

# **Delayed Mode QA/QC Best Practice Manual**

Version 3.1

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# 1 Introduction

This document is the IMOS Ocean Gliders (formerly known as Australian National Facility for Ocean Gliders (ANFOG)) Best Practice manual for delayed mode processed data. IMOS Ocean Gliders is a facility under Australia’s Integrated Marine Observing System (IMOS). IMOS Ocean Gliders, based in the University of Western Australia (UWA), with IMOS National Collaborative Research Infrastructure Strategy (NCRIS) funding, currently deploys a fleet of 11 gliders all around Australia, successfully completing an average of 30 glider missions annually. The data retrieved from the glider fleet contributes to the study of the major boundary current systems surrounding Australia and their links to coastal ecosystem processes.

This document describes the quality analyses/quality control (QA/QC) methods and correction procedures employed by IMOS Ocean Gliders for delayed mode glider data files available for public download through the Australian Ocean Data Network (AODN) portal (<https://portal.aodn.org.au/>) (Figure 1). Information from past IMOS Ocean Gliders’ documents regarding CTD (Gourcuff, 2014a) and Optode corrections (Gourcuff, 2014b), as well as Data Management (Woo *et al.*, 2018) has been updated and incorporated into this document.

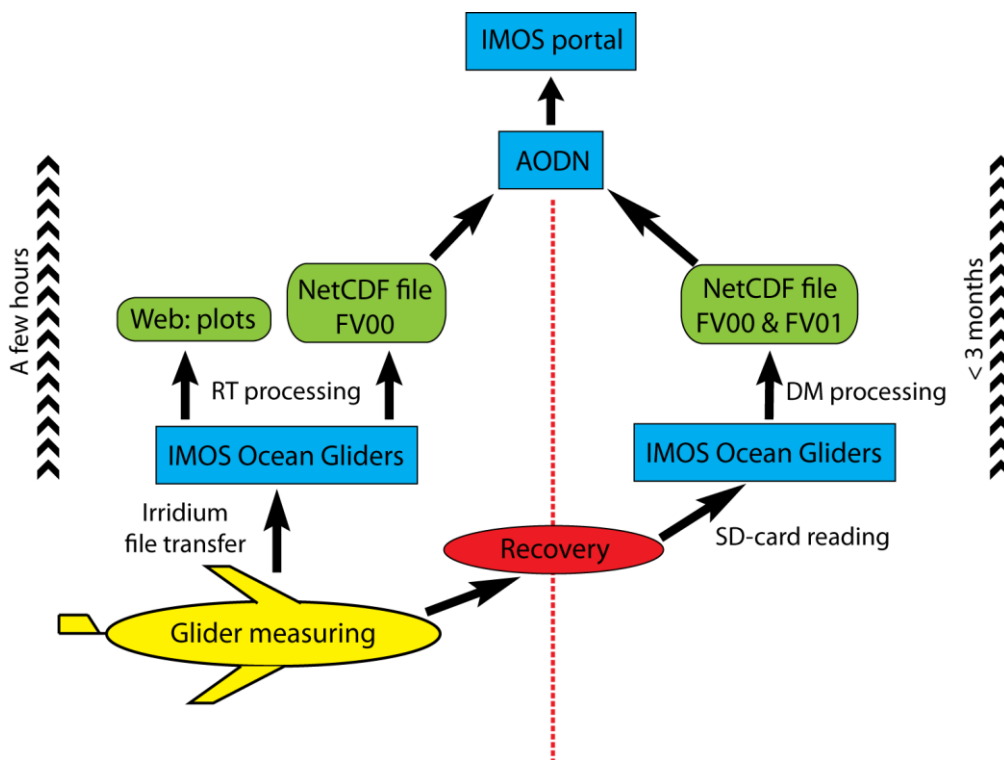
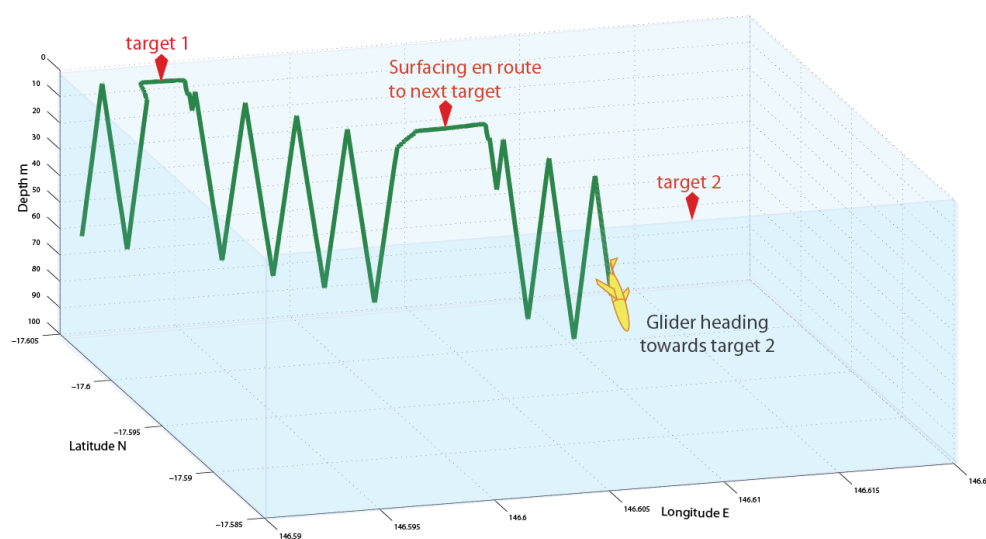


Figure 1 IMOS Ocean Gliders data flow chart. AODN stands for Australian Ocean Data Network (an IMOS supported facility), RT for ‘Real Time’ and DM for ‘Delayed Mode’.

## 2 Background

### 2.1 Gliders and sensor types

The underwater ocean glider represents a technological revolution for oceanography. Autonomous ocean gliders can be built relatively cheaply, are controlled remotely and reusable allowing them to make repeated subsurface ocean observations at a fraction of the cost of conventional methods. The IMOS Ocean Gliders fleet consists of two vehicle types: Slocum gliders and Seagliders. Slocum gliders (named for Joshua Slocum the first solo global circumnavigator), manufactured by Teledyne Webb Research Corp, are optimised for shallow coastal waters (< 200 m) where high manoeuvrability is needed. IMOS currently has 7 Slocum gliders for deployment on the continental shelf. Slocum gliders have an endurance of ~20 days and range of 1,500 km. The Slocum glider first records its position and time stamp at the surface and then performs multiple dive-ascent cycles continuously in a saw-tooth pattern through the water column (Figure 2). After that, it surfaces again to transmit a sample of data, receive new instructions from the base station (if any), and finally it records its position and time stamp before diving into the next segment of saw-tooth sampling. IMOS gliders are usually configured to sample up to 200 m depth. Currently, all IMOS Slocum gliders are instrumented with a Seabird-CTD, WETLabs FLBBCD 3 parameters optical sensor (measuring Chlorophyll-a, CDOM and Backscatter), an Aanderaa Oxygen Optode and a Satlantic 4-channel OCR (Ocean Colour Radiometer) downwelling irradiance sensor. Note that Slocum gliders of G1 type used in the past were not equipped with any irradiance sensor.



**Figure 2** A Slocum glider travels in saw-tooth pattern. It surfaces after a specified number of yo-yo's have been completed as it progresses towards its next target point. This is different from a Seaglider, which usually surfaces after every descent-ascent cycle.

Seagliders, originally designed and built at the University of Washington, then manufactured by iRobot and now Kongsberg, are designed to operate most efficiently in the open ocean. IMOS uses Seagliders to monitor the boundary currents surrounding Australia. The Seagliders are used to conduct repeated glider surveys across the boundary currents and continental shelves. As such, they are particularly valuable for gathering long-term environmental records of physical, chemical and

biological data. Seagliders have an endurance of 1-6 months, range of 6,000 km and can sample up to 1000 m depth. Typically, the Seaglider surfaces after every dive-ascent cycle, takes GPS fixes and sends data. On some occasions, pilots may set the Seaglider to surface after a pre-determined number of dives have been completed in order to navigate through strong surface currents. Unlike Slocum gliders for which only a subset of the dataset is transmitted while the glider is in the water (the full dataset will only be available for processing upon vehicle retrieval), Seagliders always send all their data at each surfacing. IMOS Seagliders are equipped with a Seabird-CTD, WETLabs BBFL2VMT 3 parameters optical sensor (measuring Chlorophyll-a, CDOM and Backscatter) and a Seabird Oxygen sensor.

## 2.2 Known issues with sensors

### 2.2.1 Sea-Bird CTD recorder

All gliders used at IMOS have been equipped with a Sea-Bird Conductivity Temperature Depth (CTD) recorder, optimized for low power consumption. Sea water salinity is computed using temperature, conductivity and pressure measurements acquired by this CTD. During the numerous IMOS Slocum missions performed to date, two types of CTD sensors have been used: the CTD41CP before June 2011 and the GPCTD thereafter. Both these instruments sample at a rate of  $\sim 0.5$ Hz. Their principal difference is that the CTD41CP was an un-pumped CTD, whereas the GPCTD, which has been specifically designed for Slocum gliders and are now installed on all current IMOS Slocum gliders, is equipped with a pump that allows for a constant flow inside the conductivity cell.

Sensor dynamics issues related to the typical profiling CTD, which were mainly high-frequency sampling CTD mounted on rosettes deployed from ships, have been described in the past (Horne and Toole (1980); Gregg and Hess (1985); Morison et al. (1994)). The issues usually manifest as spikes in salinity profiles as well as differences between a downward salinity profile and the following upward profile.

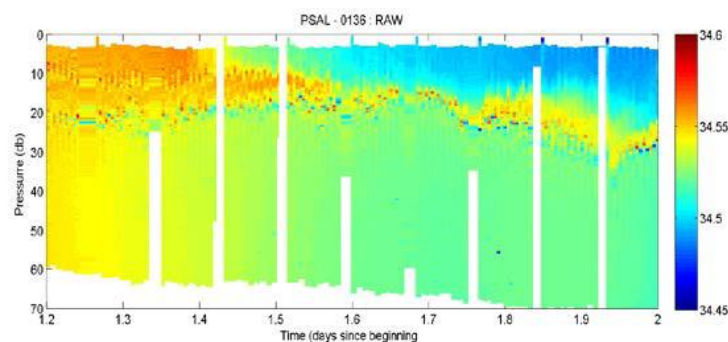
There are two main sources of data imperfections observed in salinity profiles: (i) different sensor time-responses of the thermistor, conductivity sensor and pressure sensor, and (ii) thermal lag effect. In the presence of differences in sensor time-responses, salinity is computed from pressure, conductivity and temperature measurement that don't match up with one another. The thermal lag effect is due to conductivity cell inertia: the conductivity used to compute salinity is measured inside a conductivity cell, which has the capacity of storing heat. Thus, the temperature used to compute salinity does not accurately reflect the temperature of the ocean, especially when the glider is flying through strong temperature gradients. The thermal lag issue was shown to be much reduced when the glider CTD was pumped, so that the flushed water sample is supposedly the same as the water sampled by the thermistor (Janzen and Creed 2011). However, in practice, the issue is still present in data from pumped CTDs (see examples below), although more easily correctable as the flow in the conductivity cell is known and constant.



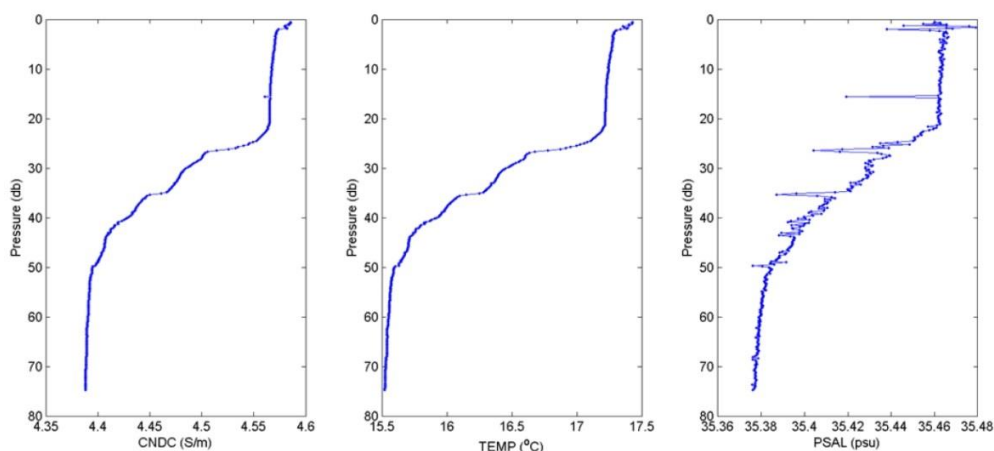
## 2.2.2 Examples of Slocum CTD data problems seen in IMOS data

In order to check validity of CTD data, it is appropriate to examine the quality of salinity data, since salinity is calculated from a combination of both temperature and conductivity (using TEOS-10 thermodynamic equation of seawater). Before correction, salinity spikes have been observed in Slocum CTD data near the thermocline (Figure 3 & Figure 4). This phenomenon is intensified in cases of strong gradients. In the example seen in Figure 4, Salinity spikes occur despite the absence of similar spikes in temperature and conductivity data (apart from ~18m depth, where a salinity spike is associated with a spike in conductivity).

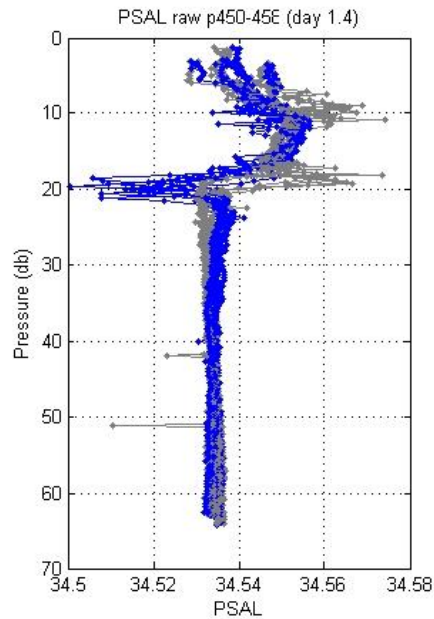
Additionally, there is dissymmetry in the salinity profiles between up- and down-casts. As seen in Figure 5, negative spiking occurs in the downward profiles whilst positive spiking occurs in the upward profiles in the thermocline. During down-cast when temperature and salinity are decreasing with increasing pressure, negative salinity spiking is indicative of the conductivity signal leading the temperature signal (Sea-Bird Electronics, 2013).



**Figure 3 Salinity time-series data recorded during the first 2 days of a Kimberly deployment made by a Slocum glider in September 2012.**

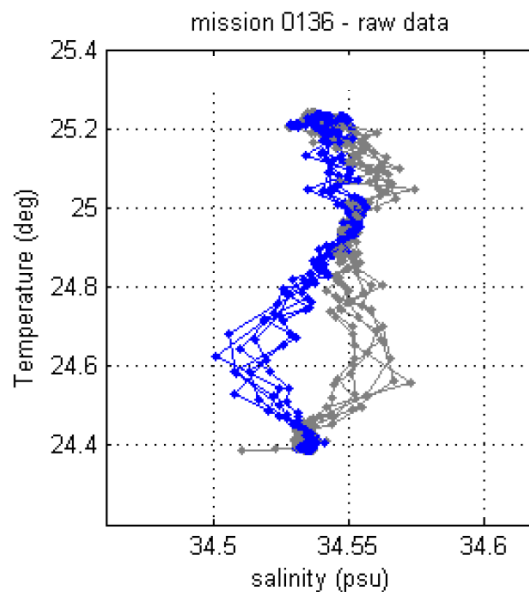


**Figure 4 Associated Conductivity (left), Temperature (middle) and Salinity (right) downward profiles from a Yamba deployment (Sept 2012) (day 18.896).**



**Figure 5 Four downward (blue) and four upward (grey) consecutive salinity profiles measured during the September 2012 Kimberly deployment.**

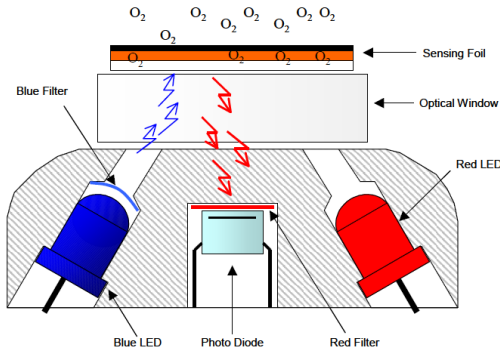
Upon closer examination of Figure 5, it can also be seen that between 20db and 30db (20-30m depth), salinity measured on the descent is higher than that on the ascent. Such discrepancies are obvious on TS-diagrams, as can be seen in Figure 6 where data plotted from a series of four dives during the Yamba20120904 mission clearly exhibit a salinity difference of 0.05 psu when comparing glider descent with ascent. These differences result from thermal lag issues (Garau *et al.*, 2011).



**Figure 6 Temperature versus salinity plot for four down-casts (blue) and four up-casts of the September 2012 Yamba deployment.**

### 2.2.3 Aanderaa Optode

IMOS Slocum gliders are equipped with Aanderaa Optodes (3835 – 5013W). The following is the way in which the Optode internally computes dissolved oxygen concentration (in  $\mu\text{mol/L}$ ).



**Figure 7 Optode optical design (Aanderaa, 2007).**

The uncalibrated phase measurement (UNCAL\_PHASE) is calculated as the difference between phase obtained with blue light excitation (BPHASE) and phase obtained with red light excitation (RPHASE) (Aanderaa, 2007; Thierry *et al.*, 2013):

$$\text{UNCAL\_PHASE} = \text{BPHASE} - \text{RPHASE}$$

Since RPHASE is not used, it is set to zero.

Thus,  $\text{UNCAL\_PHASE} = \text{BPHASE}$

A calibrated phase (DPHASE) is calculated as a 3<sup>rd</sup> degree polynomial of UNCAL\_PHASE (or BPHASE, in our case):

$$\text{DPHASE} = A + B \times \text{BPHASE} + C \times \text{BPHASE}^2 + D \times \text{BPHASE}^3$$

where A, B, C and D are the *PhaseCoef* calibration coefficients (C and D are usually equal to zero).

#### **For Aanderaa Optode 3930, 3835, 3975, 4130 and 4175:**

DPHASE is then converted to dissolved oxygen concentration, MOLAR\_DOXY ( $\mu\text{mol/L}$ ), using additional foil-dependant coefficients in a 4<sup>th</sup> degree polynomial:

$$\text{MOLAR\_DOXY} = C_0 + C_1 \times \text{DPHASE} + C_2 \times \text{DPHASE}^2 + C_3 \times \text{DPHASE}^3 + C_4 \times \text{DPHASE}^4$$

where C0, C1, C2, C3, C4 are temperature dependant coefficients calculated as:

$$C_i = C_{i0} + C_{i1} \times T + C_{i2} \times T^2 + C_{i3} \times T^3$$

T is temperature ( $^{\circ}\text{C}$ ), and Cij are 20 foil-dependant calibration coefficients. One set of these 20 calibration coefficients is associated with each batch of foils.

**For Aanderaa Optode 4330, 4831 and 4835:**

A few more steps are involved for the calculation of dissolved oxygen concentration, MOLAR\_DOXY ( $\mu\text{mol/L}$ ) for Optode types 4330, 4831 and 4835.

For 4330 and 4831, Aanderaa has introduced SVU foil coefficients to take advantage of the **Stern/Volmer/Uchida** formula, so that:

$$MOLAR\_DOXY = \frac{\left(\frac{P_o}{P_c} - 1\right)}{K_{SV}}$$

Where

$$K_{SV} = c_0 + c_1 t + c_2 t^2$$

$$P_o = c_3 + c_4 t$$

$$P_c = c_5 + c_6 \text{ DPHASE}$$

t is temperature ( $^{\circ}\text{C}$ ).  $c_0$  to  $c_6$  are listed on Aanderaa calibration sheets as SVUFoilCoef. From March 2021, IMOS has calculated MOLAR\_DOXY ( $\mu\text{mol/L}$ ) using the above **Stern/Volmer/Uchida** formula.

Where SVUFoilCoef (i.e.  $c_0 - c_6$ ) is unavailable, MOLAR\_DOXY ( $\mu\text{mol/L}$ ) is calculated by:

$$MOLAR\_DOXY = \frac{C^* \times 44.659 \times \text{AirSaturation}}{100}$$

(1)

where  $C^*$  is oxygen solubility ( $\text{cm}^3/\text{dm}^3$ ) is calculated from the Garcia & Gordon (1992) equation as:

$$C^* = \exp [ A_0 + A_1 T_s + A_2 T_s^2 + A_3 T_s^3 + A_4 T_s^4 + A_5 T_s^5 + S ( B_0 + B_1 T_s + B_2 T_s^2 + B_3 T_s^3 ) + C_0 S^2 ]$$

Where  $T_s$  is scaled temperature calculated by:

$$T_s = \ln \left( \frac{298.15 - t}{273.15 - t} \right)$$

t is temperature ( $^{\circ}\text{C}$ ), and S is salinity, set to a constant 35 in our case<sup>1</sup>.

$$A_0 = 2.00856$$

$$B_0 = -6.24097e^{-3}$$

---

<sup>1</sup> In future, we may consider applying CTD measured salinities instead of a constant 35. But at present, a constant value of 35 is preferred so as to avoid introducing spikes (seen in salinity data) into the dissolved oxygen data. Impact of varying salinity on the final oxygen data is small.

$$\begin{aligned}
A_1 &= 3.22400 & B_1 &= -6.93498e^{-3} \\
A_2 &= 3.99063 & B_2 &= -6.90358e^{-3} \\
A_3 &= 4.80299 & B_3 &= -4.29155e^{-3} \\
A_4 &= 9.78188e^{-1} & C_0 &= -3.11680e^{-7} \\
A_5 &= 1.71069
\end{aligned}$$

Air saturation (%) in equation (1) is calculated by:

$$AirSaturation = \frac{\Delta p \times 100}{(NomAirPress - p_{vapour}) \times NomAirMix}$$

where NomAirPress is nominal air pressure = 1013.25 hPa,

NomAirMix is the nominal oxygen content in air = 0.20946,

$\Delta p$  is partial pressure of oxygen, calculated using DPHASE, temperature and polynomial calibration coefficients for the foil given by the manufacturer:

$$\Delta p = C_0 \cdot t^{m_0} \cdot DPHASE^{n_0} + C_1 \cdot t^{m_1} \cdot DPHASE^{n_1} + C_2 \cdot t^{m_2} \cdot DPHASE^{n_2} + \dots + C_{27} \cdot t^{m_{27}} \cdot DPHASE^{n_{27}}$$

(2)

where c, m and n are coefficients found in Aanderaa calibration sheets (see Table 1).

**Table 1 Listing of relevant coefficients for equation (2) as found in Aanderaa calibration sheets.**

Coefficients in equation (2)	Listing on Aanderaa sheet
$C_0 - C_{13}$	FoilCoefA
$C_{14} - C_{27}$	FoilCoefB
$m_0 - m_{27}$	FoilPolyDegT
$n_0 - n_{27}$	FoilPolyDegO

$p_{vapour}$  is vapour pressure calculated from temperature t:

$$p_{vapour} = \exp\left(52.57 - \frac{6690.0}{t + 273.15} - 4.681 \times \ln(t + 273.15)\right)$$

Thereafter, multipoint calibration is applied using additional ConcCoef\_0 and ConcCoef\_1 values found in Aanderaa calibration sheets, such that

$$MOLAR\_DOXY_{corrected} = MOLAR\_DOXY \times (ConcCoef_1) + ConcCoef_0$$

#### Salinity compensation:

The dissolved oxygen concentration is also corrected for salinity effects. Salinity compensated MOLAR\_DOXY is finally calculated as:

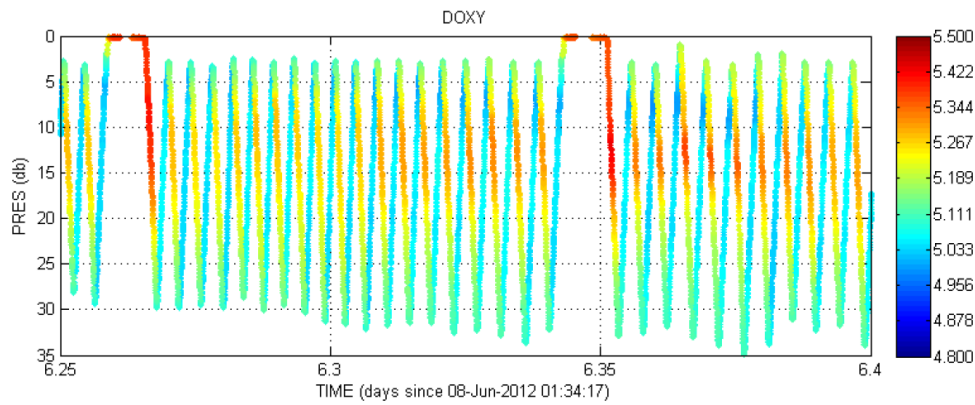
$$MOLAR\_DOXY_{SAL-compensated} = MOLAR\_DOXY * \exp [ (S_{set}) (B_0 + B_1 T_S + B_2 T_S^2 + B_3 T_S^3) + C_0 * (S_{set}^2) ]$$

where Sset=35, in our case.

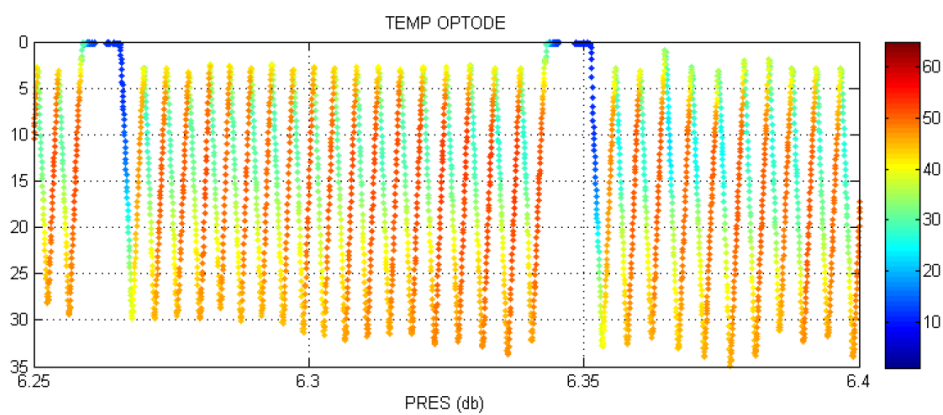
Early IMOS Slocum deployments were performed with the glider configured such that only the internally computed dissolved oxygen data in  $\mu\text{mol/L}$  were recorded. However, from May/June 2011, glider configuration settings were changed to “wphase” (`sci_oxy3835_wphase_is_installed=1`), allowing outputs of many more parameters. Thus, for deployments performed since mid-2011, the BPHASE, DPHASE and Optode temperature measurements have also become available. This is of critical importance for the improvement of oxygen data quality, as described in section 3.2.2.

#### 2.2.4 Examples of Optode data problems seen in IMOS Slocum data

A major issue in dissolved oxygen data is the disparity between up- and down-casts. For example, a sample of dissolved oxygen data recorded during the StormBay20120608 mission clearly shows a difference of up to 0.3ml/L (Figure 1). Moreover, after the Slocum glider has been parked on the surface, the dissolved oxygen values recorded upon the initial dive from the surface are often significantly higher. These two issues are due partly to problems with temperature values used in the computation of dissolved oxygen concentration from raw phase measurements. Indeed, looking at a plot of the Optode-measured temperature, there is evidently similar dissymmetry between up- and down-casts (Figure 9).

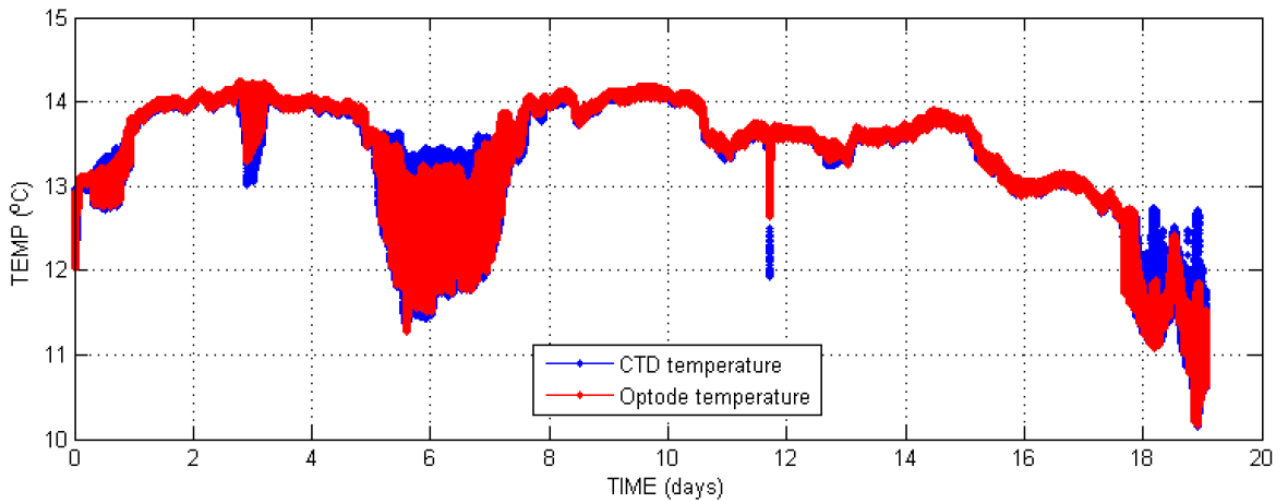


**Figure 8** A sample of raw dissolved oxygen concentration (ml/L) time-series data taken from the June 2012 Storm Bay mission shows discrepancies between up- and down-casts.



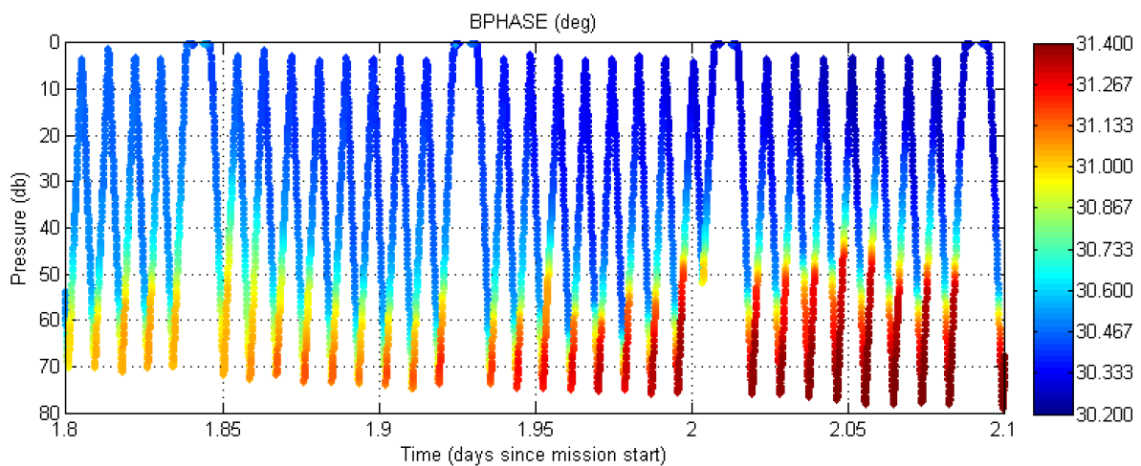
**Figure 9** A sample temperature ( $^{\circ}\text{C}$ ) time-series data measured by the Optode during the June 2012 Storm Bay mission shows discrepancies between up- and down-casts.

Discrepancy between Optode-measured and CTD-measured temperature are especially pronounced whenever the glider traverses steep temperature gradients (Figure 10). Such an issue is well-known with Optodes because Optode temperature measurement is made inside the instrument rather than externally in ocean water. Recording of any major variations in ocean temperature is softened by instrument self-heating. Thus, the manufacturer recommends the use of temperature data from fast response temperature sensors when available to compensate for the temperature effect on oxygen (Aanderaa, 2007).



**Figure 10** Temperature time-series data measured by the Optode (red) and CTD (blue) during the June 2012 Storm Bay deployment.

Another source of problem in dissolved oxygen data is the time response of the phase sensor, of the order of 20s, according to the manufacturer. Omitting to account for this time response induces a temporal mismatch between the different parameters used to compute oxygen. The effect of this time lag is obvious in Figure 11, where dissymmetry between up- and down-cast profiles highlights the lag in the BPHASE data.



**Figure 11** Raw BPHASE measurements taken from the Kimberley Mission conducted in July 2012 show dissymmetry between up- and down-casts.

IMOS Seagliders are equipped with Seabird SBE\_43FO2 oxygen sensors and Seabird CT (SBE\_CT) sensors. Although these CTD are not pumped, dissymmetry such as that seen with Slocum glider data is not typically observed because Seagliders travel more slowly through the water, and the dive and climb profiles are very widely spaced, with surfacings 6 km apart during dives to 1km depth (Frajka-Williams, 2011).



## 2.2.5 Bio-optical Sensors

All gliders at IMOS are equipped with WETLabs ECO Puck triplets which incorporate scattering meters to measure Chlorophyll-a fluorescence, coloured dissolved organic matter (CDOM) fluorescence and backscattering. The scattering meter sensors have a  $117^{\circ}$  centroid angle and a single LED light source and detector. Specifically, the older Slocum gliders were fitted with WETLabs BBFL2SL and BBFL2VMT, which function at wavelengths of 650nm or 660nm. These sensors were replaced with FLBBCDSLK and FLBBCSLC, which function at a wavelength of 700nm. Seagliders are fitted with WETLabs BBFL2VMT also. Additionally, the Slocum gliders are also fitted with Satlantic OCR-504 Multispectral Radiometers to measure downwelling spectral irradiance at 4 frequencies.

The parameters for Chlorophyll-a concentration (CPHL), CDOM concentration (CDOM), Volumetric Backscatter Coefficient (VBSC) and downwelling spectral irradiance (IRRAD<sub>xxx</sub><sup>2</sup>) are computed using raw measurements made in counts and the associated calibration coefficients and dark count values, i.e.:

$$\text{PARAM}_{\text{units}} = \text{SF} \times (\text{PARAM}_{\text{counts}} - \text{DC})$$

where SF is scale factor coefficient, DC is dark count coefficient.

For downward spectral irradiance, there is an additional scaling factor (IRRAD\_IC) according to the chosen wavelength:

$$\text{PARAM}_{\text{units}} = \text{IRRAD\_IC} \times \text{SF} \times (\text{PARAM}_{\text{counts}} - \text{DC})$$

Scale factors and dark count coefficients are obtained from independent laboratory-based calibrations performed by each instrument's respective manufacturer.

Additionally, VBSC is converted to Particle Backscatter Coefficients (BBP) during delayed mode processing. Details of how this is done are available in Mantovanelli & Thomson (2016). Basically, Matlab code developed by Zhang *et al.* (2009)<sup>3</sup> is used to calculate seawater volumetric scattering,  $\beta_{\text{sw}}$ . Input comprises the wavelength of the sensor (650 – 700nm, depending on the model used), sensor centroid angle ( $117^{\circ}$  recommended by Boss & Pegau (2001)), depolarization ratio (0.039 used by default by Zhang *et al.* (2009) based on Farinato and Roswell (1976)), and CTD temperature and salinity.

Particle backscatter coefficient, BBP, is then computed as follows:

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<sup>2</sup> The parameter is named according to the wavelength of the beam, i.e. IRRAD443 for the wavelength closest to 443nm. The actual wavelength which may vary slightly from 443nm is specified in the 'comment' attribute of the parameter.

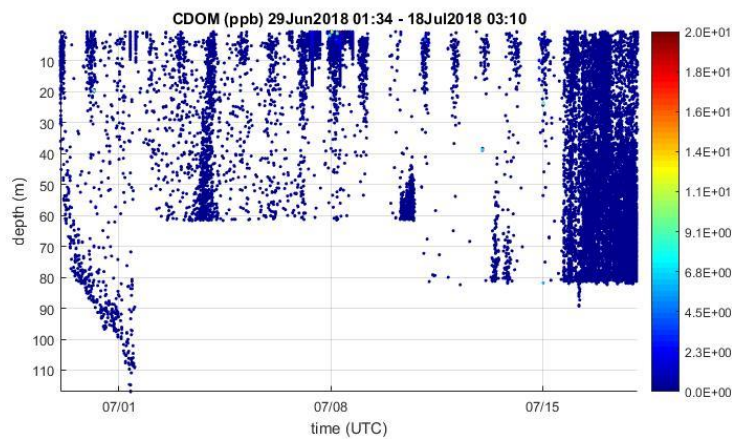
<sup>3</sup> Zhang *et al.* (2009) Matlab code is available to the public at [http://www1.und.edu/faculty/zhang-xiaodong/\\_files/docs/programs/betasw\\_zhh2009.m](http://www1.und.edu/faculty/zhang-xiaodong/_files/docs/programs/betasw_zhh2009.m)

$$BBP = 2\pi \times (VBSC - \beta_{sw}) \times X_p$$

where  $X_p = 1.1$  (recommended by WETLabs 2013)

### 2.2.6 Examples of bio-optical data problems seen in IMOS Slocum data

Dark counts in bio-optical instruments can be affected by various environmental (e.g. temperature) and platform dependent (e.g. power) parameters (Cetinic *et al.*, 2009). As such, applying the lab-determined value sometimes leads to an inordinately large proportion of negative values calculated. For example, application of the lab calibrated darkcount resulted in an unacceptable 93.6% of the calculated CDOM values being negative (depicted as the blank areas in Figure 12).



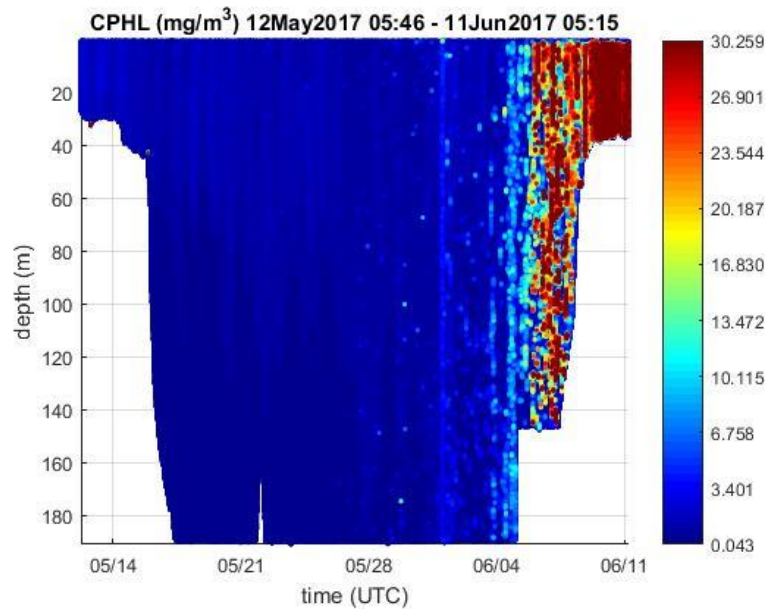
**Figure 12 Uncorrected CDOM time-series data from Forster20180629 mission with 93.6% of values being negative (seen as the white spaces).**

Another problem with optical sensors deployed in the oceans around Australia is their susceptibility to biofilm and barnacle growth (Figure 13), depending on the duration, location of deployment and type of fouling. Just 10% coverage of the optical path will affect the quality of data strongly, resulting in noisy data which may be enhanced or dampened (Lehaitre *et al.*, 2008, Cetinic *et al.*, 2009).



**Figure 13 Examples of biofouling growing on the windows of optical sensors in a (left) Slocum glider and (right) Seaglider.**

In the example shown in Figure 14, noise generated from the gradual growth of biofouling starts to completely take over the Chlorophyll-a fluorescence signal 3 weeks into the TwoRocks20170512 mission off Perth.



**Figure 14 Biofouled optical sensor at the end of the mission (TwoRocks20170512) is seen as severely raised values in the chlorophyll-a fluorescence time-series data.**

### 3 Delayed-mode QA/QC

This section describes the main delayed mode QA/QC procedures for the data that has been extracted from .dbd and .edb files of Slocum gliders, and .log and .eng files of Seagliders, which falls within the step circled red in Figure 15. Subsequently, the completed IMOS NetCDF files are uploaded to AODN to be checked, stored and made available to the public online, along with the associated QA/QC report and data plots.

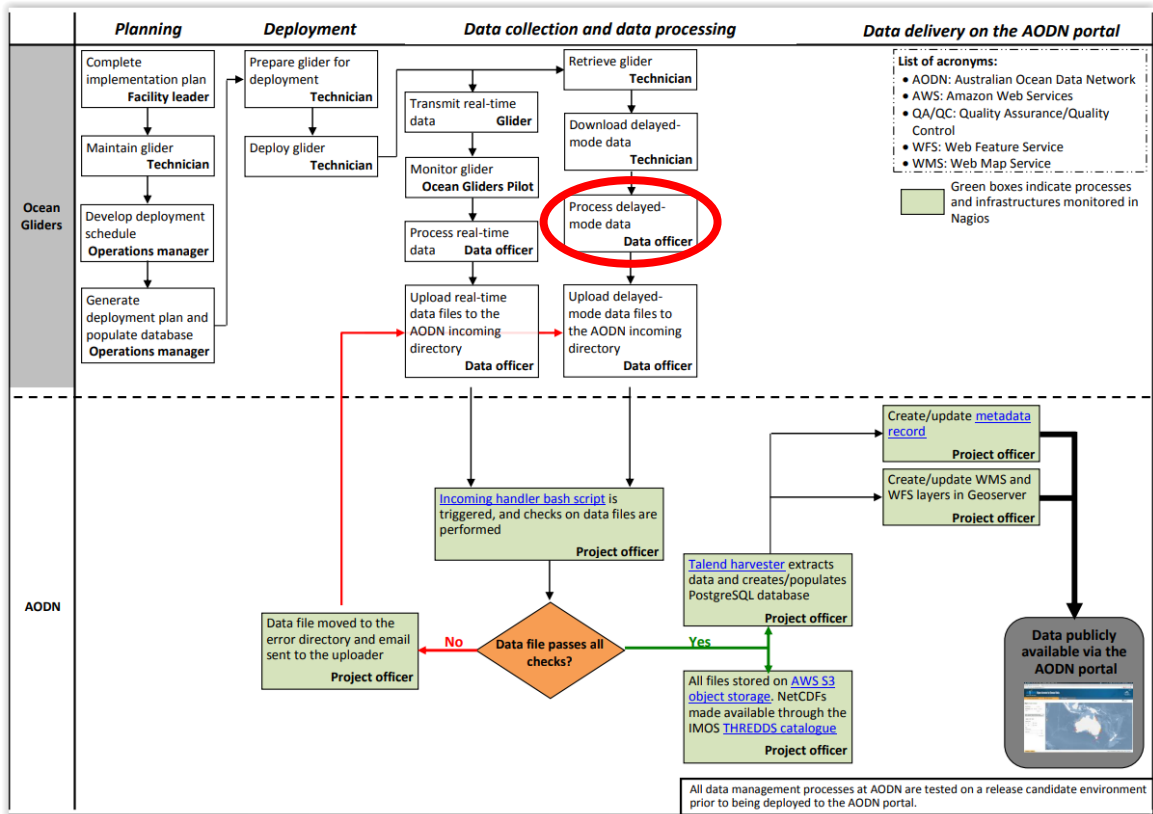


Figure 15 Workflow of IMOS Ocean Gliders data. Red circle highlights the part covered in this document. (AODN Portal User Guide Public Documents, 2016).

#### 3.1 Glider data and metadata format

Firstly, the proper data file structure must be set up and populated with the sufficient metadata to make the data in each NetCDF file self-described. IMOS Ocean Gliders delayed-mode format files contain meta-data and scientific data for one deployment of one glider. Since the advent of delayed mode processing version 4.0, IMOS Ocean Gliders has generated NetCDF-4 format files (versus NetCDF-3 format previously), and released 2 types of NetCDF files for each deployment: FV00 and FV01. These two files contain the same global attributes. The FV00 file contains all the raw data from the deployment (both in engineering and physical units), with each parameter following its own time dimension. Data in FV00 files are not quality controlled. The FV01 file is the one recommended to

users, with all parameters associated with quality control flags. The FV01 file contents include corrected data and also parameters which have been interpolated (slightly, as all the time dimensions are usually very similar) following the same unique time dimension.

IMOS Ocean Gliders delayed-mode NetCDF files comply with Climate and Forecast (CF) Metadata Conventions v1.6 and IMOS conventions v1.4. For clarity, only the FV01 file format is described extensively in this document.

### 3.1.1 File name convention

NetCDF files follow the following IMOS convention (also described in Mancini, Tattersall, Proctor, and Galibert (2016)), described in Table 2

*IMOS\_ANFOG\_<data-code>\_<start-date>\_<platform-code>\_FV<file-version>\_<product-type>\_END-<end-date>.nc*

Examples:

IMOS\_ANFOG\_BCEOPSTUV\_20181030T021121Z\_SL248\_FV01\_timeseries\_END-20181126T073524Z.nc

IMOS\_ANFOG\_BCEOPRSTUV\_20170427T030417Z\_SG516\_FV00\_timeseries\_END-20170703T000315Z.nc

**Table 2 Elements of file-naming convention.**

Part of filename	Description
data-code	B: biology (plankton, fluorescence, nutrients, dissolved organic matter) C: conductivity E: Engineering or technical parameters. O: oxygen concentration P: pressure S: salinity of sea water T: temperature of sea water U: turbidity of sea water (including backscatter) V: velocity of sea water N: nitrates R: Raw data.
start-time	Start date and time of the measurements in UTC.

	<p>Date format is: <code>yyyymmddTHHMMSSZ</code> where T is the delimiter between date and time, and Z indicates that time is in UTC.</p> <p>Example: <code>20090211T114713Z</code> is 11th February 2009, 11:47:13 AM</p>
platform-code	The glider unit's name. See Table 3.
file-version	<p>Value representing the version of the file. This value is preceded by two characters: 'FV'.</p> <p>00 : Level 0 – raw data. Raw data is defined as unprocessed data and data products that have not undergone quality control. The data may be in engineering units or physical units. Time and location details can be in relative units and values can be pre-calibration measurements. Level 0 data is unsuitable for public access.</p> <p>01 : Level 1 – quality controlled data. Quality controlled data have passed quality assurance procedures such as routine estimation of timing and sensor calibration or visual inspection and removal of obvious errors. The data are in physical units using standard SI metric units, with calibration and other pre-processing and corrections applied. All time and location values are in absolute coordinates to agreed standards and datum. Metadata exists for the data. This is the standard data level that is made available to the IMOS community.</p>
product-type	<p>(optional) This code gives information about the product included in the dataset.</p> <p>Example: timeseries</p>
end-date	<p>End date and time of the measurements in UTC. The code is preceded by four characters: 'END-'.</p> <p>Date format is: <code>yyyymmddTHHMMSSZ</code> where T is the delimiter between date and time, and Z indicates that time is in UTC.</p> <p>Example: <code>20090211T114713Z</code> is 11th February 2009, 11:47:13 AM</p>
creation-date	<p>(optional) Creation date and time of the file. The data format is the same as the start and end date. The code is preceded by the two characters C-. In the case of IMOS Ocean Gliders' datasets, files that include a creation date have been re-processed with an updated version of the processing software.</p> <p>Example: C-20081112T231255Z</p>

Listed in Table 3 are codes by which each glider is identified. Each glider unit's name is unique within the IMOS project, and used as its platform code. IMOS Seaglider codes begin with 'SG', while the Slocum codes begin with 'SL'.

**Table 3 IMOS Ocean Gliders platform codes.**

Glider type	Platform code	Platform type	Active as of May 2023
Seaglider	SG151	Seaglider UW	No (lost in 2010)
	SG152	Seaglider UW	No (decommissioned in 2019)
	SG153	Seaglider UW	No (decommissioned in 2019)
	SG154	Seaglider UW	No (decommissioned in 2019)
	SG155	Seaglider UW	No (lost in 2016)
	SG514	Seaglider 1kA (iRobot)	No (lost in 2014)
	SG516	Seaglider 1kA (iRobot)	No (decommissioned in 2019)
	SG517	Seaglider 1kA (iRobot)	No (lost in 2011)
	SG519	Seaglider 1kA (iRobot)	No (lost in 2011)
	SG520	Seaglider 1kA (iRobot)	No (lost in 2011)
	SG521	Seaglider 1kA (iRobot)	No (lost in 2012)
	SG540	Seaglider 1kA (iRobot)	No (lost in 2018)
Slocum	SL104	Slocum G1	No (lost in 2010)
	SL106	Slocum G1	No (lost in 2010)
	SL109	Slocum G1	No (lost in 2009)
	SL130	Slocum G1	No (lost in 2011)
	<b>SL209</b>	<b>Slocum G2</b>	<b>Yes</b>
	<b>SL210</b>	<b>Slocum G2</b>	<b>Yes</b>
	SL239	Slocum G2	No (lost in 2018)
	<b>SL248</b>	<b>Slocum G2</b>	<b>Yes</b>
	SL281	Slocum G2	No (lost in 2020)
	<b>SL286</b>	<b>Slocum G2</b>	<b>Yes</b>
	<b>SL287</b>	<b>Slocum G2</b>	<b>Yes</b>
	SL502	Slocum G2	No (lost in 2022)
	<b>SL812</b>	<b>Slocum G3</b>	<b>Yes</b>
	<b>SL994</b>	<b>Slocum G3</b>	<b>Yes</b>
<b>SL995</b>	<b>Slocum G3</b>	<b>Yes</b>	

### 3.1.2 Global attributes

This section contains general information about the global attributes defined in the IMOS Ocean Gliders' NetCDF files (Table 4).

**Table 4 IMOS Ocean Gliders Facility NetCDF files global attributes.**

Name	Example	Definition
project	char('Integrated Marine Observing System (IMOS)');	The scientific project that produced the data
institution	char('IMOS Ocean Gliders');	Name of the institute or facility where the original data was produced.
references	char(' <a href="http://www.imos.org.au">http://www.imos.org.au</a> ; "ANFOG Data Management Users Manual v5 November 2016"');	Published or web-based references describing the data or methods used to produce it.
naming_authority	char('IMOS');	Naming authority will always be IMOS.
cdm_data_type	char('Trajectory')	Unidata Common Data Model data type used by THREDDS.  More information on <a href="http://www.unidata.ucar.edu/projects/THREDDS/CDM/CDMTDS.htm">http://www.unidata.ucar.edu/projects/THREDDS/CDM/CDMTDS.htm</a>
data_center	char(' Australian Ocean Data Network (AODN)')	Data center in charge of management and distribution of the data resource.
data_centre_email	char('info@aodn.org.au')	Data centre contact email address.
principal_investigator	char('Pattiaratchi, Charitha')	Name of principal investigator in charge of the glider unit.
principal_investigator_email	char('chari.pattiaratchi@uwa.edu.au')	Principal investigator's email address.
institution_references	char('http://imos.org.au/facilities/aodn/; http://imos.org.au/facilities/oceanradar/')	Reference to the data provider and producer.
citation	char('Citation to be used in publications should follow the format: "IMOS.[year-of-data-download],[Title],[Data access URL],accessed [date-of access]".'	Citation used for usage of this data.



acknowledgement	char('Any users of IMOS data are required to clearly acknowledge the source of the material in the format: "Data was sourced from the Integrated Marine Observing System (IMOS) - IMOS is a national collaborative research infrastructure, supported by the Australian Government.')	Any users (including re-packers) of IMOS data are required to acknowledge the source of the data in this format.
disclaimer	char(' Data, products and services from IMOS are provided "as is" without any warranty as to fitness for a particular purpose.')	Statement describing data distribution policy.
license	char('http://creativecommons.org/licenses/by/4.0/')	Reference for the license for the data
standard_name_vocabulary	char('NetCDF Climate and Forecast (CF) Metadata Convention Standard Name Table Version 29')	Reference for CF standard names
source	char('Glider observation');	Method of production of the original data.
geospatial_lat_units	char('Degrees_north')	Units used for geospatial_lat_min/max attributes.
geospatial_lon_units	char('Degrees_east')	Units used for geospatial_lon_min/max attributes.
geospatial_vertical_units	char('meter')	Units used for geospatial_vertical_min/max attributes.
geospatial_vertical_positive	char('down')	Direction of vertical coordinates
Conventions	char('CF-1.6,IMOS-1.4');	Format convention used by the dataset
title	char(['Slocum G1 glider data from the mission SpencerGulf20080716']);	Short description of the dataset indicating the type of glider from which data has come from, and the corresponding name of the mission.
date_created	char('2014-06-11T09:16:22Z');	Date and time at which the data was created.

		<p>Format: yyyy-mm-ddTHH:MM:SSZ'</p> <p>Example: 2008-12-10T09:35:36Z : December 10<sup>th</sup> 2008 9:35:36AM</p>
abstract	<pre>char(' This NetCDF file contains data from the SpencerGulf20080716 glider deployment. The platform deployed was UNIT109 (Slocum G1) with the following instruments on board: SBE CTD CTD41CP (Conductivity, Temperature, Depth), Wetlabs BBFL2S 3 parameters optical sensor (measuring Chlorophyll-a, CDOM and 660nm Backscatter)');</pre>	A paragraph describing the dataset: type of data contained, how it was created, who collected it, what instruments were used, etc.
comment	<pre>char(' This file contains data from the following specific instruments: SBE CTD CTD41CP, SN 106, cal 9/09/2007; Wetlabs bio-optical sensor BBFL2S, SN 498, cal 5/02/2008; ');</pre>	Additional information about the data, methods used to produce it, instruments used (model, serial number and calibration date), and correction applied to the data.
keywords	<pre>char('Water Temperature, Conductivity, Salinity, Oxygen, Turbidity, Chlorophyll, Organic Matter, Fluorescence, Scattering, Downwelling spectral irradiance');</pre>	A comma separated list of key words and phrases.
geospatial_lat_min	<pre>double(-35.5568);</pre>	Southernmost latitude (positive north) from which dataset was obtained; a value between -90 and 90 degrees.
geospatial_lat_max	<pre>double(-35.4248);</pre>	Northernmost latitude (positive north) from which dataset was obtained; a value between -90 and 90 degrees.
geospatial_lon_min	<pre>double(136.3502);</pre>	Westernmost longitude (positive east) from which dataset was obtained; a value between -180 and 180 degrees.

geospatial_lon_max	double(136.9128);	Easternmost longitude (positive east) from which dataset was obtained; a value between -180 and 180 degrees.
geospatial_vertical_min	double(-1.5731);	Minimum depth of measurements, in metres.
geospatial_vertical_max	double(100.559);	Maximum depth of measurements, in metres.
time_coverage_start	char('2008-07-16T00:47:11Z')	Start date and time in UTC, for which data in the dataset was collected.  Format: yyyy-mm-ddTHH:MM:SSZ'  Example: 2008-12-10T09:35:36Z : December 10th 2008 9:35:36AM
time_coverage_end	char('2008-07-24T02:37:22Z')	End date and time in UTC, for which data in the dataset was collected.  Format: yyyy-mm-ddTHH:MM:SSZ'  Example: 2008-12-10T09:35:36Z : December 10th 2008 9:35:36AM
author	char('Gourcuff, Claire')	Name of person responsible for the creation of the dataset.
processing	char('Written by MATLAB processing code version 5.00 - processing_ID=2216')	Version of IMOS Ocean Gliders processing used to generate the file, and processing ID number (useful internally for IMOS Ocean Gliders in case of reprocessing).
deployment_code	char('SpencerGulf20080716')	IMOS mission name
netcdf_version	char('4.0')	NetCDF file version
platform_code	char('SL109');	IMOS Glider unit number (as listed in Table 3). These are platform codes unique within the IMOS project.
local_time_zone	double(10)	Local time zone (UTC+)
author_email	char('anfog-ecm@uwa.edu.au')	NetCDF file author contact email address.

data_mode	Char('Delayed Mode')	Mode of data processing
history	Char('2018-11-29T06:11:55Z Created. 2019-02-18T10:02:17Z Corrected CTD serial number and calibration date')	Audit trail for modifications to the original data. If no changes have been made, this contains creation date.

### 3.1.3 Metadata containers

In each NetCDF datafile, information describing the platform and sensors used, and the deployment itself is stored in the attributes of empty and dimensionless variables known as 'containers'. *PLATFORM*, *DEPLOYMENT* and *SENSOR* are such empty, dimensionless variables. Their associated attributes are as listed in Table 5.

**Table 5 Metadata containers and their attributes. Note: If an attribute value is empty (information unknown), the attribute does not exist in the NetCDF file.**

Variable	Attributes	Example
PLATFORM	trans_system_id	'Iridium'
	positioning_system	'GPS'
	platform_type	'Slocum G2'
	long_name	'Platform information'
	platform_maker	'Teledyne Webb Research'
	firmware_version_navigation	7.16
	firmware_version_science	7.16
	glider_serial_no	'209'
	battery_type	'Alkaline'
	glider_owner	'IMOS Ocean Gliders'
	operating_institution	'IMOS Ocean Gliders'
wmo	6801513	
DEPLOYMENT	deployment_start_date	'2016-03-30-T24:23:29Z'
	deployment_start_latitude	-29.467 ( <i>decimal degrees</i> )
	deployment_start_longitude	121.8523 ( <i>decimal degrees</i> )
	long_name	'Deployment information'
	deployment_start_technician	'Thomson, Paul'

	deployment_end_date	'2016-04-03-T02:45:17Z'
	deployment_end_latitude	-17.1947 ( <i>decimal degrees</i> )
	deployment_end_longitude	121.726 ( <i>decimal degrees</i> )
	deployment_end_technician	'Thomson, Paul'
	deployment_end_status	'recovered'
	deployment_pilot	'Coia, Martin'
	deployment_anomaly	'Fin rudder removed by shark. Mission terminated early and glider recovered'
SENSOR1	sensor_type	'CTD'
	sensor_maker	'Seabird'
	sensor_model	'GPCTD'
	sensor_serial_no	'96'
	long_name	'Sensor1 information'
	sensor_calibration_date	'2011-11-30' ( <i>yyyy-mm-dd</i> )
	sensor_parameters	'TEMP, CNDC, PRES, PSAL'
SENSOR2	sensor_type	'ECO Puck'
	sensor_maker	'Wetlabs'
	sensor_model	'FLBBCDSLK '
	sensor_serial_no	'2375'
	long_name	'Sensor2 information'
	sensor_calibration_date	'2011-10-06' ( <i>yyyy-mm-dd</i> )
	sensor_parameters	'CPHL, CDOM, VBSC, BBP'
SENSORn	...	

### 3.1.4 Dimensions

IMOS Glider data are collected as time-series, where three-dimensional coordinates of latitude, longitude and depth coordinates are recorded, along with various measured parameters. A few computed parameters included in the files allow users to easily identify up and down profiles within the time-series. The length of the time-series data varies according to the duration spent underwater and frequency of sampling, with deeper dives typically producing longer data time-series. FV01 files only include one dimension: *TIME* (Table 6). FV00 files can contain up to four time dimensions among the ones described in Table 7, with each parameter associated with one of the available dimensions (see EGO (2013)).

**Table 6 Data dimension in IMOS Ocean Gliders FV01 NetCDF files.**

Dimension	Definition
TIME	Number of time steps over which data was sampled. For Seaglider missions, this corresponds to the Science Bay time stamp. For Slocum missions, this corresponds to the CTD time stamp if recorded or the Science Bay time stamp if not.

**Table 7 Dimensions found in IMOS Ocean Gliders FV00 NetCDF files.**

Possible Dimension	Definition
EVENT_SCIENCE	Number of time steps over which some of the data was sampled. Always present, both for Seagliders and Slocums.
EVENT_NAVIGATION	Number of time steps over which some of the data was sampled. Always present, both for Seagliders and Slocums (main Bay)
EVENT_GPS	Number of time steps over which Seaglider GPS data was sampled. Always present for Seagliders, never for Slocums.
EVENT_CTD	Number of time steps over which the Slocum CTD data was sampled. Never present for Seagliders, present for Slocums if the glider was configured to record the CTD time stamp.
EVENT_OXY	Number of time steps over which the Slocum Optode data was sampled. Never present for Seagliders, present for Slocums if the glider was configured to record the Optode time stamp.
EVENT_WETLABS	Number of time steps over which the Slocum ECO-triplet data was sampled. Never present for Seagliders, present for Slocums if the glider was configured to record the ECO-triplet time stamp.

### 3.1.5 Variables

This section contains information about the various types of data recorded during data sampling. Table 8 lists IMOS Ocean Gliders' variables with their attributes. Please refer to Mancini *et al.* (2016) for further details.

**Table 8 Variable attributes in FV01 NetCDF files.**

Variable	Attributes	Definition
TIME	double TIME (TIME); TIME.standard_name = 'time'; TIME.long_name = 'time from the CTD'; TIME.units = 'days since 1950-01-01 00:00:00 UTC';	Time at which <PARAM> measurements were made. Values are recorded as days since 12 am of 1 <sup>st</sup> January 1950.

	<p>TIME.axis = 'T';</p> <p>TIME.valid_min = 0;</p> <p>TIME.valid_max = 90000.0;</p> <p>TIME.calendar = 'gregorian';</p> <p>TIME.ancillary_variables = 'TIME_quality_control';</p> <p>TIME.observation_type = 'measured';</p> <p>TIME_quality_control_set = 1;</p> <p>TIME.quality_control_indicator = 1;</p>	<p>Information on the <i>quality_control_set</i> is found in Table 10 (usually '1', i.e. IMOS standard using IODE flags).</p>
LATITUDE	<p>double LATITUDE(TIME);</p> <p>LATITUDE.standard_name = 'latitude';</p> <p>LATITUDE.long_name = 'latitude';</p> <p>LATITUDE.units = 'degrees_north';</p> <p>LATITUDE.axis = 'Y';</p> <p>LATITUDE.valid_min = -90;</p> <p>LATITUDE.valid_max = 90;</p> <p>LATITUDE._FillValue = 99999.0;</p> <p>LATITUDE.comment = 'obtained from GPS fixes';</p> <p>LATITUDE.reference_datum = 'geographical coordinates, WGS84 projection';</p> <p>LATITUDE.ancillary_variables = 'LATITUDE_quality_control';</p> <p>LATITUDE.observation_type = 'measured';</p> <p>LATITUDE.quality_control_set = 1;</p> <p>LATITUDE.quality_control_indicator = 1;</p>	<p>Estimates of latitudinal position based on the position at the surface.</p> <p>Information on the <i>quality_control_set</i> is found in Table 10 (usually '1', i.e. IMOS standard using IODE flags).</p>
LONGITUDE	<p>double LONGITUDE(TIME);</p> <p>LONGITUDE.standard_name = 'longitude';</p> <p>LONGITUDE.long_name = 'longitude';</p> <p>LONGITUDE.units = 'degrees_east';</p> <p>LONGITUDE.axis = 'X';</p> <p>LONGITUDE.valid_min = -180;</p> <p>LONGITUDE.valid_max = 180;</p> <p>LONGITUDE._FillValue = 99999.0;</p>	<p>Estimates of longitudinal position based on the position at the surface.</p> <p>Information on the <i>quality_control_set</i> is found in Table 10 (usually '1', i.e. IMOS standard using IODE flags).</p>

	<p>LONGITUDE.comment = 'obtained from GPS fixes';</p> <p>LONGITUDE.reference_datum = 'geographical coordinates, WGS84 projection';</p> <p>LONGITUDE.ancillary_variables = 'LATITUDE_quality_control';</p> <p>LONGITUDE.observation_type = 'measured';</p> <p>LONGITUDE.quality_control_set = 1;</p> <p>LONGITUDE.quality_control_indicator = 1;</p>	
PRES	<p>double PRES(TIME);</p> <p>PRES.standard_name = 'sea_water_pressure';</p> <p>PRES.long_name = 'sea_water_pressure';</p> <p>PRES.units = 'dbar';</p> <p>PRES._FillValue = 99999.0;</p> <p>PRES.valid_min = -5;</p> <p>PRES.valid_max = 1100;</p> <p>PRES.coordinates = 'TIME LATITUDE LONGITUDE DEPTH';</p> <p>PRES.comment = 'pressure measured by the CTD';</p> <p>PRES.ancillary_variables = 'PRES_quality_control';</p> <p>PRES.observation_type = 'measured';</p> <p>PRES.quality_control_set = 1;</p> <p>PRES.quality_control_indicator = 1;</p>	<p>Pressure values are recorded in decibars downward from the sea surface (when available, the pressure recorded is the one measured by the CTD).</p> <p>Information on the <i>quality_control_set</i> is found in Table 10 (usually '1', i.e. IMOS standard using IODE flags).</p>
DEPTH	<p>double DEPTH(TIME);</p> <p>DEPTH.standard_name = 'depth';</p> <p>DEPTH.long_name = 'depth';</p> <p>DEPTH.units = 'm';</p> <p>DEPTH._FillValue = 99999.0;</p> <p>DEPTH.valid_min = -5;</p> <p>DEPTH.valid_max = 1000;</p> <p>DEPTH.positive = 'down';</p> <p>DEPTH.axis = 'Z';</p> <p>DEPTH.reference_datum = 'sea surface';</p>	<p>Depths computed from latitude and relative pressure measurements.</p> <p>Information on the <i>quality_control_set</i> is found in Table 10 (usually '1', i.e. IMOS standard using IODE flags).</p>



	<pre>DEPTH.ancillary_variables = 'DEPTH_quality_control'; DEPTH.observation_type = 'computed'; DEPTH.quality_control_set = 1; DEPTH.quality_control_indicator = 1; DEPTH.comment = 'Depth computed using the Gibbs-SeaWater toolbox (TEOS- 10) v3.02, from latitude and relative pressure measurements';</pre>	
<PARAM>	<pre>double &lt;PARAM&gt;(TIME); &lt;PARAM&gt;.standard_name<sup>4</sup> = '&lt;X&gt;'; &lt;PARAM&gt;.long_name = '&lt;X&gt;'; &lt;PARAM&gt;.units = '&lt;X&gt;'; &lt;PARAM&gt;._FillValue = 99999.0; &lt;PARAM&gt;.valid_min = &lt;X&gt;; &lt;PARAM&gt;.valid_max = &lt;X&gt;; &lt;PARAM&gt;.coordinates = &lt;X&gt;; &lt;PARAM&gt;.ancillary_variables = '&lt;X&gt;'; &lt;PARAM&gt;.observation_type = 'measured'; &lt;PARAM&gt;.quality_control_set = 1; &lt;PARAM&gt;.quality_control_indicator = 1; &lt;PARAM&gt;.comment = ' ';</pre>	<p>&lt;PARAM&gt; contains the values of a parameter listed in Table 9.</p> <p>&lt;X&gt; : this field is specified in Table 9.</p> <p>The observation_type is either 'measured' if the parameter directly comes from the sensor, or 'computed' if not.</p> <p>Information on the <i>quality_control_set</i> is found in Table 10 (usually '1', i.e. IMOS standard using IODE flags).</p>
<PARAM_quality_control>	<pre>double &lt;PARAM_quality_control&gt; (TIME); &lt;PARAM_quality_control&gt; .standard_name<sup>1</sup> = ' &lt;PARAM&gt;.standard_name status_flag'; &lt;PARAM_quality_control&gt; .long_name = 'quality flag for &lt;PARAM&gt;.standard_name'; &lt;PARAM_quality_control&gt;.quality_control_set = 1; &lt;PARAM_quality_control&gt;.quality_control_conventions = 'IMOS standard flags'; &lt;PARAM_quality_control&gt;._FillValue = 99; &lt;PARAM_quality_control&gt;.valid_min = 0; &lt;PARAM_quality_control&gt;.valid_max = 9;</pre>	<p>Quality flag applied on the &lt;PARAM&gt; values.</p> <p>Information on the <i>quality_control_set</i> is found in Table 10 (usually '1', i.e. IMOS standard using IODE flags).</p> <p>Meaning of quality_control flag values is found in Table 11.</p>

<sup>4</sup> <PARAM>.standard\_name is not used if the parameter does not have a CF standard name.

	<PARAM_quality_control>.flag_values = [0,1,2,3,4,5,6,7,8,9];  <PARAM_quality_control>.flag_meanings = 'no_qc_performed good_data probably_good_data bad_data_that_are_potentially_correctable bad_data value_changed not_used not_used interpolated_values missing_values';	
--	---	--

The parameter codes used for IMOS Ocean Gliders data management (FV01 files) other than *LONGITUDE*, *LATITUDE*, *PRES*, *DEPTH* and *TIME* are defined in Table 9. Some of these parameters are directly measured by the sensors, whereas some others are calculated from raw parameters.

**Table 9 Parameters measured as time-series by sensors on IMOS gliders.**

code	standard_name / long_name (for non-CF)	observation _type	_FillValue	valid _min	valid_ max	coordinates	Ancillary _variables	units
CNDC	sea_water_electrical_con ductivity	measured	99999	0	60	TIME LATITUDE LONGITUDE DEPTH	CNDC_quality_co ntrol	S m <sup>-1</sup>
TEMP	sea_water_temperature	measured	99999	-2.5	40	TIME LATITUDE LONGITUDE DEPTH	TEMP_quality_co ntrol	Celsius
PRES	sea_water_pressure	measured	99999	-5	1100	TIME LATITUDE LONGITUDE DEPTH	PRES_quality_co ntrol	dbar
BBP	particle_backscattering_c oefficient	computed	99999	0	1	TIME LATITUDE LONGITUDE DEPTH	BBP_quality_cont rol	m <sup>-1</sup>
PSAL	sea_water_salinity	computed	99999	2	41	TIME LATITUDE LONGITUDE DEPTH	PSAL_quality_con trol	1e <sup>-3</sup>
DOX1	mole_concentration_of_d issolved_molecular_oxyge n_in_sea_water	measured (SG) computed (SL)	99999	0	650	TIME LATITUDE LONGITUDE DEPTH	DOX1_quality_co ntrol	umol l <sup>-1</sup>
DOX2	moles_of_oxygen_per_un it_mass_in_sea_water	computed	99999	0	650	TIME LATITUDE LONGITUDE DEPTH	DOX2_quality_co ntrol	umol kg <sup>-1</sup>
CPHL	mass_concentration_of_c hlorophyll_in_sea_water	computed	99999	0	100	TIME LATITUDE	CPHL_quality_co ntrol	mg m <sup>-3</sup>

						LONGITUDE DEPTH		
CDOM	concentration_of_colored_dissolved_organic_matter_in_sea_water_expressed_as_equivalent_mass_fraction_of_quinine_sulfate_dihydrate	computed	99999	0	400	TIME LATITUDE LONGITUDE DEPTH	CDOM_quality_control	1e <sup>-9</sup>
≠VBSC	volumetric_scattering_function	computed	99999	0	0.1	TIME LATITUDE LONGITUDE DEPTH	VBSC_quality_control	m <sup>-1</sup> sr <sup>-1</sup>
≠IRRADxx*	downwelling_spectral_irradiance_in_sea_water_beamn*	computed	99999	0	1000	TIME LATITUDE LONGITUDE DEPTH	IRRADxx*_quality_control	uW cm <sup>-2</sup> nm <sup>-1</sup>
≠HEAD	vehicle_heading	measured	99999	0	360	TIME LATITUDE LONGITUDE	HEAD_quality_control	Degrees
UCUR	eastward_sea_water_velocity	computed	99999	-10	10	TIME LATITUDE LONGITUDE	UCUR_quality_control	m s <sup>-1</sup>
VCUR	northward_sea_water_velocity	computed	99999	-10	10	TIME LATITUDE LONGITUDE	VCUR_quality_control	m s <sup>-1</sup>
≠UCUR_GPS	eastward_surface_sea_water_velocity	computed	99999	-10	10	TIME LATITUDE LONGITUDE	UCUR_GPS_quality_control	m s <sup>-1</sup>
≠VCUR_GPS	northward_surface_sea_water_velocity	computed	99999	-10	10	TIME LATITUDE LONGITUDE	VCUR_GPS_quality_control	m s <sup>-1</sup>
≠PHASE	glider_trajectory_phase_code	computed	99	0	6	TIME LATITUDE LONGITUDE	PHASE_quality_control PROFILE	no unit
≠PROFILE	glider_trajectory_profile_number	computed	999999	0	900000	TIME LATITUDE LONGITUDE	PROFILE_quality_control PHASE	No unit

≠ indicates a non-CF parameter. These parameters do not have associated standard names. Instead, *long\_name* is listed.

\* the codes are wave length dependant. In total we have 7 generic wavelengths, i.e. IRRAD443, IRRAD490, IRRAD555, IRRAD670, IRRAD456, IRRAD 470 and IRRAD520. The real wavelength, slightly different from the generic one (and differs from one sensor SN to another), is specified in the *comment* attribute of the corresponding parameter.

+ n indicates the beam number, e.g. 1, 2, 3 or 4.

### 3.1.6 Quality control flags

The attribute *quality\_control\_set* shows the quality control flags set used in the dataset (Table 10). IMOS Ocean Gliders Facility uses Set Number 1.

**Table 10 List of QC flags sets used in the IMOS project (Mancini *et al.* (2016)).**

Set Number	Description
1	IMOS standard set using the IODE flags
2	ARGO quality control procedure
3	BOM (SST and Air-Sea flux) quality control procedure
4	WOCE quality control procedure (Multidisciplinary Underway Network – CO <sub>2</sub> measurements)

Thus, values stored in *<PARAM>\_quality\_control* show the quality of data according to flags stated in Table 11. When all flags in *<PARAM>\_quality\_control* are constant, that constant value is recorded in the attribute *quality\_control\_indicator* associated with the corresponding *<PARAM>*.

**Table 11 IODE<sup>5</sup> flags used in flagging IMOS Ocean Gliders data (after Mancini *et al.*, 2016).**

Flag value	Meaning	Description
0	No QC performed	The level at which all data enter the working archive. They have not yet been quality controlled.
1	Good data	Top quality data in which no malfunctions have been identified and all real features have been verified during the quality control process.
2	Probably good data	Good data in which some features (probably real) are present but these are unconfirmed. Code 2 data are also data in which minor malfunctions may be present but these errors are small and/or can be successfully corrected without seriously affecting the overall quality of the data.

<sup>5</sup> IODE is the International Oceanographic Data and Information Exchange.

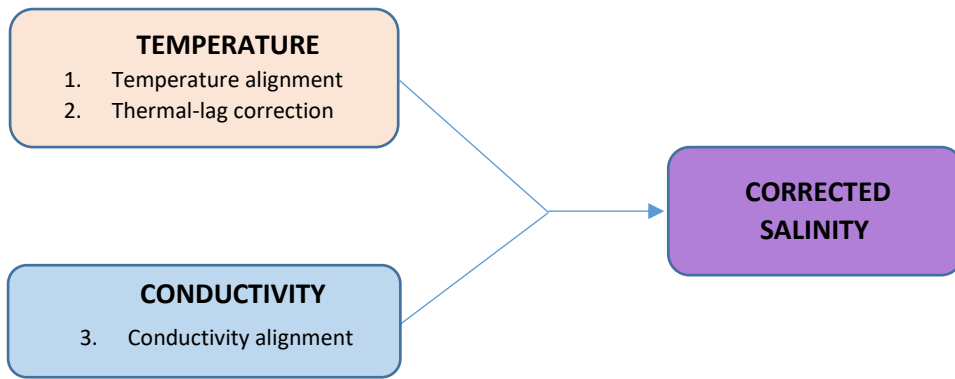
3	Bad data that are potentially correctable	Suspect data in which unusual, and probably erroneous features are observed.
4	Bad data	Obviously erroneous values are observed.
5	Value changed	Altered by a QC centre, with original values (before the change) preserved in the history record of the profile.
6	Not used	Reserved for future use.
7	Not used	Reserved for future use.
8	Interpolated value	Indicates that data values are interpolated.
9	Missing Value	Indicates that the element is missing.

### 3.2 Automated data corrections

In version 4.0 and above of IMOS Ocean Gliders data processing, the data officer can choose to apply corrections on Slocum CTD and Optode data. Indeed, the Seaglider processing chain has always included scripts developed by the University of Washington where thermal lag and small scale time lags are taken into account in salinity computation. However, in Slocum data processing, before version 4.0, these considerations were missing. This section discusses automated corrections made to Slocum CTD and Optode data. Additionally, basic corrections to biogeochemical data are also shown.

#### 3.2.1 CTD corrections

Work presented by Bishop (2008), Garau et al. (2011) and Kerfoot et al. (2006) are used for automatic CTD corrections. In order to correct erroneous spiking seen in salinity values discussed in section 2.2.2, a 3-step automated correction process is employed (Figure 16).



**Figure 16 Schematic of 3-step process to correct CTD data.**

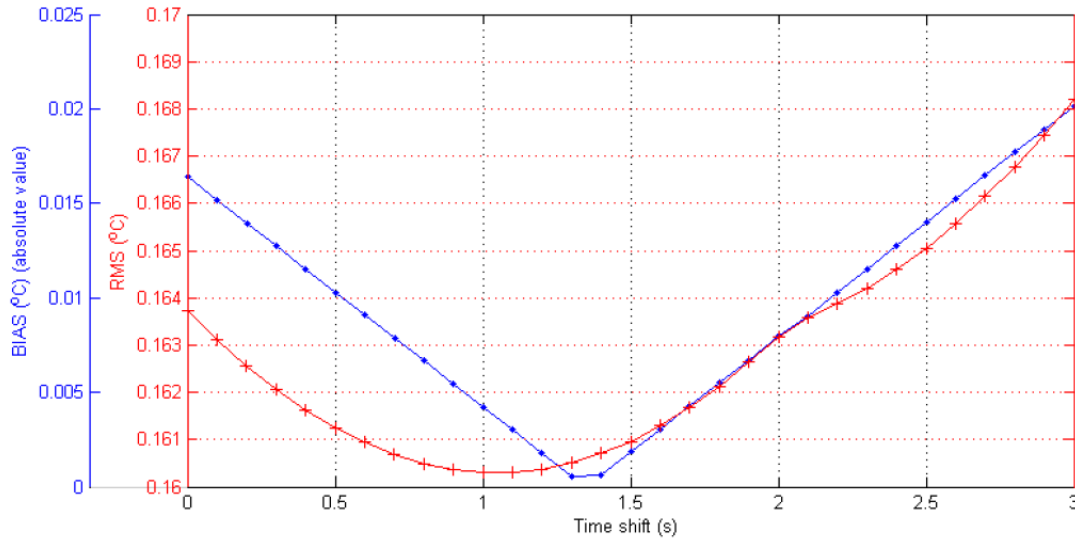
The first step (section 3.2.1.1) takes into account the temperature sensor time response and re-aligns the temperature with pressure (assuming that the pressure sensor time response is negligible). Once the best correction for temperature has been defined, we use this corrected temperature in step 2 (section 3.2.1.2) to estimate the temperature inside the conductivity cell as part of the thermal lag correction, and then finally in step 3 (section 3.2.1.3) correct the conductivity misalignment, looking for the best salinity match.

### *3.2.1.1 Temperature alignment*

Temperature is first corrected (independent of salinity) by finding the best match between down- and up-cast profiles of temperature. A linear time shift is applied to the temperature data based on a method described in Kerfoot *et al.* (2006) where they computed mean temperature profiles of 100 up-casts and 100 down-casts and compared the two mean profiles, time-shifted from 0 to 5 seconds by intervals of 0.1 seconds. The time shift value which gave the best match between the mean downcast and mean upcast profiles could then be determined. At IMOS Ocean Gliders, a similar method is applied, except that data from the entire mission is used.

The procedure is as follows:

- 1) At each 0.1 s time shift, RMS difference and BIAS values are computed for every pair of descent and ascent profile, and the median found;
- 2) The process is repeated for each subsequent time shift, resulting in a graph like Figure 17.
- 3) The temperature data is then corrected using the time shift that results in the smallest absolute BIAS (seen as the minimum point on the blue curve).



**Figure 17 Absolute value of the median BIAS and the median RMS difference between up- and down-cast temperature profiles for the Yamba October 2013 mission, as a function of time shift.**

There is usually only little difference between the minimum RMS difference and BIAS (0.2s in this case). Because the reduction in RMS difference between the original value and the minimum value is proportionally very small, the minimum BIAS value is chosen over the RMS difference value. However, both are calculated for verification purpose.

### 3.2.1.2 Thermal lag correction

#### 3.2.1.2.1 Pumped CTD

In the case of pumped CTD recorders, flow through the conductivity cell is known and constant, so we can easily apply the method of Lueck and Picklo (1990), generalised by Morison et al. (1994), which estimates temperature inside the conductivity cell and uses this temperature to compute salinity, rather than the thermistor temperature measured outside the cell. According to Lueck and Picklo (1990) the temperature inside the cell can be estimated by applying the following recursive filter:

$$T(n) = -bT(n-1) + a [ T(n) - T(n-1) ] \quad (1)$$

Where  $T_T$  is the temperature correction subtracted from the measured temperature  $T$ ,  $n$  is the sample index, and the constants  $a$  and  $b$  are:

$$a = 4f_n\alpha\tau / (1 + 4f_n\tau) \quad \text{and} \quad b = 1 - 2a/\alpha$$

Where  $f_n$  is the Nyquist frequency, i.e. half the CTD sampling interval (Kerfoot et al., 2006).

Morison et al. (1994) show that if the flow in the conductivity cell is constant,  $\alpha$  and  $\tau$  can be estimated using the following empirical relation:

$$\alpha = 0.0264 V^{-1} + 0.0135 \quad \text{and} \quad \tau = 2.7858 V^{-1/2} + 7.1499 \quad (2)$$

In the case of GPCTD recorders used in IMOS Slocum gliders, the flow rate in the conductivity cell is 10 ml/s, the volume of the cell is 3 ml and its length 146mm, which gives a velocity:

$$V = 0.4867 \text{ m s}^{-1}$$

As this velocity falls within the valid range stated by Morison et al. (1994),  $\alpha$  and  $b$  can then be computed and the temperature inside the conductivity cell derived using equations (2) and (1).

#### 3.2.1.2.2 Unpumped CTD

When correcting data from unpumped CTD,  $\alpha$  and  $\tau$  from equation (2) are computed by estimating that velocity for each profile is the same as the glider velocity of travel through the water column. Temperature within the conductivity cell is then calculated by applying equations (1) and (2).

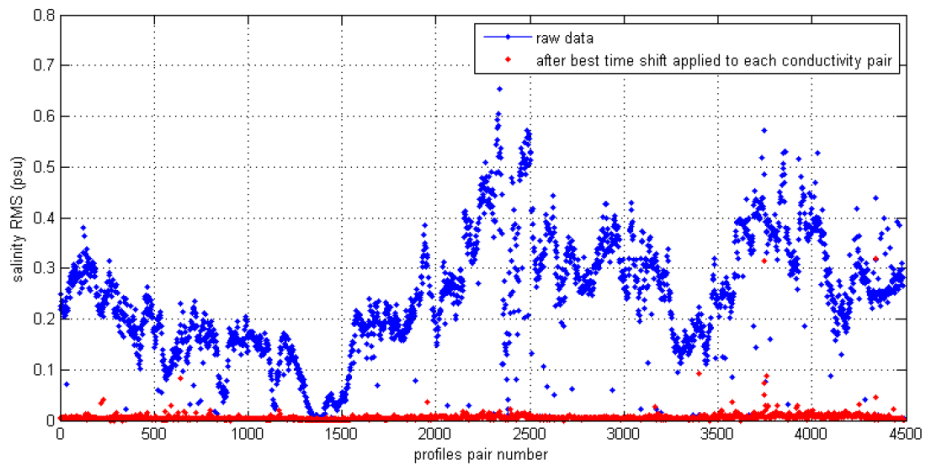
This method was chosen over the method proposed by Garau *et al.* (2011) which had been formulated as an improvement of the commonly used Morison *et al.* (1994) method so as to take into account for variable flow speed inside the conductivity cell, irregular sampling intervals etc., as an un-pumped glider-mounted CTD would have. However, our testing found that using their method did not lead to better results than when recomputing  $\alpha$  and  $\tau$  using an estimate of the glider's velocity across the water column,  $V$ , per profile. Moreover, their method was time consuming, especially when taking into account the conductivity sensor time response, which forced us to perform many iterations to get the best parameters and time lag.

#### 3.2.1.3 Conductivity alignment

Conductivity time lag is estimated after the completion of temperature alignment and thermal lag correction. It was found that conductivity time lag is not constant throughout the whole deployment. It is speculated that this may be due to geometrically induced time lag, i.e. the conductivity cell is a distance away from the pressure sensor, and pitch and dive rate of the glider are too variable on a single profile. Our efforts to correct for geometric time lag failed. The method employed for conductivity alignment which brought good results is as follows:



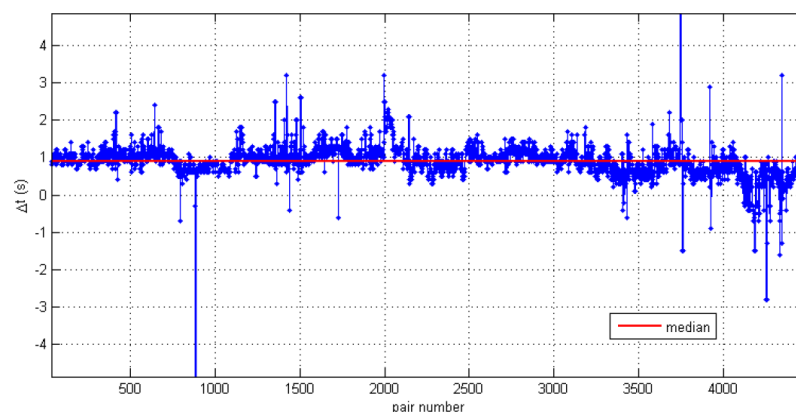
- 1) Determine the time shift in conductivity data that produces the best match (smallest RMS difference) for each individual pair of computed salinity up- and down-cast profile (values tested at increasing 0.1s time shift intervals). The RMS difference is used for this estimate rather than the BIAS value, due to the presence of spikes in salinity profiles which can change the sign of the BIAS difference between the 2 profiles of a dive-climb pair.



**Figure 18 Salinity RMS difference between consecutive up- and down-cast pair is greatly reduced by the introduction of a best time shift in conductivity data for each individual pair.**

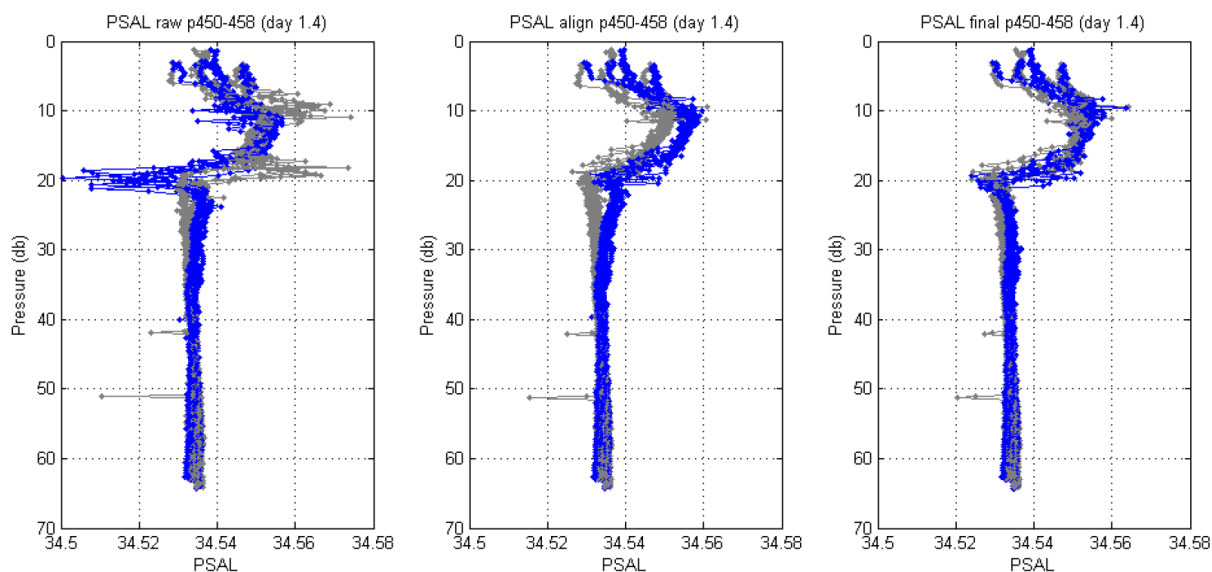
In the Yamba20120904 mission for instance, applying the best time shift for each individual dive-climb pair in conductivity data, successfully decreases the salinity RMS difference significantly from values of the order of 0.1 psu (blue dots) to the order of 0.01 psu (red dots) (Figure 18).

- 2) When a best time shift for conductivity has been determined for each and every individual dive-climb pair, their median is found (Figure 19) and applied to the entire conductivity time-series dataset to correct its alignment.



**Figure 19 Conductivity time delay (in seconds) by pair of profiles, from beginning of the Yamba20120904 mission (left) to the end mission (right). The red line is the median time shift (0.9s here).**

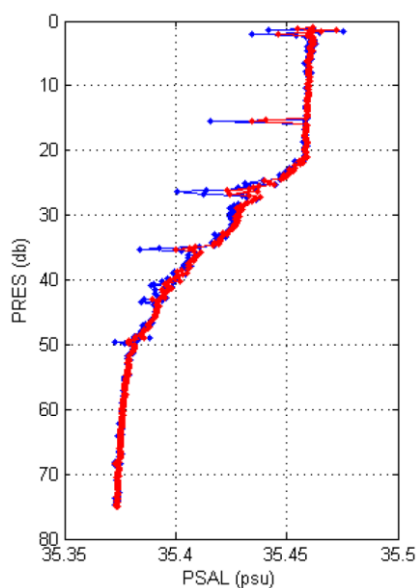
The effect of the abovementioned CTD corrections can be seen in Figure 20 where time lag corrections and thermal lag correction are applied separately to data from the Kimberley20120914 mission CTD data.



**Figure 20 (Left) Uncorrected raw salinity data from 4 profile pairs, (middle) only temperature and conductivity alignments corrected, (right) thermal lag corrected as well as temperature and conductivity alignment.**

Comparing the three plots in Figure 20, it can be seen that the erroneous spikes seen in raw data (left plot) are significantly reduced by corrections in temperature and conductivity alignment (middle plot). And this is improved further with the addition of thermal lag correction (right plot).

As a result of these corrections, much of the salinity spiking problems described in section 2.2.2 can be largely minimised (see Figure 21).



**Figure 21 Salinity profile no. 4114 from the Yamba20120904 mission: (blue) raw salinity, (red) corrected salinity.**

### 3.2.2 Oxygen Optode corrections

To improve dissolved oxygen data (MOLAR\_DOXY, as internally computed by the glider), re-computed must be performed using corrected Optode BPHASE measurements, corrected CTD temperature data and Optode calibration coefficients provided by Aanderaa for each sensor<sup>6</sup>.

The CTD temperature has now been corrected for short term mismatch with the CTD pressure (see section 3.2.1.1), so BPHASE data must also be aligned with pressure. Moreover, because the Optode is separated from the pressure sensor by a distance of 90cm on the Slocum glider (Figure 22), at typically slow speed of glider travel, this distance induces a non-negligible time difference between when the pressure and the BPHASE measurements are recorded, which needs to be accounted for (3.2.2.1). Subsequently, the lag resulting from BPHASE sensor response time must also be minimised (3.2.2.2). Finally, we combine this corrected BPHASE data with the CTD temperature and the calibration coefficients, to get the final corrected dissolved oxygen data, in  $\mu\text{mol/L}$ .

#### 3.2.2.1 Geometrical alignment

On Slocum gliders, the Optode is installed aft, close to the fin, and the CTD is installed toward the middle of the glider, close to the wings (Figure 22).

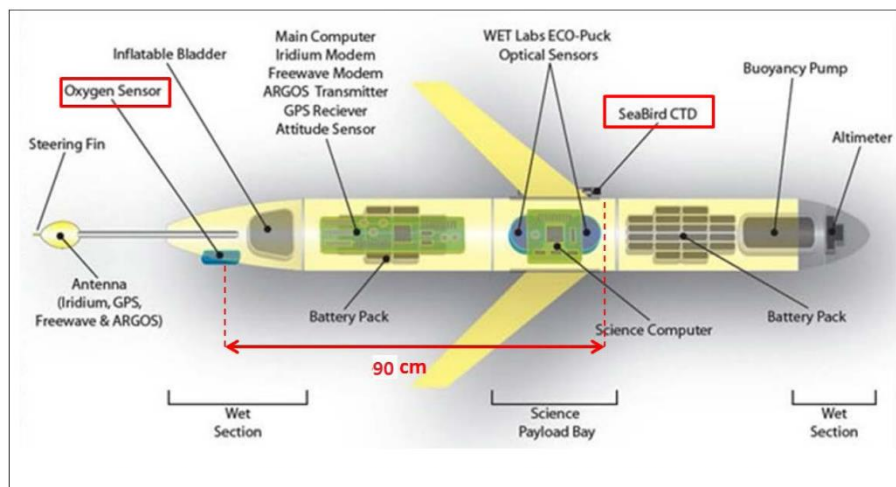


Figure 22 Schematic diagram of Slocum glider (After AUVAC, 2018).

<sup>6</sup> For this re-computation to be possible, both the temperature and BPHASE data must share the same time axis, thus linearly time-interpolated CTD temperature is used.

The time,  $\tau$ , taken to travel the 90cm distance between the Optode and CTD recorder is:

$$\tau = \frac{d}{v}$$

where  $d$  is the distance between the sensors and  $v$  is the glider velocity of travel, i.e.

$$v = \frac{r}{\sin \theta}$$

where  $r$  is dive rate (m/s) and  $\theta$  is glider pitch.

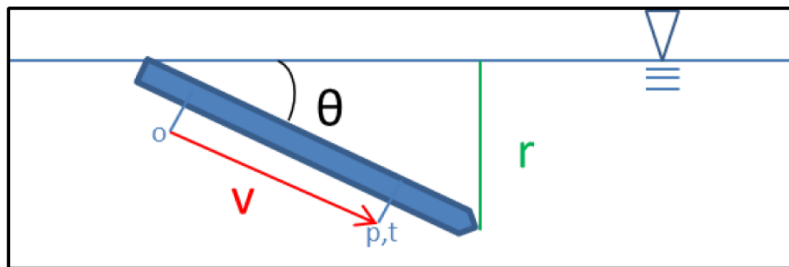


Figure 23 Glider orientation during descent. (p: pressure, t: temperature, o: oxygen)

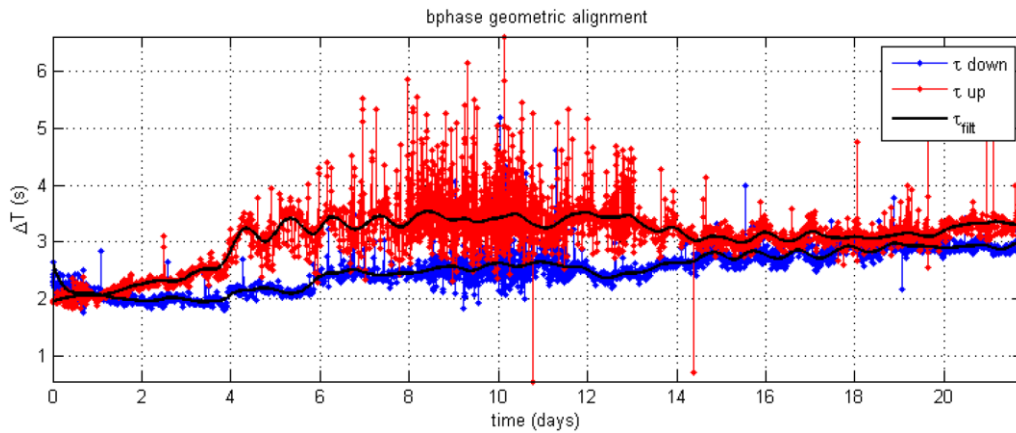
Thus, the time delay between oxygen (or BPHASE) and pressure is:

$$\tau = \frac{d \cdot \sin \theta}{r}$$

Applying the measured distance between the sensors  $d = 0.9\text{m}$ , and ideal values for glider travel,  $r = 0.1 \text{ m/s}$ ,  $\theta = 26^\circ$ ,

$$\tau = 3.9450 \text{ s}$$

However, in practice, the glider travels with varying pitch and dive rate. Depending on the ballast, the average pitch (in absolute value) on dives can significantly depart from the average pitch on climbs, so the time delay,  $\tau$ , also varies between dive and climb. Therefore, in order to account for this,  $\tau$  is found for each cast using the average pitch and dive rate on that particular cast. Then, the results for the whole mission are filtered to avoid extreme values (e.g. see Figure 24). Finally, using the filtered values of  $\tau$ , a linear time shift is applied to the BPHASE data to correct for geometrical alignment.

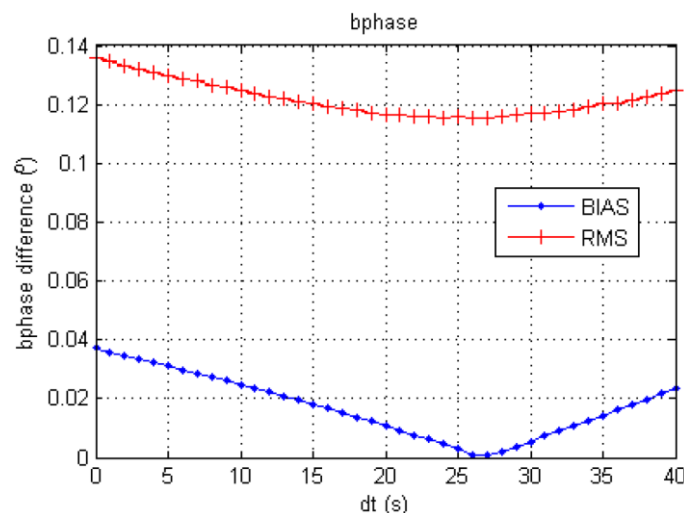


**Figure 24 Time lag between BPHASE and pressure measurements, as a timeseries over the course of the Kimberley20120727 mission. Blue: down-cast, Red: up-cast, Black: filtered values.**

### 3.2.2.2 Time lag correction

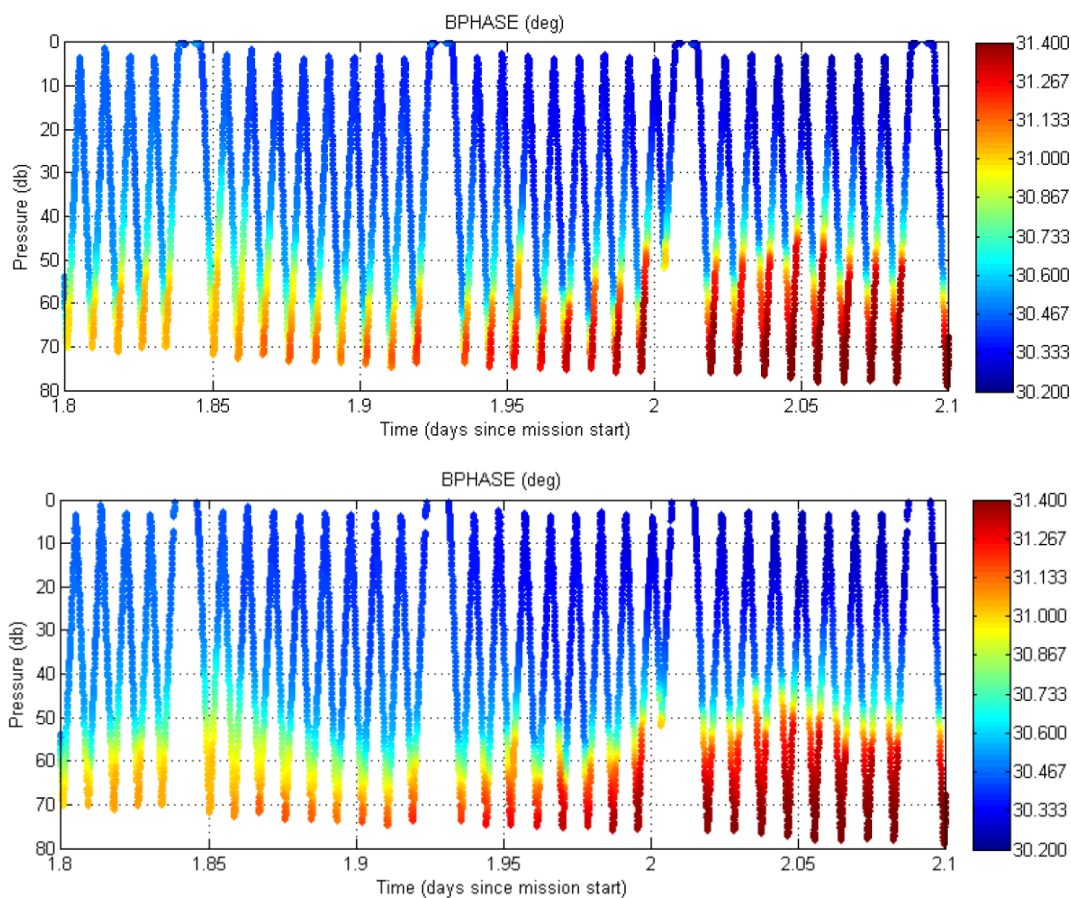
Time taken for the Optode sensor to respond while taking measurements results in a time lag that must be corrected. The lag is relatively long (of the order of 20s, according to the manufacturer). A similar method to that previously used for correcting CTD temperature time lag is also applied here to correct the time lag in the Optode BPHASE:

- 1) At each 1 s time shift, RMS difference and BIAS values are computed for every pair of descent and ascent profile, and the median found;
- 2) The process is repeated for each subsequent time shift, resulting in a graph like Figure 25.
- 3) The BPHASE data is then corrected using the time shift found to result in the smallest RMS difference value (e.g. 26s for the Kimberley20120727 mission (Figure 25)).



**Figure 25 Median values of RMS (red) difference and BIAS (blue) between up- and down-cast BPHASE (in degrees) data, plotted against time shifts applied, for the Kimberley20120727 mission.**

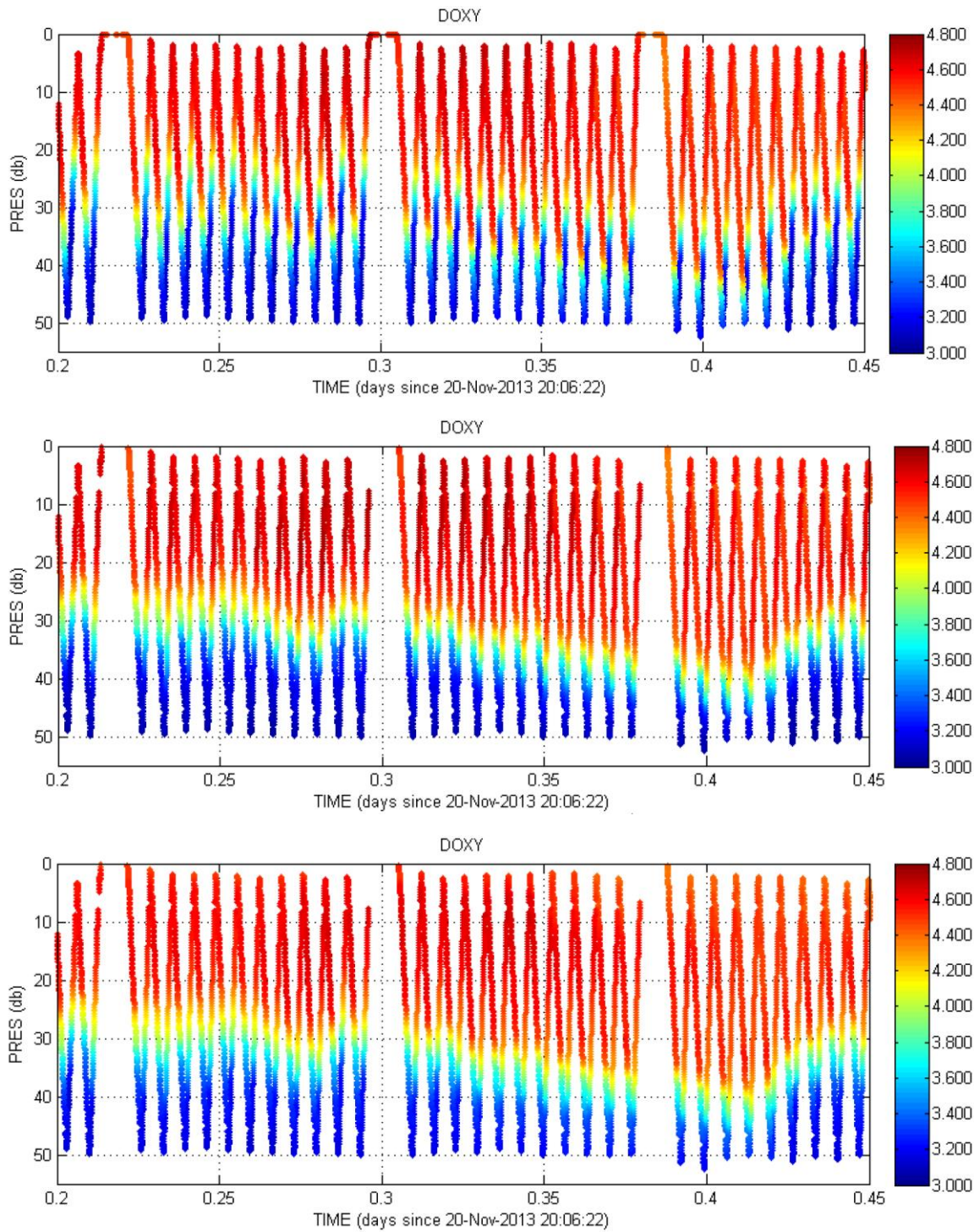
For data from the Kimberley20120727 mission, a linear time shift of 26s minimised the dissymmetry previously seen in the raw BPHASE data (Figure 26).



**Figure 26 (Top) Uncorrected BPHASE data exhibiting dissymmetry between up- and down-casts; (bottom) symmetry between up- and down-casts is improved by 26s time lag correction.**

With BPHASE corrected for geometrical lag and sensor time lag, the concentration of dissolved oxygen is finally re-computed as described in section 2.2.3, using manufacturer calibration coefficients, temperature data from the CTD instead of from the Optode (time interpolated to match with the Optode BPHASE), and with compensation for salinity effects also applied.

From Figure 27, it can be seen that the uncorrected dissolved oxygen data directly reported by the Optode (top plot) is significantly improved by corrections to BPHASE to account for geometrical and sensor lags (middle plot). Data on dive and climb profiles become much more symmetrical. Substituting Optode temperature data with CTD temperature in calculations further improves the quality of the oxygen data (bottom plot).



**Figure 27 Dissolved oxygen concentration time-series profiles that are (top) uncorrected, (middle) recomputed with geometrical and sensor lag corrections, and (bottom) recomputed using CTD temperature and corrected for geometrical and sensor lags.**

In future, our Optode data corrections will include the application of pressure compensation also (as recommended by the manufacturer).

This will involve multiplying the oxygen concentration by a factor F:

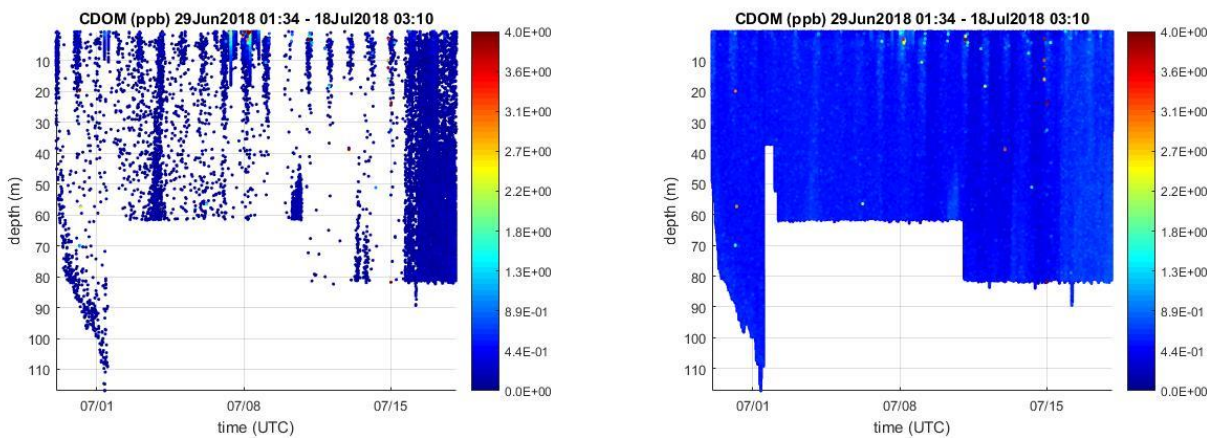
$$F = 1 + \frac{0.032 \times \text{pressure}}{1000}$$

where pressure is measured in dbar.

The pressure effect is small in shallow water ( $F=1.0064$  for 200db), but becomes more significant for deep Slocum missions where the glider reaches pressures of up to 1000db.

### 3.2.3 Bio-optical data corrections

No automatic corrections to bio-optical data are applied if less than 1% are negative values. Otherwise, the factory calibrated dark count value is corrected. This is performed to Chlorophyll-a, CDOM fluorescence and downwelling spectral irradiance data by iteratively decreasing the dark counts until less than 1% of computed values are negative. Subsequently, the corrected data are recomputed using the new dark count according to the method described in section 2.2.5.



**Figure 28 CDOM timeseries data (left) calculated with factory calibrated dark count, and (right) with corrected dark count.**

Using the factory calibrated CDOM dark count of 47 to compute CDOM values for the Forster20180629 mission resulted in loss of 93.55% of CDOM data (Figure 28, left). It was found that 41 was a more suitable dark count value, resulting in 0.21% of recomputed CDOM data being negative (Figure 28, right).



## 4 Automatic Quality Tests

This section describes a series of QC tests that are automatically run to flag scientific data.

It should be noted because GPS location fixes of the glider can be obtained only when the glider has surfaced, where the glider is travelling underwater, *LONGITUDE* and *LATITUDE* values are linearly interpolated between the 2 GPS fixes obtained at the ocean surface at either end of the submerged segment. Thus, *LONGITUDE\_quality\_control* and *LATITUDE\_quality\_control* are flagged with 8 accordingly (see Table 11). On the other hand, if some of the science data have been slightly interpolated to match with the single time dimension found in FV01 files, they are not flagged to 8.

### 4.1 Impossible date test

The impossible date test checks that time values are within the timeframe associated with the deployment (defined in the *deployment\_start\_date* and *deployment\_end\_date* attributes of the variable *DEPLOYMENT*). All data outside of this timeframe are removed from the dataset.

### 4.2 Impossible location test

The impossible location test requires that the latitude and longitude that position the observations are sensible. *LATITUDE* or *LONGITUDE* data that fail this test are flagged with 4 (Table 11).

Latitude in range -90 to 90 degrees

Longitude in range -180 to 180 degrees

Correspondingly, good scientific data recorded at unknown locations (i.e. flagged as bad or missing) then receive a flag of QC=3.

### 4.3 Range test

The range test applies a gross filter on observed values for the measured scientific parameters which must accommodate all expected extremes encountered in the oceans around Australia. Valid maxima and minima as listed in Table 9 are tested, except for the engineering parameters *HEAD*, *UCUR* and *VCUR* for which no QC is performed (QC flag = 0). A QC flag of 4 is applied to data that fail this test.

#### 4.4 Spike test

The spike test is based on Argo Data Management (Argo, 2013) for temperature and salinity. A difference between sequential measurements, where one measurement is quite different than adjacent ones, is a spike in both size and gradient. The test does not consider the differences in depth, but assumes a sampling that adequately reproduces the temperature and salinity changes with depth. The algorithm is used on both the temperature and salinity profiles.

$$\text{Test value} = | V2 - (V3 + V1)/2 | - | (V3 - V1) / 2 |$$

where V2 is the measurement being tested as a spike, and V1 and V3 are the values above and below.

Temperature:

The V2 value is flagged (QC flag = 4) when

- the test value exceeds 6.0 degree C. for pressures less than 500 db or
- the test value exceeds 2.0 degree C. for pressures greater than or equal to 500 db

Salinity:

The V2 value is flagged (QC flag = 4) when

- the test value exceeds 0.9 PSU for pressures less than 500 db or
- the test value exceeds 0.3 PSU for pressures greater than or equal to 500 db

Presently, spikes in the other data types are manually flagged, although in the initial version of the IMOS Ocean Gliders' processing code, some automatic spike flagging had been implemented. In future, this may again be used.

#### 4.5 Gradient test

This test is based on Argo Data Management (Argo, 2013). It fails when the difference between vertically adjacent measurements is too steep. The test does not consider the differences in depth, but assumes a sampling that adequately reproduces the temperature and salinity changes with depth. The algorithm is used on both the temperature and salinity profiles.

$$\text{Test value} = | V2 - (V3 + V1)/2 |$$

where V2 is the measurement being tested as a spike, and V1 and V3 are the values above and below.

Temperature: V2 value is flagged 4 when

- the test value exceeds 9.0 degree C for pressures less than 500 db or
- the test value exceeds 3.0 degree C. for pressures greater than or equal to 500 db

Salinity: V2 value is flagged 4 when

- the test value exceeds 1.5 PSU for pressures less than 500 db or
- the test value exceeds 0.5 PSU for pressures greater than or equal to 500 db

Presently, spikes in the other data types are manually flagged, although in the initial version of the IMOS Ocean Gliders' processing code, some automatic spike flagging using the gradient test had been implemented. In future, this may again be used.

#### 4.6 Surface data

The surface (0 m to 0.5m depth) Chlorophyll-a fluorescence (CPHL), downwelling irradiance (IRRADxxx), coloured dissolved organic matter concentration (CDOM), volumetric backscatter (VBSC) and particulate backscatter coefficient (BBP) data are flagged 4 because these parameters are often noisy due to surface water interactions.

#### 4.7 Descending IRRAD profiles

Radiometers are mounted on the Slocum gliders at an angle of  $-20^{\circ}$  to horizontal so that they are parallel to the ocean surface during glider ascent. Due to the cosine effect, downwelling irradiance measured on a flat plane decreases as a function of the cosine of the incoming light's average angle (Mobley, 1994; Berwald et.al, 1995; Kirk, 2011). Consequently, all descending upwelling irradiance data are flagged 4 due to incorrect orientation of the radiometer during glider descent.

## 5 Manual Corrections

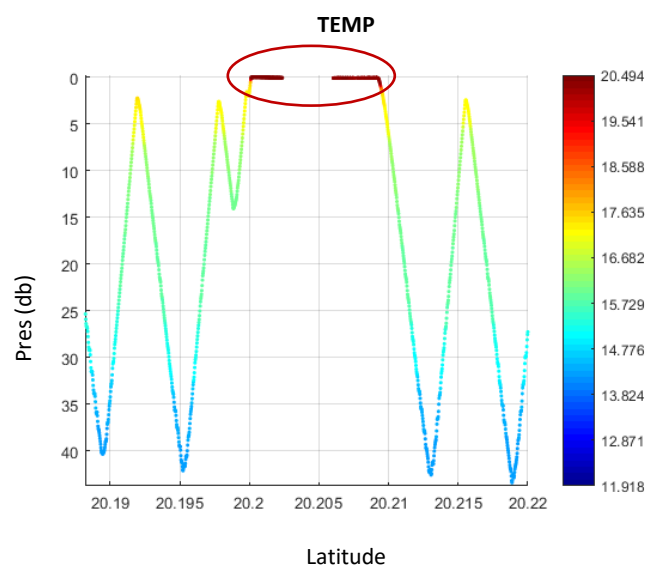
Manual quality control is by subjective visual inspection of data values by an operator. To avoid delays, this is not mandatory before real-time distribution and is only performed in delayed mode.

The parameters that are visually checked and manually flagged are: PSAL, CNDC, TEMP, DOX1 (and thus DOX2), CPHL, CDOM, VBSC, BBP and IRRADxxx. The consistency in PSAL flags is also checked knowing that PSAL is calculated from CNDC and TEMP, as well as the consistency with DOX1 and DOX2 in case oxygen has been recomputed using TEMP, the temperature from the CTD, and in any case for DOX2, whose computation depends on density, i.e. PRES, TEMP and PSAL. Similarly, consistency for BBP is also checked as its computation is dependent on VBSC, PSAL and TEMP.

Common examples of conditions where additional QC is applied:

- glider out of the water (QC flag = 4 (bad); Figure 29)
- glider sitting in the seabed (QC flag = 4 (bad); Figure 30)
- coarse outliers (QC flag = 4 (bad))
- various instrumental glitches (QC flag = 4 (bad); Figure 31, Figure 32, Figure 33)
- noise experienced due to bio-fouling or other reasons (QC flag = 4 (bad); Figure 34)
- problematic sensor lag issues (QC flag = 3 (bad but potentially correctable); Figure 35 )

Apparently anomalous segments of data may be further investigated by considering environmental and geographical factors (Figure 36), as well as additional data, e.g. Sea-surface temperature satellite imagery.



**Figure 29 Significant raise in temperature (°C) recorded due to vehicle heating while partly out of the water in surface parked position.**

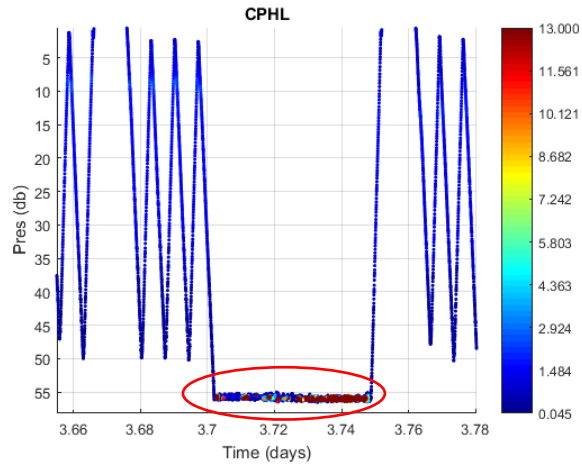


Figure 30 Fouling of chlorophyll concentration ( $\text{mg}/\text{m}^3$ ) is seen where the glider sits in the seabed.

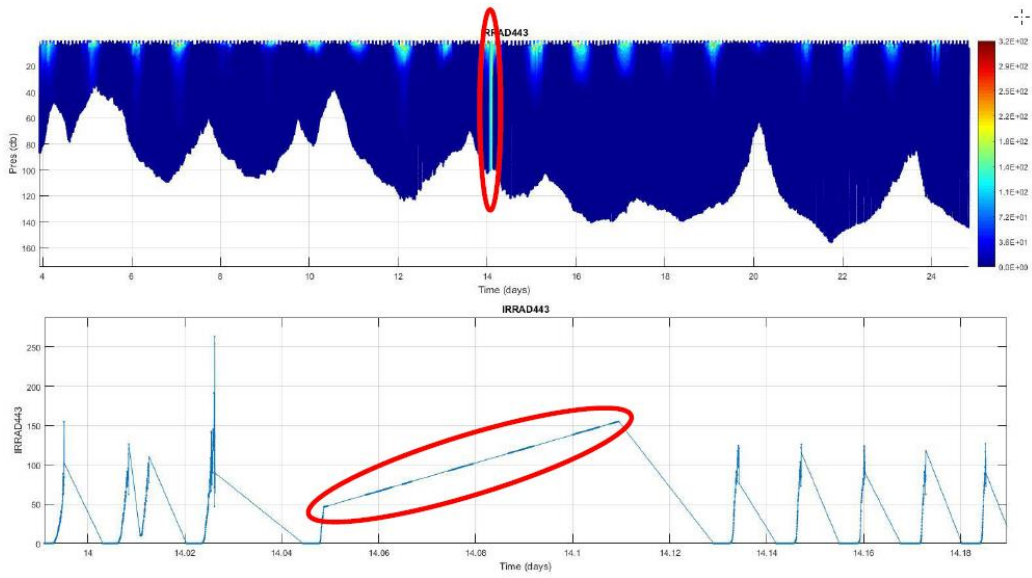


Figure 31 Linear glitch found in downwelling irradiance ( $\mu\text{W}/\text{cm}^2/\text{nm}^{-1}$ ) time-series data.

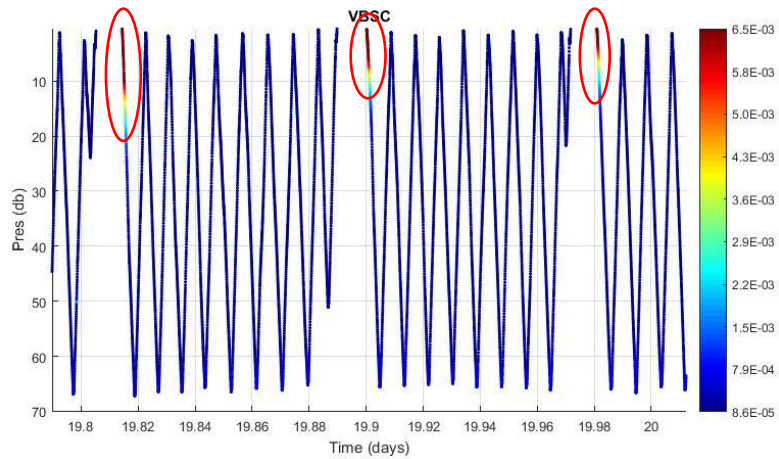
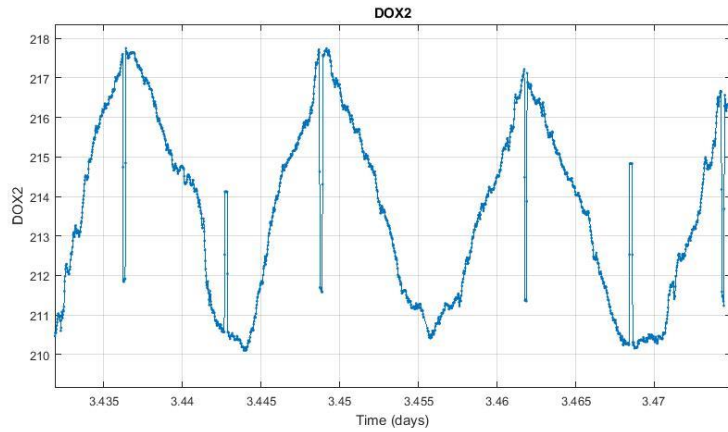
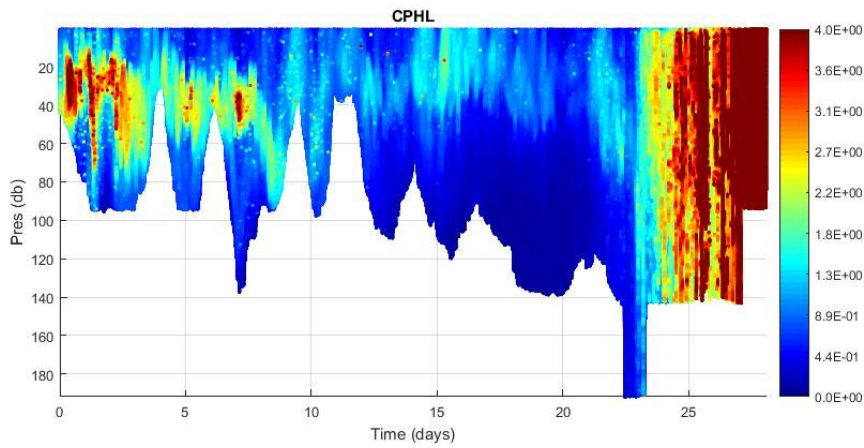


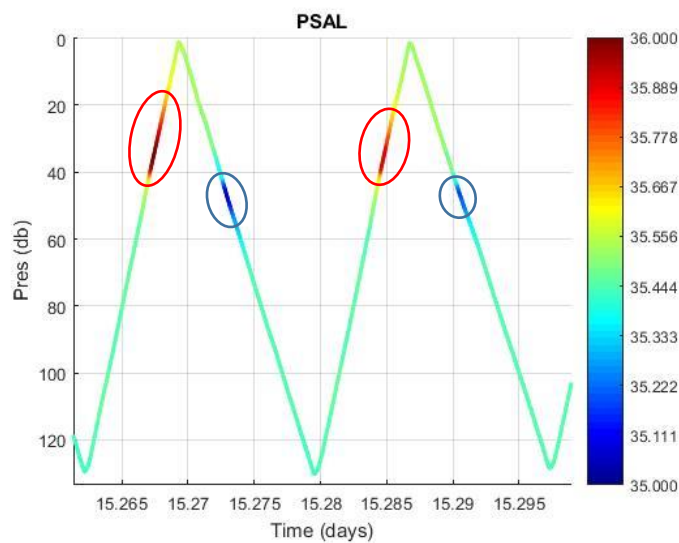
Figure 32 Streaks of raised volumetric backscatter coefficients ( $\text{m}^{-1}\text{sr}^{-1}$ ) upon first dive from the surface.



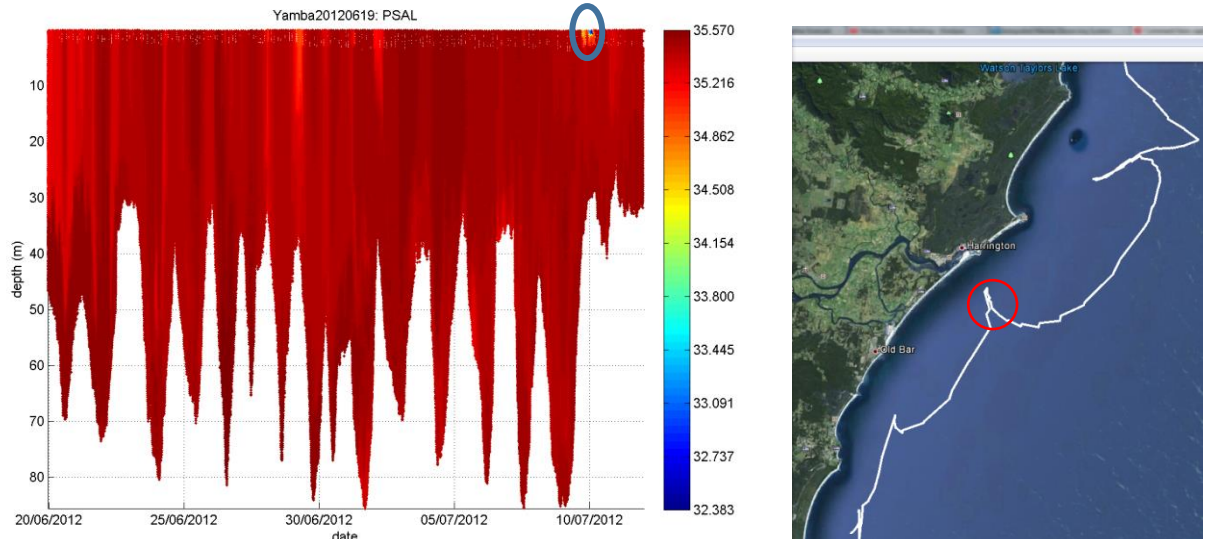
**Figure 33** Glitches seen in the vicinity of vehicle inflexion and deflection, in dissolved oxygen concentration ( $\mu\text{mol/kg}$ ) data.



**Figure 34** Extremely heavy bio-fouling seen in chlorophyll concentration ( $\text{mg/m}^3$ ) after 25 days.



**Figure 35** Positive and negative spiking (circled) in salinity data that could not be sufficiently resolved by the present automatic lag correction procedures; these occur especially the interphase between different water types.



**Figure 36** Satellite imagery confirmed the validity of an abrupt occurrence of low salinity water; (left) circled in salinity time-series data and (right) location circled in satellite geographical image (white line indicates path taken by glider).

At the end of manual quality control, the consistency of flags for TEMP, CNDC, PSAL, DOX1 and DOX2 is checked.

## 6 QC Reporting and File Submission

Each quality controlled NetCDF file (FV01) distributed in delayed mode is associated with a Quality Control report which contains information about the corrections applied to the data and their manual quality control. This report is not exhaustive and is distributed for information purposes only.

An associated FV00 NetCDF file which contains all the raw engineering parameters (not contained in the FV01 file) is also submitted to AODN, along with the raw files<sup>7</sup> from the glider, a .kml Google Earth plot of the mission path/location, data time-series plots of the quality controlled data, as well as any photographs taken of the vehicle and sensors during deployment and/or recovery.

Download IMOS Ocean Gliders NetCDF files from the AODN Portal:

<https://portal.aodn.org.au/>

<sup>7</sup> A backup copy of raw data is also stored in the UWA Institutional Research Data Store (IRDS), which is a centralised, secure and UWA-supported data storage facility in which to store electronic research data. The IRDS is supported by a dedicated high speed fibre optic connection that ensures reliable high-performance bandwidth, has secure access and includes backup and recovery capability.

## 7 Data Visualisation Tools

Two data visualisation tools: *GLIDERSCOPE* and *NetCDF Ninja*, have been developed for users of ocean glider data. Both have been designed to install on both Window and Macintosh platforms as standalone applications. No access to MATLAB software and no coding knowledge is required for these software to run.

Free software downloads available from:

<https://imos.org.au/facilities/oceangliders>

(look at the Data Tools Link)

### 7.1 GLIDERSCOPE

GLIDERSCOPE is a standalone Win/Mac software package designed to give you the power to visualise glider data effortlessly via a convenient graphical user interface. By using the freely available GLIDERSCOPE software, anyone can examine NetCDF files they have downloaded, filter out bad data, interactively isolate segments of data and apply a variety of useful data graphical visualisation techniques to examine the data (Figure 38), e.g.

- three/four-dimensional plots of water properties,
- interpolated contour charts,
- vertical profile plots,
- water properties comparison charts (e.g. TS-diagrams)
- light attenuation coefficients charts

GLIDERSCOPE performs additional calculations for Geostrophic Velocity, Buoyancy Frequency Squared, PAR, Underwater Sound Velocity, Light Attenuation Coefficient, 1% Photic Depth and Local Time Zone to further inform you. And you can make use of a host of clever on-screen tools. For example, you can drop a 'Virtual Niskin Bottle' to instantly find out what the water properties are like anywhere in your cross-section; change the look of plots by dragging on sliders or swap between different cmoccean colour maps to best highlight patterns of interest. Additionally, you can export any segment of data as text or NetCDF files for easy access in other applications

*GLIDERSCOPE* download:

<https://imos.org.au/gliderscope>

Furthermore, *GLIDERSCOPE* is supported by

- (i) A workshop paper, entitled "Observing the Ocean with Gliders: Techniques for Data Visualization and Analysis", published in *Oceanography* (Hanson *et al.*, 2017).
- (ii) *GLIDERSCOPE* instructional videos, available on The Ocean Society (TOS) channel on YouTube.



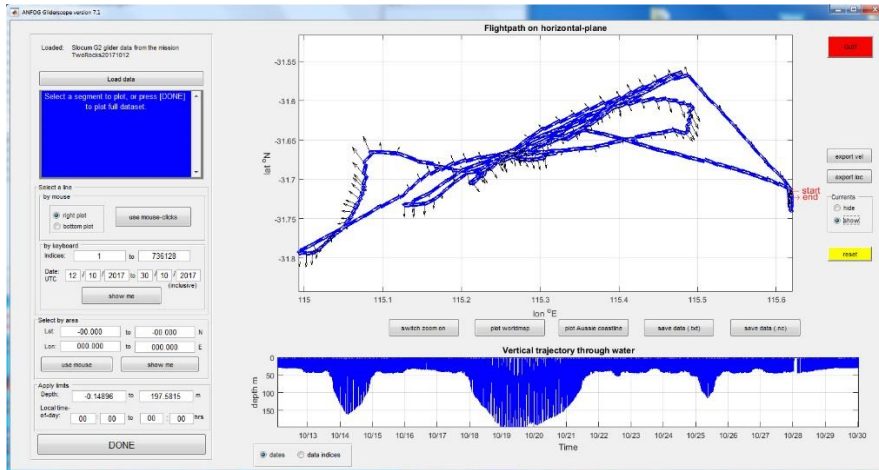


Figure 37 *GLIDERSCOPE* allows users to view the glider path and water velocity, as well as to isolate any segment of data spatially and temporally for visualisation/data export.

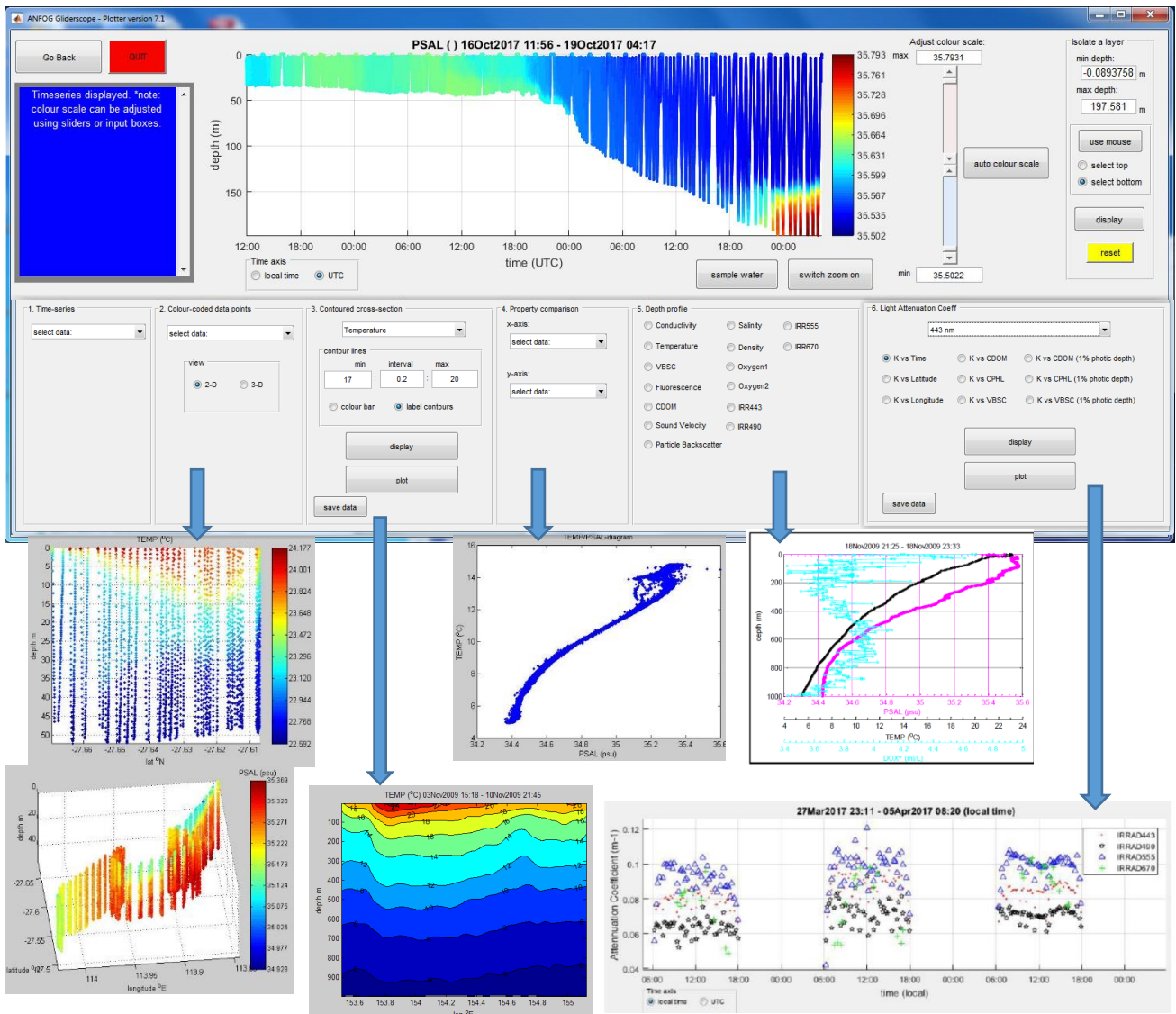


Figure 38 A variety of in-built calculations and visualisation techniques are available in *GLIDERSCOPE*.

## 7.2 NetCDF Ninja

*NetCDF Ninja* is a NetCDF file browser used for exploring and editing information in not just ocean glider data NetCDF files, but any NetCDF file. This software was created as an IMOS Ocean Gliders initiative to complement *GLIDERSCOPE*. Using *NetCDF Ninja*, all Global Attributes and Variable Attributes may be read and edited (Figure 39). Variables may be viewed graphically and individual data points read/edited. A zoom tool and sample box are also available to allow the user to scrutinise data more closely and immediately determine the range in any chosen segment of the dataset.

With the advent of the international version of *GLIDERSCOPE*, users will find that NetCDF files downloaded from certain overseas repositories sometimes contain errors (e.g. all *TIME* data are invalid since all the *TIME* values exceed the *valid\_max* stated), which make data visualisation problematic. In such cases, *NetCDF Ninja* can be used to quickly identify and correct the mistake (e.g. change the value of *valid\_max*) without any need for coding, so that the user may quickly proceed to plot and analyse the data.

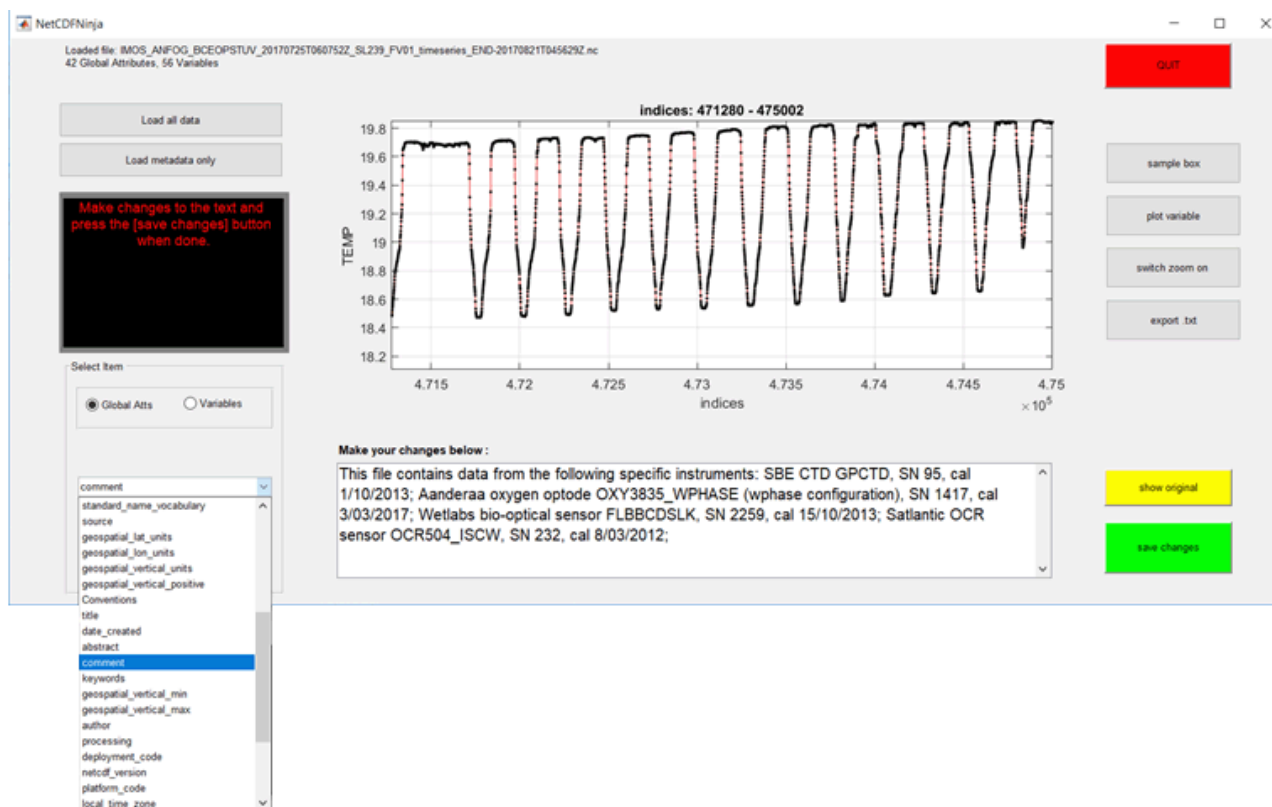


Figure 39 Dashboard of *NetCDF Ninja*.

*NetCDF Ninja* download:

<https://imos.org.au/netcdfninja>

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