI=WI*SUMI
    WORK(I+1)=TEMPR+TEMPI
    WORK(I*CONJ+1)=TEMPR-TEMPI
    CONTINUE
    IF(J2-I3)685,686
685 WR=WSTPI
    WI=TO 690
    TEMPR=WR*WSTPR-WI*WSTPI
    WI=WR*WSTPR+WI*WSTPR
    TOWR=WR+WR
    I=I+1
    I2MAX=I3+NP2-NP1
    DO 695 I2=I3,I2MAX,NP1
    DATA(I2)=WORK(I)
    DATA(I2+1)=WORK(I+1)
    I=I+2
    IF=IF+1
    IFPI=IFP2
    IF(IFP1-NP2)610,700,700
    COMPLETE A REAL TRANSFORM IN THE 1ST DIMENSION, N EVEN, BY CON-
    JUGATE SYMMETRIES.
    GO TO (900,800,900,701),ICASE
700 NHALF=N
701 N=NH+N
    THETA=-TWOP/IFLOAT(N)
    IF(ISA=703,702,702)
    THETA=-THETA
    WSTPR=COS(THETA)
    WSTPI=SIN(THETA)
    WR=WSTPI
    WI=WSTPI
    IMIN=3*NHALF-1
    JM TO 725
    J=JMIN
    DO 720 I=IMIN,NTOT,NP2
    SUMR=(DATA(I)+DATA(J))/2.
    SUMI=(DATA(I)-DATA(J))/2.
    DI FR=
  
```

APP19700
 APP19710
 APP19720
 APP19730
 APP19740
 APP19750
 APP19760
 APP19770
 APP19780
 APP19790
 APP19800
 APP19810
 APP19820
 APP19830
 APP19840
 APP19850
 APP19860
 APP19870
 APP19880
 APP19890
 APP19900
 APP19910
 APP19920
 APP19930
 APP19940
 APP19950
 APP19960
 APP19970
 APP19980
 APP19990
 APP20000
 APP20010
 APP20020
 APP20030
 APP20040
 APP20050
 APP20060
 APP20070
 APP20080
 APP20090
 APP20100
 APP20110
 APP20120
 APP20130
 APP20140
 APP20150
 APP20160
 APP20170

```

DI FI = (DATA(I+1) - DATA(J+1))/2.
TE MPI = WR*SUMI + WI*DI*IFR
DATA(I+1) = SUMR + TI + TEMPR I
DATA(J+1) = SUMR - TEMPR I
DATA(J+1) = -DI*FI + TEMPI
J = J + NP2
JM IN = JM IN + 2
JM IN = JM IN - 2
TE MPI = WR*STPR - WI*WSTPR
WR = WR*WSTPR + WI*WSTPR
IF (ISIGN(J), 740, 740)
DO TA(I+1) = INTOT + NP2
NP2 = NP2 + NP2
NTOT = NTOT + NTOT
JM IN = NTOT / 2 + 1
JM IN = JM IN - 2 * NHALF
I = JM IN
GO TO 755
DATA(I) = DATA(I+1)
DATA(J+1) = -DATA(I+1)
I = I + 2
J = J - 2
IF (I - JM IN) 750, 760, 760
DATA(J) = DATA(J+1)
DATA(J+1) = 0
IF (I - J) 770, 780, 780
DATA(I) = DATA(I)
I = I - 2
J = J - 2
IF (I - JM IN) 775, 765, 765
DATA(J) = DATA(J+1) + DATA(J+1)
DATA(J+1) = 0.
JM IN = JM IN
GO TO 745
DATA(1) = DATA(1) + DATA(2)
DATA(2) = 0.
GO TO 900

```

720
 725
 730
 735
 740
 745
 750
 755
 760
 765
 770
 775
 780
 800

COMPLETE A REAL TRANSFORM FOR THE 2ND OR 3RD DIMENSION BY
 CONJUGATE SYMMETRIES.
 C
 C
 C

APP20180
 APP20190
 APP20200
 APP20210
 APP20220
 APP20230
 APP20240
 APP20250
 APP20260
 APP20270
 APP20280
 APP20290
 APP20300
 APP20310
 APP20320
 APP20330
 APP20340
 APP20350
 APP20360
 APP20370
 APP20380
 APP20390
 APP20400
 APP20410
 APP20420
 APP20430
 APP20440
 APP20450
 APP20460
 APP20470
 APP20480
 APP20490
 APP20500
 APP20510
 APP20520
 APP20530
 APP20540
 APP20550
 APP20560
 APP20570
 APP20580
 APP20590
 APP20600
 APP20610
 APP20620
 APP20630
 APP20640
 APP20650

```

805      DO 860 I3=1,NTOT,NP2
      I2MAX=I3+NP2-NP1
      DO 860 I2=I3,I2MAX,NP1
      IMIN=I2+IRING
      IMAX=I2+NP1-2
      JMAX=I3+NP2
      IF(I2-I3)820,810
      J=JMAX*NP0
      DO 840 I=IMIN,IMAX,2
      DATA(I)=DATA(J)
      DATA(I+1)=-DATA(J+1)
      J=J-2
      J=JMAX
      DO 860 I=IMIN,IMAX,NP0
      DATA(I)=DATA(J)
      DATA(I+1)=-DATA(J+1)
      J=J-NP0
      END OF LOOP ON EACH DIMENSION
      NP0=NP1
      NP1=NP2
      NPREV=N
      RETURN
      END

/*GO,SYSIN DD *
LA MESA VILLAGE, 13 MAY 83
COIL ANTENNA AMP, IN NT
LA MESA VILLAGE, 13 MAY 83
LA SQ-81 AMP IN NT
LA MESA VILLAGE, 13 MAY 83
FLUXGATE AMP IN NT
LA MESA VILLAGE, 13 MAY 83
PROGRAM OUTPUT IN NT
LA MESA VILLAGE, 13 MAY 83
RAW COIL VILLAGE, 13 MAY 83
LA MESA ANTENNA AMP, IN NT
LA MESA VILLAGE, 13 MAY 83
LA SQ-81 AMP IN NT
LA MESA VILLAGE, 13 MAY 83
FLUXGATE AMP IN NT
PROGRAM OUTPUT IN NT
LA MESA VILLAGE, 13 MAY 83
LA MESA VILLAGE, 13 MAY 83

```

```
RAW COIL TIME SERIES IN VOLTS
/*
//GO.FT20F001 DD UNIT=3400-4,VOL=SER=MIKE1,DISP=(OLD,KEEP),
//          LABEL=(1,NI,IN)
//          DCB=(RECFM=FB,ARL=32,BLKSIZE=512,DEN=2)
//GO.SYSDUMP DD SYSOUT=A,OUTLIM=65000
```

```
APP20660
APP20670
APP20680
APP20690
APP20700
APP20710
```

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