



TECHNICAL PAPER

STANDARDIZED UXO DEMONSTRATION SITES

G-TEK AUSTRALIA PTY LTD. TM-5 EMU/SLING

OPEN FIELD SCORING RECORD NO. 154



The TM-5 EMU/Sling detection platform as demonstrated by G-Tek Australia PTY Ltd.

The TM-5 EMU/Sling detection platform

was demonstrated by G-Tek Australia PTY Ltd.
at the Aberdeen Proving Ground
Open Field Grid Area. This technical paper
contains the results of that demonstration.

*This is a reference document only and
does not serve as an endorsement of
the demonstrator's product by the
US Army or the Standardized UXO
Technology Sites Program.*



Technologies under development for the detection and discrimination of unexploded ordnance (UXO) require testing so that their performance can be characterized. To that end, standardized test sites have been developed at Aberdeen Proving Ground, Maryland, and Yuma Proving Ground, Arizona. These test sites provide a diversity of geology, climate, terrain, and weather as well as diversity in ordnance and clutter. Testing at these sites is independently administered and analyzed by the government for the purposes of characterizing technologies, tracking performance with system development, comparing performance of different systems, and comparing performance in different environments.

The Standardized UXO Technology Demonstration Site Program is a multi-agency program spearheaded by the US Army Environmental Center. The US Army Aberdeen Test Center and the US Army Corps of Engineers Engineering Research and Development Center provide programmatic support. The program is being funded and supported by the Environmental Security Technology Certification Program, the Strategic Environmental Research and Development Program, and the Army Environmental Quality Technology Program.

DEMONSTRATOR'S SYSTEM AND DATA PROCESSING DESCRIPTION

The TM-5 EMU electromagnetic (EM) detector system may be configured with one or two sensors measuring the transient EM response. In application, two sensors were mounted in an array, oriented perpendicular to the survey direction delivering a 1.2m swath width. In the dual-sensor mode, the TM-5 EMU is operated by a single person.

The TM-5 EMU interfaces with both industry standard real-time kinetic digital Global Positioning System (DGPS) and proprietary cotton thread based odometer systems providing versatile positioning adaptable to varied terrain and vegetation conditions. It has been used successfully for over five years. The odometer remains the positioning technology of choice in adverse terrains; DGPS is preferred in open environments. Combined, they meet the requirements of most situations.

The TM-5 EMU user interface provides a continuous set of data quality monitors. There are audio and graphic displays and alarms monitoring sensor signal quality and position data quality. A key attribute of the TM-5 EMU is its virtual immunity to hot rocks.

Prior to the commencement of a survey, sensor pulse repetition frequency is swept over about 100 Hz, centered at 1200 Hz, to select the frequency corresponding to the lowest receiver RMS noise level, in order to minimize RF interference; the sensor is ground-balanced to compute ground response

parameters that are stored in memory so that the ground response may then be subtracted from the received signal in real-time and a control source known as an EMULATOR is used check that sensor signal levels are within specification.

The sensor is a monocoil acting as both transmitter and receiver, operated as a vertical magnetic dipole, with 16 turns, a diameter of 18 inches, inductance of 300 mH and resistance of 0.7 W. During surveying, the sensor coil height is maintained at an elevation of 100 mm, with the minimum HERO safe-operating height calculated to be 10 cm above ground.

The transmitted waveform consists of two different length pulses (200 ms, 3.3 A and 50 ms, 830 mA), repeated at the rate of approximately 1200 Hz. The peak pulse amplitudes are based on an application of 5 V, and at turn-off, the pulses ramp to zero in about 2-4 ms, (corresponding to the self-induced electromagnetic frequency clipped to 187 V). The theoretical bandwidth of about 500 kHz reduces to about 300 kHz after the addition of amplifiers and integrators. The detector is based on synchronous demodulation, sampling the secondary field decays over narrow integration gates. After subtracting the ground response and digitizing at approximately 60 Hz, the output is decimated to 32 samples per second that are recorded with a DGPS position at a >1 Hz rate. Amplifier gains are adjusted to provide digital output between +40% units such that background noise is set to +1 to 2 units. A low-pass filter is applied at periodic intervals to reset the background signal to a zero mean. During a traverse this filter is switched out so that the filter does not attenuate target responses, and the drift is removed from the digital record in post-processing with a high-pass filter.

The TM-5 EMU EM detector system interfaces with both industry standard real-time kinetic (RTK) DGPS and proprietary cotton thread-based odometer systems providing versatile time or position-based positioning that is adaptable to varied terrain and vegetation conditions. In both cases, where UXO detection standards of survey coverage is required, G-TEK operators use a pre-established control grid and visual sighters for straight-line navigation, and use the DGPS or odometer for data positioning only.

PERFORMANCE SUMMARY

Results for the open field test broken out by size, depth, and nonstandard ordnance are presented in the table below. Results by size and depth include both standard and nonstandard ordnance. The results by size show how well the demonstrator did at detecting/discriminating ordnance of a certain caliber range. The results are relative to the number of ordnance items emplaced. Depth is measured from the geometric center of anomalies.

The response stage results are derived from the list of anomalies above the demonstrator-provided noise level. The results for the discrimination stage are derived from the demonstrator's recommended threshold for optimizing UXO field cleanup by minimizing false digs and maximizing ordnance recovery. The lower 90 percent confidence limit on probability of detection and P_{fp} was calculated assuming that the number of detections and false positives are binomially distributed random variables. All results have been rounded to protect the ground truth. However, lower confidence limits were calculated using actual results.

SUMMARY OF OPEN FIELD RESULTS FOR TM-5 EMU

Metric	Overall	Standard	Non-Standard	By Size			By Depth, m		
				Small	Medium	Large	< 0.3	0.3 to <1	>= 1
RESPONSE STAGE									
P _d	0.65	0.70	0.55	0.65	0.65	0.65	0.80	0.60	0.30
P _d Low 90% Conf	0.62	0.67	0.50	0.60	0.58	0.59	0.77	0.56	0.23
P _{fp}	0.55	-	-	-	-	-	0.55	0.50	0.45
P _{fp} Low 90% Conf	0.52	-	-	-	-	-	0.54	0.49	0.26
BAR	1.00	-	-	-	-	-	-	-	-
DISCRIMINATION STAGE									
P _d	0.45	0.50	0.35	0.50	0.35	0.50	0.50	0.45	0.30
P _d Low 90% Conf	0.41	0.45	0.31	0.42	0.31	0.43	0.43	0.41	0.21
P _{fp}	0.55	-	-	-	-	-	0.55	0.50	0.45
P _{fp} Low 90% Conf	0.52	-	-	-	-	-	0.54	0.49	0.26
BAR	1.00	-	-	-	-	-	-	-	-

Response Stage Noise Level: 0.76
 Recommended Discrimination Stage Threshold: 0.29

Note: The recommended discrimination stage threshold values are provided by the demonstrator.

