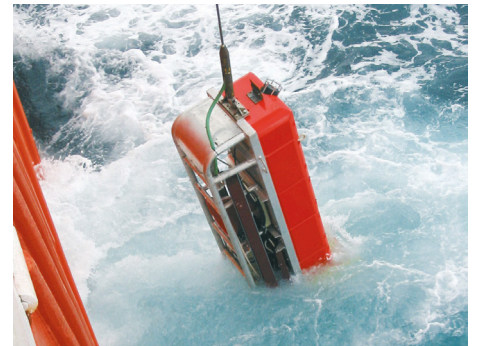


# Posidonia 2

## Ultra-deep, long-range USBL

Posidonia II is a USBL acoustic positioning system for high-accuracy / ultra-long range tracking of subsea vehicles. It offers enhanced performance with a new electronic cabinet (USBL-Box) including the most recent iXblue acoustic signal processing and full compatibility with Ramses 6000 synthetic baseline positioning system.



### FEATURES

- Extreme long-range beyond 10,000 m and 0.2% of slant distance accuracy \*
- Low frequency band, full wideband, robust to noise and multipath
- Smoothly interfaces with iXblue positioning building blocks (INS, Ramses, motion sensors)
- Full Ethernet and iXblue web-based user interface

\* Performance depends on environment/noise conditions

### BENEFITS

- Deep tow operations with no need for second tracking vessel
- High performance even in extremely adverse conditions
- Added flexibility and better performance
- Simple to deploy and operate

### APPLICATIONS

- Deep towfish tracking
- AUV, ROV and any deep sea vehicle tracking
- Pipe / cable laying operations

## SPECIFICATIONS

### Performances

Accuracy	0.2% of slant range
Range	> 10,000 m
Antenna Aperture	70/100 deg
Operating frequency	14-18 kHz

Optimum performance of Posidonia II can be achieved when used in conjunction with other iXblue navigation equipment (Octans gyrocompass or Phins/Rovins inertial navigation system).

A complete and modular navigation solution comprising Posidonia II, Ramses 6000 and Phins/Rovins offers ultimate performance with high position update rate and robust positioning.

### Characteristics

	Deployable	Flush
<b>Transmitter</b>		
Source level	190 ± 3 dB ref 1µPa	192 ± 3 dB ref 1µPa
Bandwidth	8 - 14 kHz	8 - 14 kHz
<b>Receiver</b>		
Bandwidth	14 - 18 kHz	14 - 18 kHz
Signal	M-FSK	M-FSK
Height	420 mm	245 mm (without connector)
Width Ø	580 mm	800 mm
Weight in air	34 kg	180 kg

### Performances

Man machine interface	iXblue web-based user interface and Delph RoadMap display software
Protocols	Industry standard (NMEA0183, binary)
GPS	Any external GPS, DGPS, and RTK receiver
Pitch / roll / heading	Input iXblue's inertial sensors and standard sensors
Sound velocity	Sound velocity correction (ray bending, velocity error)
Pressure sensor	External pressure sensor, optional Oceano transponder sensor
External synchronisation	Input / output

(1) Performance depends on environment / noise conditions