

SkyVUE™8 (CS136)

LIDAR Ceilometer



Guarantee

This equipment is guaranteed against defects in materials and workmanship. We will repair or replace products which prove to be defective during the guarantee period as detailed on your invoice, provided they are returned to us prepaid. The guarantee will not apply to:

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- Batteries
- Any product which has been subjected to misuse, neglect, acts of God or damage in transit.

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Note that goods sent air freight are subject to Customs clearance fees which Campbell Scientific will charge to customers. In many cases, these charges are greater than the cost of the repair.



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PLEASE READ FIRST

About this manual

Please note that this SkyVUE™8 product manual describes the installation and use of the SkyVUE™8 and CS136 LIDAR Ceilometers. Please use references made in this manual to either sensor interchangeably.

Some useful conversion factors:

Area: 1 in² (square inch) = 645 mm²

Length: 1 in. (inch) = 25.4 mm
1 ft (foot) = 304.8 mm
1 yard = 0.914 m
1 mile = 1.609 km

Mass: 1 oz. (ounce) = 28.35 g
1 lb (pound weight) = 0.454 kg

Pressure: 1 psi (lb/in²) = 68.95 mb

Volume: 1 UK pint = 568.3 ml
1 UK gallon = 4.546 litres
1 US gallon = 3.785 litres

Recycling information



At the end of this product's life it should not be put in commercial or domestic refuse but sent for recycling. Any batteries contained within the product or used during the product's life should be removed from the product and also be sent to an appropriate recycling facility.

Campbell Scientific Ltd can advise on the recycling of the equipment and in some cases arrange collection and the correct disposal of it, although charges may apply for some items or territories.

For further advice or support, please contact Campbell Scientific Ltd, or your local agent.



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Safety

DANGER — MANY HAZARDS ARE ASSOCIATED WITH INSTALLING, USING, MAINTAINING, AND WORKING ON OR AROUND **TRIPODS, TOWERS, AND ANY ATTACHMENTS TO TRIPODS AND TOWERS SUCH AS SENSORS, CROSSARMS, ENCLOSURES, ANTENNAS, ETC.** FAILURE TO PROPERLY AND COMPLETELY ASSEMBLE, INSTALL, OPERATE, USE, AND MAINTAIN TRIPODS, TOWERS, AND ATTACHMENTS, AND FAILURE TO HEED WARNINGS, INCREASES THE RISK OF DEATH, ACCIDENT, SERIOUS INJURY, PROPERTY DAMAGE, AND PRODUCT FAILURE. TAKE ALL REASONABLE PRECAUTIONS TO AVOID THESE HAZARDS. CHECK WITH YOUR ORGANIZATION'S SAFETY COORDINATOR (OR POLICY) FOR PROCEDURES AND REQUIRED PROTECTIVE EQUIPMENT PRIOR TO PERFORMING ANY WORK.

Use tripods, towers, and attachments to tripods and towers only for purposes for which they are designed. Do not exceed design limits. Be familiar and comply with all instructions provided in product manuals. Manuals are available at www.campbellsci.eu or by telephoning +44(0) 1509 828 888 (UK). You are responsible for conformance with governing codes and regulations, including safety regulations, and the integrity and location of structures or land to which towers, tripods, and any attachments are attached. Installation sites should be evaluated and approved by a qualified engineer. If questions or concerns arise regarding installation, use, or maintenance of tripods, towers, attachments, or electrical connections, consult with a licensed and qualified engineer or electrician.

General

- Prior to performing site or installation work, obtain required approvals and permits. Comply with all governing structure-height regulations, such as those of the FAA in the USA.
- Use only qualified personnel for installation, use, and maintenance of tripods and towers, and any attachments to tripods and towers. The use of licensed and qualified contractors is highly recommended.
- Read all applicable instructions carefully and understand procedures thoroughly before beginning work.
- Wear a **hardhat** and **eye protection**, and take **other appropriate safety precautions** while working on or around tripods and towers.
- **Do not climb** tripods or towers at any time, and prohibit climbing by other persons. Take reasonable precautions to secure tripod and tower sites from trespassers.
- Use only manufacturer recommended parts, materials, and tools.

Utility and Electrical

- **You can be killed** or sustain serious bodily injury if the tripod, tower, or attachments you are installing, constructing, using, or maintaining, or a tool, stake, or anchor, come in **contact with overhead or underground utility lines.**
- Maintain a distance of at least one-and-one-half times structure height, or 20 feet, or the distance required by applicable law, **whichever is greater**, between overhead utility lines and the structure (tripod, tower, attachments, or tools).
- Prior to performing site or installation work, inform all utility companies and have all underground utilities marked.
- Comply with all electrical codes. Electrical equipment and related grounding devices should be installed by a licensed and qualified electrician.

Elevated Work and Weather

- Exercise extreme caution when performing elevated work.
- Use appropriate equipment and safety practices.
- During installation and maintenance, keep tower and tripod sites clear of un-trained or non-essential personnel. Take precautions to prevent elevated tools and objects from dropping.
- Do not perform any work in inclement weather, including wind, rain, snow, lightning, etc.

Maintenance

- Periodically (at least yearly) check for wear and damage, including corrosion, stress cracks, frayed cables, loose cable clamps, cable tightness, etc. and take necessary corrective actions.
- Periodically (at least yearly) check electrical ground connections.

WHILE EVERY ATTEMPT IS MADE TO EMBODY THE HIGHEST DEGREE OF SAFETY IN ALL CAMPBELL SCIENTIFIC PRODUCTS, THE CUSTOMER ASSUMES ALL RISK FROM ANY INJURY RESULTING FROM IMPROPER INSTALLATION, USE, OR MAINTENANCE OF TRIPODS, TOWERS, OR ATTACHMENTS TO TRIPODS AND TOWERS SUCH AS SENSORS, CROSSARMS, ENCLOSURES, ANTENNAS, ETC.

SkyVUE™8 Packing list

A SkyVUE™8 is delivered with the following items:

Description	Quantity
Ceilometer	1
Power supply cable	1
Data cable	1
Bolt, sleeve anchor	4
Cable USB Type A plug to USB Type B plug 2 m	1

Contents

PDF viewers note: These page numbers refer to the printed version of this document. Use the Adobe Acrobat® bookmarks tab for links to specific sections.

Section 1. General Information	1
1.1 General Safety	1
1.2 Sensor Unit Safety	1
1.3 Laser Safety	2
1.4 Electrical Safety	3
Section 2. Product Overview	4
2.1 Introduction	4
2.1.1 Overview	4
2.1.2 Cloud height detection	5
2.1.3 Sky condition	6
2.1.4 Backscatter profile reporting	6
2.2 Optical Measurement	7
2.2.1 Optical Arrangement	7
2.3 Internal Monitoring	7
2.4 Specifications	7
2.4.1 Measurement Specifications	7
2.4.2 Mechanical Specifications	8
2.4.3 Electrical Specifications	9
2.4.4 Optical Specifications	10
2.4.5 Environmental Specifications	10
2.4.6 Communications Specifications	10
Section 3. Initial preparation and checks	11
Section 4. Installation	12
4.1 Location and Orientation	12
4.2 Grounding	12
4.3 Mounting the SkyVUE™8	12
4.4 Tilt Angle	14
4.5 Connectors and wiring	15
4.5.1 Base connectors	15
4.5.2 Wiring using supplied Campbell Scientific Cables	16
4.5.3 USB connection	18
4.5.4 I/O connection	18
4.6 Connecting the Back-up Battery	19
4.7 Bird Spike Kit	20
4.8 Storage Information	21
Section 5. Operation	22
5.1 Terminal Mode	22
5.1.1 Entering / Exiting the SkyVUE™8 Terminal Mode	22
5.1.2 Terminal Mode Commands General	22
5.1.3 Terminal Mode Command Examples	23
5.1.4 MCFG Command Message Types	30
5.1.5 Measurement and message intervals	30
5.1.6 STATUS Command	32
5.1.7 Message Polling	35

5.1.8	Loading a New Operating System (OS)	36
5.1.9	Stratocumulus backscatter calibration	37
5.1.10	CRC-16 Codes on terminal commands	38
5.1.11	Service command	39
5.1.12	Locked features	40
5.2	Restoring Factory Defaults	40
5.3	LED Indicator	41

Section 6. Messages41

6.1	Data Messages General	41
6.2	Checksums used in SkyVUE™8 messages	41
6.3	CS Messages	43
6.4	CL31 Messages	56
6.5	CT25K Messages	64

Section 7. Maintenance69

7.1	General	69
7.2	Cleaning	69
7.3	Diagnostic LED Indicators Within the Enclosure	70
7.4	Electrical Safety Testing	71

Figures

1-1.	Location of laser warning label	3
2-1.	Principle of operation	7
2-2.	SkyVUE™8 Dimensions	7
2-3.	PSU	9
4-1.	Mounting base footprint	13
4-2.	Setting the tilt angle	14
4-3.	Connector layout	15
4-4.	Cable Connections	18
4-5.	USB port	19
4-6.	Connecting Battery	19
4-7.	Ceilometer Bird Spike Kit installed	20
4-8.	Preparing the SkyVUE™8 for Installing the Bird Spikes	20
4-9.	Attaching Bird Spikes to the SkyVUE™8 cowl	21
5-1.	Restoring factory defaults	40
5-2.	LED indicator	41
7-3.	Diagnostic LED indicators	70

Tables

4-1.	Function of the connector pins	16
5-1.	Summary of the terminal mode commands available	24
5-2.	Summary of message ID and descriptions	30

Appendix

A.	Example CRBasic programs	A-1
B.	Measurement of the attenuated backscatter profile	B-1
C.	Cloud height calculation	C-1
D.	Sky condition algorithm description	D-1

SkyVUE™8 (CS136) LIDAR Ceilometer



Important Safety Instructions – please request a translation or further advice if you cannot understand this document.

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1. General Information

1.1 General Safety

This manual provides important safety considerations for the installation, operation and maintenance of the SkyVUE™8. These safety considerations are classified into three levels:

WARNING	Warnings alert the installer or user to serious hazards. Ignoring these warnings could result in injury or death and/or irrevocable damage to the sensor unit.
CAUTION	Cautions warn of potential hazards. Ignoring these cautions could result in the sensor being damaged and data being lost.
NOTE	Notes highlight useful information in the installation, use and maintenance of this product. These should be followed carefully in order to gain the maximum benefit from the use of this product.

1.2 Sensor Unit Safety

The SkyVUE™8 sensor has been checked for safety before leaving the factory and contains no internally replaceable or modifiable parts.

- WARNING** Do not modify the SkyVUE™8 unit. Such modifications will lead to damage of the unit and could expose users to dangerous light levels and voltages.
-
- WARNING** Do not attempt to repair the SkyVUE™8 unit without consulting Campbell Scientific.
-
- CAUTION** Ensure that the correct voltage supply is provided to the sensor.
-

1.3 Laser Safety

The SkyVUE™8 sensor incorporates an InGaAs laser diode which is rated as a class 3B device. This is an embedded laser where the output from the sensor unit, through the optics, is minimised to class 1M. This classification indicates that viewing of the beam with the naked eye is safe but looking directly into the beam with optical instruments, e.g. binoculars can be dangerous.

From the laser head the output has the following characteristics:

Maximum average power: 15.0 mW (through 50 mm)

Maximum pulse energy: 1500 nJ (through 50 mm)

Pulse duration: 100 ns

Pulse frequency: 10 kHz

Wavelength: 912 nm +/- 5 nm

Tested to: EN 60825-1:2014

Half angle divergence: 0.44 mrad

The sensor is marked with the following warning information:

INVISIBLE LASER RADIATION
DO NOT VIEW DIRECTLY WITH OPTICAL INSTRUMENTS
CLASS 1M LASER PRODUCT
IEC/EN 60825-1:2014

- WARNING** Removing the laser module with the power applied to the SkyVUE™8 or battery connected may expose the user to hazardous class 3B laser radiation.
- No attempt should be made to operate the laser module outside of the housing.
-
- WARNING** Annually, check that the laser warning label on the sensor is still visible and can be clearly read.
- When installing the sensor avoid pointing the laser housing towards areas where binoculars are in common use.
-

WARNING Use of controls or adjustments or performance of procedures other than those specified herein may result in hazardous radiation exposure.



Fig 1.1 Location of laser warning label

Before removing the laser module, the sensor must be disconnected from both the mains supply and the battery to ensure that the laser is turned off.

1.4 Electrical Safety

As the sensor is powered from potentially hazardous mains voltages the wiring of its power supply should only be carried out by personnel qualified to install electrical equipment. For permanent installations outside, this usually requires a certified electrician who is also familiar with local electrical and safety legislation. Some general guidance is given in [Section 4.5](#), but the responsibility for the installation lies with that installer.

The unit is tested for electrical safety before despatch but may need subsequent testing according to local practice.

NOTE The unit should only be serviced by trained personnel.

WARNING Removal of electronic module covers or connectors while the unit is powered will expose the operator to potentially hazardous voltages and risk damage to the sensor.

The SkyVUE™8 has electrical and laser warning labels on the exterior and interior of the unit.

It is fitted with a hex-key access panel. It is recommended that the hood and access panel door are not opened in conditions of rain, hail or snow.

The sensor should be isolated before internal components, including the cover to the avalanche photodiode (APD) module, are removed and the instrument should only be disassembled by trained personnel.

Mains connectors are shrouded to prevent touching of the contacts. The mains supply should be isolated when connecting and disconnecting the cables to the sensor.

Where an isolator switch is fitted, this shall be a two-pole isolator, located as near to the sensor as possible.

The SkyVUE™8 must be properly grounded by a licensed and qualified electrician to protect against voltage leakage shock risk. See [Section 4.2](#) Grounding.

It is recommended that RCD protection units be employed with all sensors. See [4.5.2.1](#) Power Connections, for further information.

Mains powered heaters are enclosed to prevent contact. It should be noted that when powered the heaters may operate automatically and without warning and that they may remain hot even when not powered. Follow the isolation precautions, outlined above, to avoid shock and burn hazards.

The sealed battery is fitted with cables and protected connectors, to prevent shorts. Avoid shorting of the battery to protect it from damage and to avoid burns to personnel through contact with hot surfaces.

2. Product Overview

2.1 Introduction

2.1.1 Overview

The SkyVUE™8 is a LIDAR (Light Detection And Ranging). It emits short pulses of near infra-red light into the atmosphere from a semiconductor laser. These are scattered back by aerosols including cloud droplets. The time between transmission of the pulse and the return signal gives the range, and therefore height, of the scattering aerosols. The variation in the strength of the back-scattered light signal with height gives a profile of scatter coefficients and allows cloud bases to be identified. If significant scattering is detected but there is no defined cloud base then a vertical visibility can be calculated.

The control system of the SkyVUE™8 is divided into three modules, DSP, TOP and PSU as follows:

DSP is the main data processing and communications unit of the SkyVUE™8.

The DSP hosts two separate time keeping circuits. These are cross checked and an alarm produced if they disagree.

TOP provides a number of safety shutdown features such as over and under laser output level. It also contains the calibration circuitry and dirty windows system.

PSU controls the power supply, including battery charging and deep discharge protection.

The SkyVUE™8 has a rugged environmental enclosure that protects the instrument from the harshest conditions and will measure the atmosphere with high stability and repeatability.

2.1.2 Cloud height detection

A scatter profile is measured as described in [Appendix B](#).

Cloud height detection is carried out as described in [Appendix C](#). Up to four cloud heights can be detected.

If no clouds are detected the SkyVUE™8 will give one of the following reports:

- No significant backscatter.
- Full obscuration determined but no cloud base detected. This is reported if the criteria for detecting cloud base is not met but the integrated scattering coefficient reaches the limit of vertical visibility below a set height limit. The default value is 2000 m (6560 ft) but can be changed by the user. The height at which this occurs is given as vertical visibility.
- Some obscuration detected but determined to be transparent is reported if scattering is detected but no cloud is detected and the calculated vertical visibility exceeds a set height limit.

If no cloud is detected but significant scattering is detected below 50 m (160 ft) then vertical visibility is set to 0.

2.1.3 Sky Condition

Sky condition is an assessment of cloud cover measured in units of eighths or “oktas”. The number of oktas is the density of cloud in eighths of that layer. The SkyVUE™8 can report up to 5 layers of cloud when reporting Sky Condition. The algorithm used in the SkyVUE™8 follows guidance in ICAO 9837, Manual on Automatic Meteorological Observing Systems at Aerodromes.

Note that sky condition assessment is based on cloud data for the previous 30 minutes, with cloud detection in the previous 10 minutes given an extra weighting and is not an instantaneous measurement. Therefore, it will not be available before sufficient data has been collected. See [Appendix D](#) for more detail.

2.1.4 Backscatter profile reporting

Several possible data messages give the two-way attenuated backscatter profile. This consists of 2048 groups of five-character hexadecimal values (10,240 characters in total). Each character is 4 bits long and therefore each 5 figure group is 20 bits. They are given as signed two’s complement integers and numbers greater than $2^{19}-1$ represent negative integers.

NOTE After 1600 the remaining groups are all 00000.

Therefore, each group actually represents negative, a value between -2^{19} to $+(2^{19}-1)$, rather than 0 to $(2^{20}-1)$, which would be the case for unsigned, positive, 20-bit integers.

In order to translate this to the correct decimal value, a two stage process should be applied. This is as follows:

- (1) Convert from a hexadecimal to a decimal number.
- (2) If the resulting decimal number lies in the range 0 to 524287 ($2^{19}-1$) then nothing further needs to be done. If the number resulting from this conversion is greater than 524287 then subtract 1048576 (2^{20}).

In order to use this backscatter coefficient in units of $\text{sr}^{-1} \text{m}^{-1}$ this calculated decimal number has to be multiplied by a factor of 10^{-8} . The values are scaled by the *Attenuated_SCALE* parameter, see [Table 5.1](#).

NOTE The profile is not corrected for tilt angle even if cloud heights are corrected.

2.2 Optical Measurement

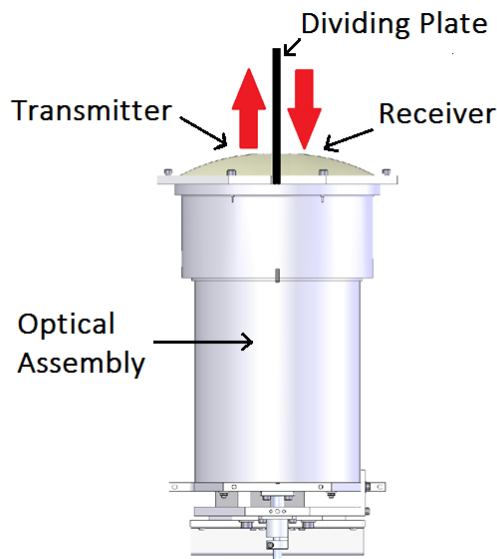


Fig 2.1 Principle of operation

2.2.1 Optical Arrangement

The SkyVUE™8 employs a novel single biaxial lens design to increase optical signal to noise ratio while maintaining Class 1M eye safety by integrating larger optics into a compact package (see [Fig 2.1](#)). One half of the lens is used by the transmitter, the other by the receiver. They are therefore very close. This design provides an alternative to traditional two lens or common-optics designs. The optical isolation of traditional biaxial systems is maintained to increase detector sensitivity, while the low overlap onset height of common-optics systems is incorporated to allow measurements at close ranges.

2.3 Internal Monitoring

The SkyVUE™8 monitors a large number of parameters relevant to its performance. These include window contamination, key voltages and currents and internal temperature and relative humidity. Data messages, see [Section 5](#), include this information allowing remote diagnosis of the SkyVUE™8 condition. In addition, a special status message can be polled.

2.4 Specifications

2.4.1 Measurement Specifications

Maximum Reporting Range: 8 km / 26,250 ft

Minimum Reporting Resolution: 5 m / 15 ft

Hard Target Range Accuracy: +/- 0.25% +/- 4.6 m (15 ft)

Reporting Cycle: 2 to 600s

Cloud Layers Reported: Up to four layers reported, instantaneously. Up to five layers reported in Sky Condition.

2.4.2 Mechanical Specifications

Height: 737 mm (29 in)

Width: 294 mm (11.6 in)

Depth: 240 mm (9.5 in)

Total weight: 18 kg (40 lbs) (excluding cables)

Shipping weight: 24.6 kg (54 lbs)

Base plate: 316 x 316 mm (12.4 in x 12.4 in)

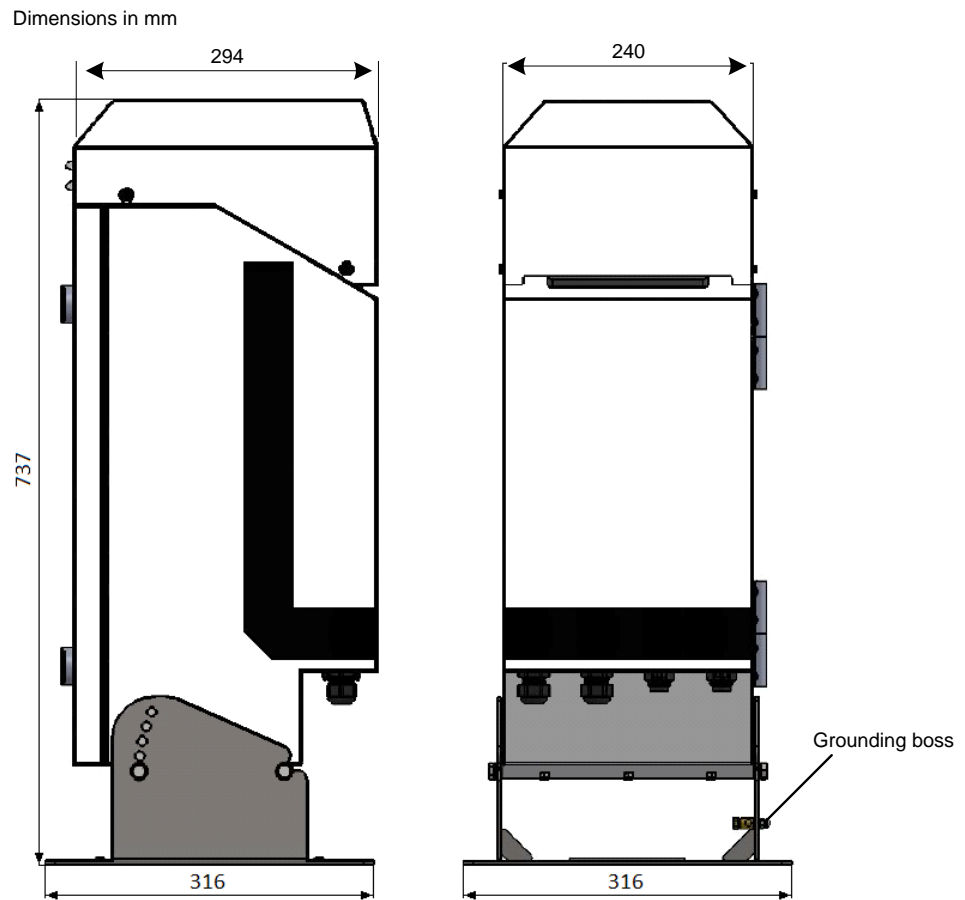


Fig 2.2 SkyVUE™8 Dimensions

2.4.3 Electrical Specifications

Power required: AC nominal 115 (106-137) or nominal 230 (216-253) VAC (automatic selection), 47-63 Hz, 380 W maximum in total.

DSP: 10-40 VDC input. 1A at 12 VDC, 0.5A at 24 VDC

12V OUT: 12 VDC/1.7A for optional or external equipment (if the SkyVUE™8 is using a DC supply this must be greater than 14 VDC for this to be available.)

Heater: Input not used with AC heaters.

The hood heater requires a maximum of 220 W (not available in DC operation).

The internal heater requires a maximum of 110 W (not available in DC operation).

Fuses:

DSP fuse HBC 5A (T)

PSU fuse HBC 5A (T)

All fuses are 5 x 20 mm slow blow (T) and are the same for both 115 VAC and 230 VAC.

Battery: Internal 12V 7Ah sealed lead-acid battery. The power supply is equipped with a system to prevent deep discharge of the battery.

The heaters within the SkyVUE™8 are purely resistive which will prove advantageous when connected to generators or when the power factor of your supply is important.

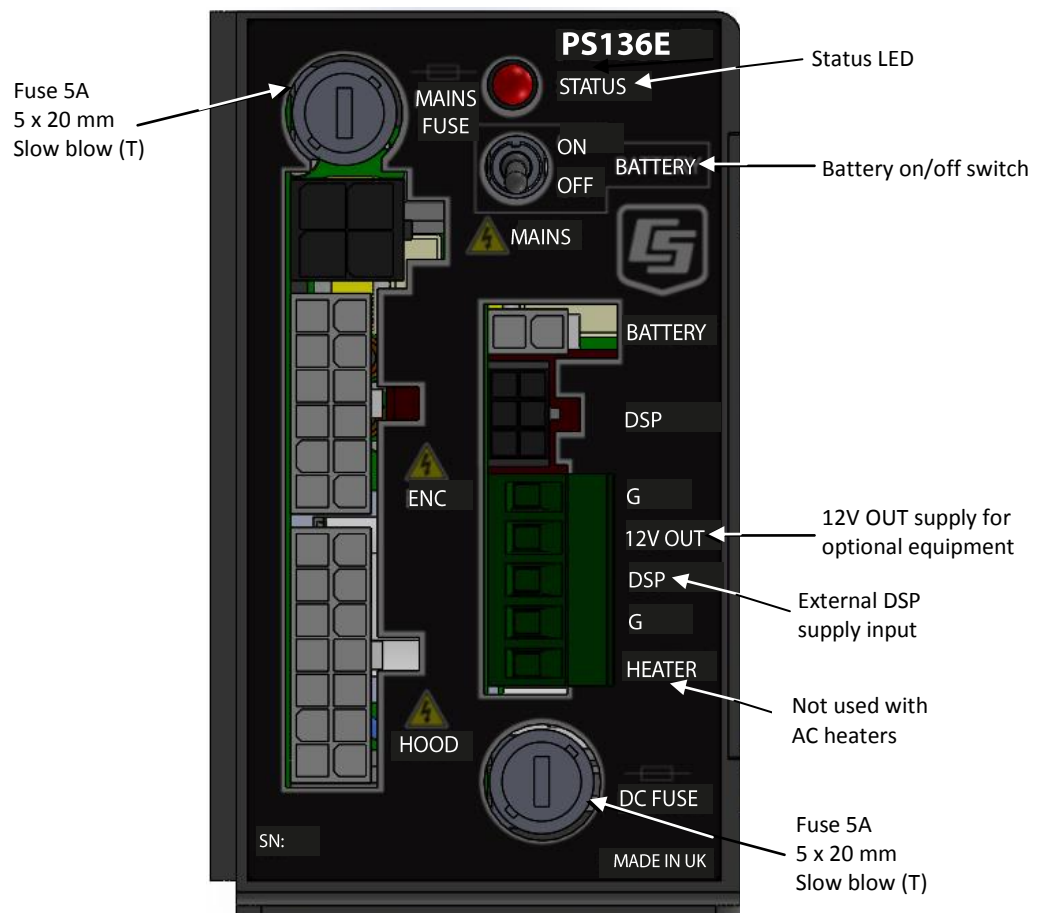


Fig 2.3 PSU

2.4.4 Optical Specifications

Pulse duration: 100 ns
Pulse frequency 10 kHz
Wavelength: 912 ± 5 nm
Half-angle laser divergence: 0.44 mrad
Field of view: 2.0 mrad
Laser lifetime: 10 years typical
Eye safety class: 1M

2.4.5 Environmental Specifications

Standard Operating Temperature Range: -40 °C to +60 °C (Excluding battery)
Battery Temperature Range: -20 °C to +50 °C. (Alternative battery types available)
Relative Humidity Range: 0 to 100%
IP Rating: IP 66
Maximum wind speed: 55 m/s

2.4.6 Communications Specifications

Supported serial settings

8 bits, no parity, 1 stop bit (default)
7 bits, even parity, 1 stop bit
7 bits, odd parity, 1 stop bit

Supported data rates

300 bps
600 baud
1200 baud
2400 baud
4800 baud
9600 baud
19200 baud
38400 baud
57600 baud
76800 baud
115200 baud (default)

Supported standards

RS-232 (default)
RS-485 full duplex
RS-485 half duplex

Signal voltage levels

	Minimum Value	Nominal Value	Maximum Value
RS-232 Communications			
RS-232 input threshold low	0.8V	1.5V	-
RS-232 input threshold high	-	2.0V	2.4V
RS-232 input absolute maximum	-15V	-	+15V
RS-232 input resistance	12K Ω	-	-
RS-232 output voltage low	-	-	0.4V
RS-232 output voltage high (into 3K Ω)	4.4V	-	-

RS-485/422 Communications			
RS-485/422 input threshold voltage	-0.2V	-	+0.2V
RS-485/422 output (Unloaded)	-	-	5V
RS-485/422 output (Load 50 Ω)	2V	-	-
Maximum voltage at any terminal	-7V	-	+7V

USB Service Port USB1.1 and 2.0 compatible, fixed 115200 baud.

3. Initial preparation and checks

The following steps will provide basic familiarisation with the SkyVUE™8 and perform basic functionality checks. To do these you must first open the door and then connect the battery (see [Section 4.6](#)).

WARNING

The laser will be operating as soon as the battery is connected. It should not point in any direction where it could be viewed with magnifying optics.

The green LED visible from above should now be flashing once every 10 seconds (see [Fig 5.2](#)).

Connect a computer using a terminal emulation program to the USB port (see [Fig 4.5](#)). The terminal emulator should be set to 115200 baud, 8N1 bits/parity.

Computer operating systems should identify the USB connection and allocate a port number. The terminal emulator program you are using should then be set to this port number. Older computer operating systems may need upgrading or additional software.

The SkyVUE™8 will be outputting message type 001 every 10 seconds (see [Section 6.3](#)).

Open terminal mode with the command “open 0”. You should now see the prompt “CS136>”, Type “Status”. You will now see the sensor status information described in [Section 5.1.6](#). If you plan to use date/time information this should be checked as it can drift up to ± 14 seconds per day.

If the unit has been in storage or transit for more than a few months, the clock battery may be discharged. However, it will charge from the back-up battery or mains power.

Close terminal mode with the command “close” (it will close automatically after 10 minutes of inactivity).

If you are not installing the unit and connecting mains power upon receipt, you should disconnect the battery to avoid it being discharged.

4. Installation

4.1 Location and Orientation

The SkyVUE™8 measures environmental variables and is designed to be located in harsh weather conditions. However, there are a few considerations to take into account if accurate and representative data from a site are to be obtained.

In order to reduce the service frequency with the unit, the SkyVUE™8 should be placed away from sources of contamination. More regular maintenance will be required when the instrument is placed in areas where contamination is unavoidable or where measurements may be safety related.

Take care that the orientation allows tilting in whatever direction is desired.

WARNING

If installing at an airport check and follow local guidance for allowed locations for a non-frangible object 1 m (3.2 ft) tall. Please contact Campbell Scientific if frangible fittings are required.

4.2 Grounding

The SkyVUE™8 must be properly grounded by taking a ground wire with a minimum cross sectional area of 16 mm² (0.62 in) and maximum length of 10 m (32.8 ft) from the brass grounding boss to an adequate grounding point. The grounding boss is located on the tilt base (see [Fig 2.2](#)).

4.3 Mounting the SkyVUE™8

The SkyVUE™8 should be mounted by bolting to a firm, level foundation. When bolting down take care that the orientation allows tilting in whatever direction is desired.

[Fig 4.1](#) shows the mounting footprint.

If a suitable surface does not already exist then a concrete foundation should be constructed at least 600 mm (23.6 in) square and 600 mm (23.6 in) deep.

Drill four 12 mm (0.47 in) diameter holes using the mount base as a template (see [Fig 4.1](#)) to a depth of 77 mm (3.03 in).

Clean the holes of all debris.

Place washers and nuts on the ends of the wedge anchors supplied (to protect the threads during installation).

Hammer the wedge anchors into the holes until the start of the threads are below the surface.

Tighten the nuts until about 25 mm (0.98 in) of thread protrudes above the surface.

Remove the washers and nuts from the protruding length screw. Then lower the SkyVUE™8 into place.

Finally, secure the SkyVUE™8 with the washers and nuts.

If the surface is not level and flat it may be necessary to add washers under the base on one or more of the foundation screws.

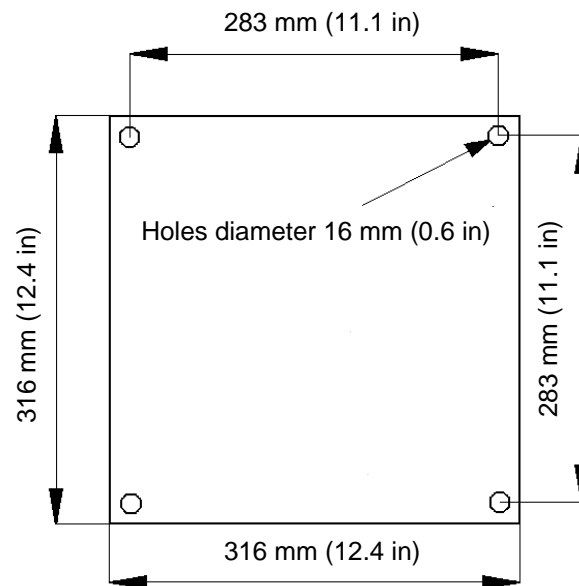


Fig 4.1 Mounting base footprint

4.4 Tilt Angle

The SkyVUE™8 is designed to be tilted 6°, 12°, 18° or 24° from vertical. There are several reasons why this might be done. In tropical regions it might be advantageous to tilt the sensor north in the northern hemisphere and south in the southern hemisphere to prevent the sun shining directly into it, it can reduce problems caused by direct specular reflections from ice crystals and reduce problems from rain or snow falling onto the window. To adjust the tilt angle remove the bolts shown in [Fig 4.2](#), move the SkyVUE™8 to the required tilt angle and replace them.

The SkyVUE™8 has tilt sensors in both axes so that if it is not possible to provide a level base, cloud height can be compensated. Cloud height compensation can be set or disabled using the UNITS command (see [Section 5.1.3](#)). This feature can be useful for mobile or marine applications. Note that profile data is NOT compensated but tilt angles are included in data messages.

Note that increasing the tilt angle beyond 24° can cause significant errors in vertical visibility measurements if scatter coefficients vary significantly with height.



Fig 4.2 Setting the Tilt Angle

4.5 Connectors and wiring

4.5.1 Base connectors

The SkyVUE™8 has two connectors on its base. One is for communications (6 pins), the other (4 pins) provides power to the unit itself.

NOTE Tilting the unit will provide better access to these connectors.

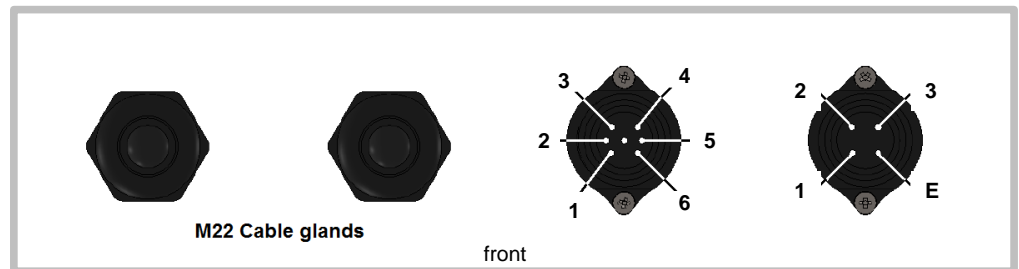


Fig 4.3 Connector Layout

The function of the connector pins is shown in [Table 4.1](#).

Table 4.1 Function of the connector pins

Mains Connector

Pin	Function	Colour of supplied cable cores
1	Live	Brown
2	Not connected	NA
3	Neutral	Blue
4	Earth	Green/yellow

Blower/Heater Connector

Pin	Function	Colour of supplied cable cores
1	Neutral	Black (1)
2	Fan + 12V	Black (2)
3	Therm	Black (3)
4	Therm (0V)	Black (4)
5	Switched 230/115 AC Live	Black (5)
6	Switch 230 VAC	Black (6)
E	Earth (0V)	Green/yellow

Communications Connector

Pin on connector on SkyVUE™8	Colour of supplied cable cores	9-Pin “D” Connector (Fig 4.4)	RS-232	RS-485 Half duplex	RS-485 Full duplex/ RS-422
1	Red	8		B/D+	Y/TXD non-inverting
2	Yellow	7			B/RXD non-inverting
3	Green	5	Gnd		
4	Black			Gnd	Gnd
5	White	2	RXD	A/D-	Z/TXD inverting
6	Blue	3	TXD		A/RXD inverting
E	Screen				

4.5.2 Wiring Using Supplied Campbell Scientific Cables

Two cables are supplied, each 10 m (32.8 ft) long. One is for the mains power supply, the other is for communications.

WARNING

If the power cable is incorrectly wired then irrevocable damage can be done to the unit and there is risk of serious injury or death.

WARNING **The power cable must not be carrying mains voltage when it is being connected or disconnected.**

4.5.2.1 Power Connections

The following guidance is given to help the wiring and installation of a permanent power supply to the sensor.

As the sensor is used outside, the installation of the power cables will normally have to be carried out by a qualified electrician. Please check local safety regulations.

A mains power source needs to be identified and the type of termination, cable type and cable run matched to comply with local regulations and the type of installation.

This needs to be able to provide the correct voltage and frequency and current in excess of the power requirement of the system. See below.

Voltage requirements: 106-137V or 216-253 VAC (auto select)

Power requirements: 380 W

Input frequency: 47-63 Hz.

The power source needs to be fused. The fuse rating should be 5A or larger and a “slow blow” design. Any extensions to the cable supplied or alternative replacement should be capable of carrying current in excess of that fuse rating.

The power source should be fitted with a two-pole isolator and should be fitted as near to the sensor as is possible.

The power cable needs to have three conductors, live, neutral and a protective earth, normally with IEC wiring colours to match those used.

This equipment requires a protective earth. **THIS MUST BE CONNECTED FOR SAFETY REASONS.** Ensure the earth connection at the power source is suitable for this purpose. The connection should be made via the earth wire of the power connector/cable or via the earth stud on the sensor base.

This equipment also requires correct connection of the live and neutral conductors – make sure these are identified and wired correctly at the power source.

Normally, the power source should be fitted with its own or system wide earth leakage breaker (also known as an RCD).

For short term testing of the sensor a suitable plug can be fitted to the end of the power cable and the sensor plugged into a standard mains supply capable of providing 5A at the rated voltage. If this is done the earth wire of the sensor must be connected to a suitable protective earth point.

For DC operation the SkyVUE™8 requires a 10-40 VDC supply capable of 1A at 12 VDC or 0.5A at 24 VDC.

4.5.2.2 Communications connections

The communications cable is terminated at one end with a removable 9 pin D-connector (DB9). The D-connector can be connected directly to a computer or data logger such as the Campbell Scientific CR1000X using a suitable interconnecting cable such as the SC110. Connections and wire colours are shown in [Fig 4.4](#). The connector can easily be removed for direct connection to screws terminals.

For details of an example of CRC basic program for connecting the SkyVUE™8 to a datalogger see [Appendix A](#).

CAUTION

The type of cable supplied is not recommended for lengths greater than 10 m (32.8 ft). In particular, longer length RS-485 cables should incorporate twisted pairs. Please contact Campbell Scientific if you wish to use a longer length of cable.

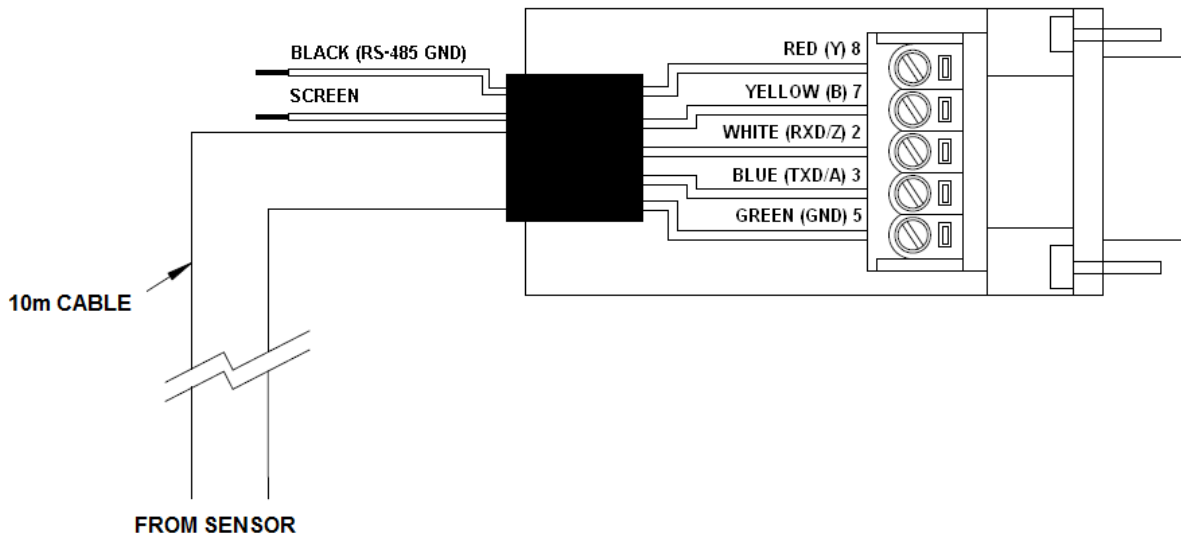


Fig 4.4 Cable Connections

Tilting the unit, see [Fig 4.2](#), will make wiring easier.

4.5.3 USB Connection

A USB port is provided inside the enclosure to aid on-site maintenance. This allows communication of commands to the SkyVUE™8 and responses in the same form as the main serial port except that the baud rate is fixed at 115200 (see [Fig 4.5](#)).

4.5.4 I/O Connection

An I/O port is present but is only used for factory setting of the instrument.

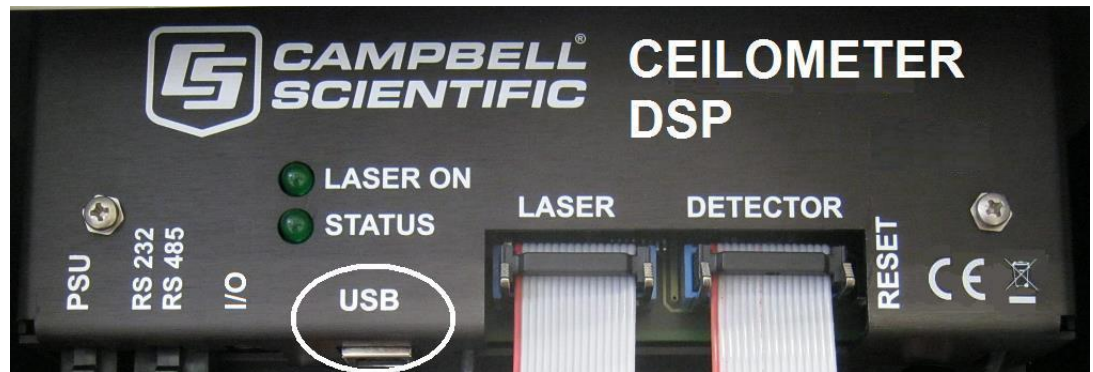


Fig 4.5 USB port

4.6 Connecting the Back-up Battery

The SkyVUE™8 will be shipped with the back-up battery disconnected. It should be connected as shown in [Fig 4.6](#) before bringing the unit into use.

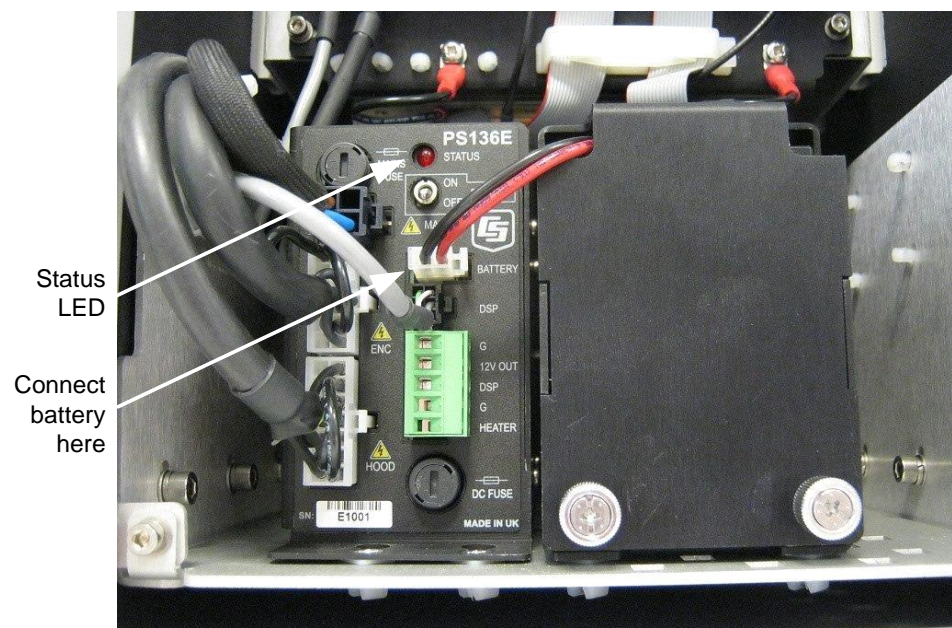


Fig 4.6 Connecting Battery

To do this the door must first be opened. The desiccant included for transport should be removed at the same time.

4.7 Bird Spike Kit

A bird spike kit is available to deter birds from sitting on the SkyVUE™8. This comprises 4 stainless “spikes” with rounded ends and a small reel of stainless wire. [Fig 4.7](#) shows installed bird spikes.



Fig 4.7 Ceilometer Bird Spike Kit installed

To install the bird spikes first remove the cowl and blanking plugs from the cowl as shown in [Fig 4.8](#). If the SkyVUE™8 is an older unit without pre-existing holes then it will be necessary to drill 4 holes each 4.5 mm (0.17 in) diameter, evenly spaced around the aperture and 10 mm (0.39 in) in from the edge. Each spike is then inserted into the holes, thread first, and nuts and washers attached and tightened, see [Fig 4.9](#). Then replace the cowl on the SkyVUE™8.

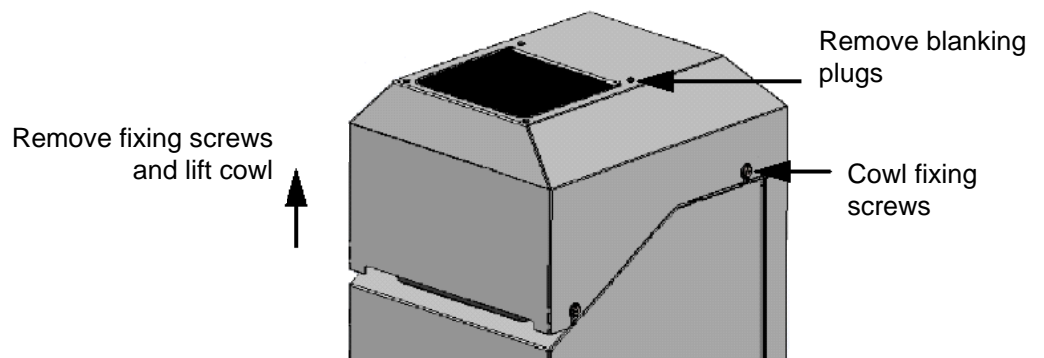


Fig 4.8 Preparing the SkyVUE™8 for Installing the Bird Spikes

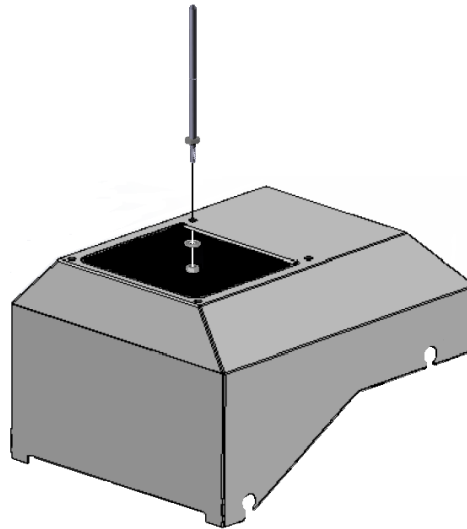


Fig 4.9 Attaching Bird Spikes to the SkyVUE™8 cowl

Finally wrap stainless steel wire around the spikes using the grooves in the spikes. The wire is easily wrapped around each spike in turn and then back on itself. Do not tighten the wire too much as it may pull the spikes inwards and obscure the field of view of the SkyVUE™8 optics.

Only use one strand of wire to reduce the possibility of water drops being collected.

Check the wire during maintenance and replace if necessary.

4.8 Storage Information

The SkyVUE™8 should be stored between -40 °C to +70 °C in a dry place, preferably with the enclosures securely fastened. The optics should be protected from possible accidental damage. For storage the back-up battery should be disconnected.

NOTE Leaving the battery connected during storage will mean that the unit will still be powered until the battery voltage falls below a shut-down threshold.

NOTE If the SkyVUE™8 has been stored below 0.0 °C the start-up time will progressively take longer - up to 10 minutes. Full accuracy will not be achieved for an hour at -20 °C.

NOTE The battery has a temperature range of -20 °C to +50 °C and should be removed if the SkyVUE™8 is to be stored outside this range.

5. Operation

5.1 Terminal mode

5.1.1 Entering/Exiting the SkyVUE™8 Terminal Mode

The menu system is entered with the command `OPEN Sensor_ID Password` (The menu will time out and close automatically if not used for 10 minutes).

Sensor_ID is the SkyVUE™8 identification, a single ASCII character 0-9,a-f,A-F case sensitive. The default is 0. If a password is set then it must be entered here otherwise it can be omitted. The following text should now be displayed: "CS136>". The SkyVUE™8 is now ready for terminal mode commands.

The SkyVUE™8 Commands are not case sensitive. The Parameters and/or password following the command are case sensitive.

Example of the "open" command followed by the parameter "0":

```
OPEN 0
```

Example of the open command with the password "Secret":

```
OPEN 0 Secret
```

5.1.2 Terminal Mode Commands General

[Table 5.1](#) gives a summary of the terminal mode commands available.

The SkyVUE™8 can be setup and controlled by using the terminal interface where discrete commands are sent. The terminal commands can be sent via a data logger to the SkyVUE™8 removing the need for a local computer to set up the unit.

The terminal emulators built into many Campbell Scientific software products can also be used. Note however that DevConfig and Present Weather (PW) Viewer cannot be used to load a new operating system as this requires XMODEM protocol. One common, freely available terminal emulator with this feature is called "Tera Term" which is readily available on the internet.

The following settings are used:

<u>RS-232/422/485 interface (default)</u>	<u>USB service port</u>
RS-232	Baud: rate 115200
Baud rate: 115200	Data bits: 8
Data bits: 8	Parity: none
Parity: none	Stop bits: 1
Stop bits: 1	Flow control: none
Flow control: none	

Ensure that if the baud rate of the unit has been adjusted and then the corresponding bits per second value are entered in the port settings of the terminal emulator. The SkyVUE™8 should now be ready to accept commands.

Note: Commands will always output all parameters on a new line after a *CR LF* (carriage return and line feed) and then the SkyVUE™8 prompt “CS136>”. If you only want to see parameter values without changing them then enter the command without parameters. If a particular parameter did not need changing then the parameter can be replaced with a comma (.). Back space will abort the command.

5.1.3 Terminal mode command examples

How to enter a command

Example 1

The following text shows an example of setting up the SkyVUE™8 serial port. This example would set the serial port to RS-232 hand shaking at 115200 bps, 8 data bits, no parity and if it was in RS-485 mode then a 100 mS turn around delay.

```
serial 0 10 0 100
```

You could also type the following to obtain the same results as the RS-485 turn around delay is not needed:

```
serial 0 10 0
```

If all you wish to do is change the data baud rate and nothing else you can replace the first number, the mode parameter, with a “,” as shown below.

```
serial , 10
```

Alternatively if you just wished to change the parity to 8-bits no parity then type the following:

```
serial , , 0
```

You do not need to replace the remaining parameters with “,” you only need to replace the ones up to the parameter you wish to edit.

NOTE

Remember to leave a space character between the command and the parameters as shown in the examples.

Example 2

Entering the MCFG command, as shown below, will set the sensor to send messages at 10 second intervals and to send one message only with the message number 112.

```
MCFG 10 112 0 0 0 0 (return)
```

The 4 zeros indicate that no other message outputs have been set. The MCFG command is described on page 26.

Table 5.1 Summary of the terminal mode commands available

Command	Parameter/ Parameter block	Description
ALARMS	<i>Angle</i>	<i>Angle</i> is the threshold tilt angle of the sensor beyond which an alarm will be flagged. The settable range is 0 to 90.0 degrees tilt and the default is 45.0 degrees.
BS (see Section 5.1.5 for more information on compatibility of different parameters)	<i>Attenuated_SCALE,</i> <i>BS_Av_Time,</i> <i>Noise_Gate,</i> <i>Measurement_Period,</i> <i>Rolling_Average,</i> <i>Message_Interval</i>	<p>Rules for BS command are: <i>BS_Av_Time</i> <= <i>Measurement_Period</i>-1s. <i>Message_Interval</i> must be a multiple of <i>Measurement_Period</i></p> <p><i>Attenuated_SCALE</i> is the scalar for the attenuated backscatter %. 0.001 to 1000 (default 100%)</p> <p><i>BS_Av_Time</i> is the backscatter average time in seconds. 1 to 30 (default 7). Note: Must not be greater than <i>Measurement_Period</i>-1.0</p> <p><i>Noise_Gate</i> controls the noise threshold applied to back-scatter. <i>Noise_Gate</i> = -1000, all backscatter range is corrected. <i>Noise_Gate</i> = 0.0-1000.0, standard deviation for noise threshold, default 2.0. Only backscatter above this is range corrected.</p> <p><i>Measurement_Period</i> 0 or 2 to 600 (default 10). If set to 0 and the SkyVUE™8 is polled it will output the last measurement made. If it is between 2 and 600 seconds then the SkyVUE™8 will continually output messages. For sky condition output it is recommended that the <i>measurement_Period</i> is set no longer than 30 seconds. If a <i>measurement_Period</i> greater than 30 seconds is used then the sky condition algorithm will be less able to resolve coverage for higher layers. Note: Must be a sub multiple of <i>Message_Interval</i></p> <p><i>Rolling_Average</i> = 1 to 29 default 3. This is the number of measurement_periods to use in a rolling average of the backscatter.</p> <p><i>Message_Interval</i> is the message interval in seconds, 2 - 600 seconds “0” gives polled messages, default 10 Note: Must be a multiple of <i>Measurement_Period</i></p>
CLOSE	<i>No parameters</i>	Closes the terminal interface to allow normal message output and saves new settings to flash non-volatile storage.
DEFAULTS	<i>No parameters</i>	Loads factory defaults
GETUSER		<p>Reads all user settings as a string of text. Parameters are read in the following order:</p> <p><i>user</i> = text “user” <i>volVer</i> = user volume version <i>OS_VER</i> = DSP OS version <i>PsuOsVer</i> = PSU OS version <i>TopOsVer</i> = TOP OS version <i>Id</i> = SkyVUE™8 ID <i>Pw</i> = SkyVUE™8 password <i>terminalCrc</i> = terminal crc mode <i>terminalTimeout</i> = terminal timeout <i>unitsTiltMode</i> = units and tilt mode <i>hoodHBMode</i> = hood heater / fan heater mode <i>hoodHBTestInt</i> = hood heater / blower test interval in hours <i>battBoost_mV</i> = boost voltage used for battery charging mV <i>battCharge_mA</i> = battery charge current mA <i>psuPresent</i> = PSU present switch</p>

		<p> <i>hoodHBNormSpeed</i> = Fan voltage for normal speed mV <i>hoodHBHighSpeed</i> = Fan voltage for high speed mV <i>hoodHBLowSpeed</i> = Fan voltage for low speed mV <i>intHMode</i> = internal heater mode <i>message[0]</i> = fields for message 0 <i>message[1]</i> = fields for message 1 <i>message[2]</i> = fields for message 2 <i>message[3]</i> = fields for message 3 <i>message[4]</i> = fields for message 4 <i>messagePeriod</i> = output message period in seconds <i>heightOffset</i> = height offset metres <i>bsAvTime</i> = backscatter average time in seconds <i>laserMode</i> = laser operation mode <i>laserPower</i> = laser power <i>laserHeater</i> = laser heater mode <i>attenuatedSCALE</i> = attenuated backscatter scaling factor <i>logInterval</i> = debug logging interval <i>measurementPeriod</i> = measurement interval in seconds <i>serMode</i> = serial port mode <i>baudSel</i> = serial port baud rate mode <i>dataParityStop</i> = serial port parity mode <i>rx2txTimeout</i> = serial port RX to TX turnaround time <i>snrMarginBoundary</i> = onset of backscatter detection threshold <i>snrMarginDetector</i> = cloud detection threshold <i>alphaGuessEnd</i> = cloud alpha guess at boundary <i>alphaMin</i> = cloud detection alpha minimum <i>Vcld_D</i> = cloud detection <i>delta_Vcld_D</i> = cloud detection <i>vis_Av_T</i> = cloud detection <i>alphaGuess</i> = visibility initial alpha guess <i>ratioLevel</i> = visibility ratio <i>alphaMin</i> = visibility alpha minimum <i>cap</i> = visibility cap in metres <i>tiltLimit</i> = tilt limit in degrees used by alarms <i>noiseGate</i> = attenuated backscatter noise gate mode <i>vvLimit_percent</i> = sky condition report vertical visibility % <i>alphaGuessStart</i> = cloud detection alpha guess at lowest height bin <i>reserved</i> <i>reserved</i> <i>reserved</i> <i>reserved</i> <i>reserved</i> <i>reserved</i> <i>reserved</i> <i>reserved</i> <i>CRC</i> = 4 digit ASCII hex CRC calculated from the “u” of user up to but not including the CRC using the standard CRC-16. </p> <p>Note: Many of these parameters may not have been adjusted. This command allows a reliable technique for copying full settings from one SkyVUE™8 to another with the “SETUSER” command.</p> <p>A typical response to the GETUSER command is:</p> <pre> >>>>>>>>> COPY FROM START OF NEXT LINE >>>>>>>>> user 7 007638-6da 106 510 0 , 0 10 2 0 1 14520 400 1 1000 1000 2000 0 1 0 0 0 0 10 0.000E+00 2.000E+00 1 1.000E+00 0 1.000E+00 0 10 1 0 10 0 100 4.000E+00 6.000E+00 2.000E-03 2.500E-04 1.000E+03 2.200E+01 4.800E+03 1.000E-01 9.000E-01 2.500E-04 2.000E+03 4.500E+01 2.000E+00 50 2.00E-03 3.000E+01 1.500E+02 1.800E+00 </pre>
--	--	---

POWEROFF	<i>No parameters</i>	This will prepare the PSU to power down the SkyVUE™8 even if the battery is connected. As soon as the mains supply is disconnected the SkyVUE™8 will power off and NOT run on battery back-up. The SkyVUE™8 can be re-activated with battery back-up enabled by re-connecting the mains supply. You will be asked to confirm.
REBOOT	<i>No parameters</i>	Forces a system reboot. This will restore previously saved user settings. Any unsaved changes will be lost. (Settings are saved in terminal mode when the command CLOSE is typed, which exits the terminal mode).
SCCAL	<i>No parameters but user interaction required</i>	Stratocumulus backscatter calibration. This requires a human observer to confirm a stable Stratocumulus cloud layer between 250 m to 2500 m without holes, precipitation or reduced visibility and has been stable for at least 10 minutes prior to running this command. See Section 5.1.9 for more information.
SERIAL	<i>Mode, Baud, Bits_Parity, Delay</i>	Set or read the serial port <i>Mode</i> = 0, RS-232, full duplex (default) <i>Mode</i> = 1, RS-232, half duplex <i>Mode</i> = 2, RS-485, full duplex <i>Mode</i> = 3, RS-485, half duplex <i>Mode</i> = 4, Reserved <i>Mode</i> = 5, RS-422, full duplex <i>Baud</i> = 0, 300 baud <i>Baud</i> = 1, 600 baud <i>Baud</i> = 2, 1200 baud <i>Baud</i> = 3, 2400 baud <i>Baud</i> = 4, 4800 baud <i>Baud</i> = 5, 9600 baud <i>Baud</i> = 6, 19200 baud <i>Baud</i> = 7, 38400 baud <i>Baud</i> = 8, 57600 baud <i>Baud</i> = 9, 76800 baud <i>Baud</i> = 10, 115200 baud (default) <i>Bits_Parity</i> = 0, 8 bits, no parity, 1 stop bit (default) <i>Bits_Parity</i> = 1, 7 bits, even parity, 1 stop bit <i>Bits_Parity</i> = 2, 7 bits, odd parity, 1 stop bit <i>Delay</i> is the delay time in mS to TX (RS-485 half-duplex mode only). Range 0-100 mS, default 100 mS
SERVICE	<i>No parameters but user intervention required</i>	Performs a service procedure
SETUSER	<i>String</i>	Load all user settings as a string of text. (not changed) = parameter will not be updated and the previously set value will persist. String = user (not changed) volVer = user volume version (not changed) OS_VER = DSP OS version (not changed) PsuOsVer = PSU OS version (not changed) TopOsVer = TOP OS version (not changed) Id = SkyVUE™8 ID (not changed) Pw = SkyVUE™8 password (not changed) terminalCrc = terminal crc mode terminalTimeout = terminal timeout unitsTiltMode = units and tilt mode hoodHBMode = hood heater / fan heater mode

		<p>hoodHBTestInt = hood heater / blower test interval in hours battBoost_mV = boost voltage used for battery charging mV battCharge_mA = battery charge current mA psuPresent = PSU present switch hoodHBNormSpeed = Fan voltage for normal speed mV hoodHBHighSpeed = Fan voltage for high speed mV hoodHBLowSpeed = Fan voltage for low speed mV intHMode = internal heater mode message[0] = fields for message 0 message[1] = fields for message 1 message[2] = fields for message 2 message[3] = fields for message 3 message[4] = fields for message 4 messagePeriod = output message period in seconds heightOffset = height offset metres bsAvTime = backscatter average time in seconds laserMode = laser operation mode laserPower = laser power laserHeater = laser heater mode attenuatedSCALE = attenuated backscatter scaling factor logInterval = debug logging interval measurementPeriod = measurement interval in seconds serMode = serial port mode baudSel = serial port baud rate mode dataParityStop = serial port parity mode rx2txTimeout = serial port RX to TX turnaround time snrMarginBoundary = onset of back-scatter detection threshold snrMarginDetector = cloud detection threshold alphaGuessEnd = cloud alpha guess at boundary alphaMin = cloud detection alpha minimum Vcld_D = cloud detection delta_Vcld_D = cloud detection vis_Av_T = cloud detection alphaGuess = visibility initial alpha guess ratioLevel = visibility ratio alphaMin = visibility alpha minimum cap = visibility cap in metres tiltLimit = tilt limit in degrees used by alarms noiseGate = attenuated backscatter noise gate mode vvLimit_percent = sky condition report vertical visibility % alphaGuessStart = cloud detection alpha guess at lowest height bin Reserved Reserved Reserved Reserved Reserved Reserved Reserved Reserved CRC = 4 digit ASCII hex CRC calculated from the “u” of user up to but not including the CRC using the standard CRC-16-CCITT. Note: String is added as text and should be added as a “cut and paste” from a stored file.</p>
STATUS	<i>No parameters</i>	<p>Outputs SkyVUE™8, serial number, ID, DSP OS version, Time & Date, DSP version, TOP OS version, PSU OS version, watch dog counts, serial parameters, blower heater mode, internal heater mode, message parameters, tilt angle, units, temperature/humidity, temperatures, supply voltages, height offset, visibility cap, laser run days, window parameters, backscatter parameters, features, alarms, warnings & status. Note: Refer to Section 5.1.6 for more information on this command</p>

TERMINAL	<i>Terminal, Timeout</i>	<p>Sets CRC-16-CCITT checking and the user terminal time out <i>Terminal</i> = 0, CRC-16-CCITT off (default) <i>Terminal</i> = 1, CRC-16-CCITT on (all terminal commands need a CRC See Section 5.1.10 for details).</p> <p><i>Timeout</i> is the delay in minutes from 1 to 15 where the terminal will automatically close if no characters are sent to the SkyVUE™8. The default is 10 minutes.</p>
TIME	<i>Date_Time</i>	<p>Date is in the format yyyy/mm/dd Time is in the format hh:mm:ss yyyy=year, mm=month, dd=day hh=hours, mm=minutes, ss=seconds (i.e. time 2013/05/25 10:00:00, would set the date and time to May 25th 2013 at 10:00:00) Note: The set time could drift by up to ±14 seconds a day.</p>
UNITS	<i>Units</i>	<p>Sets measurement units and tilt correction</p> <p><i>Units</i> = 0, metres corrected by tilt <i>Units</i> = 1, metres not corrected by tilt <i>Units</i> = 2, feet corrected by tilt (default) <i>Units</i> = 3, feet not corrected by tilt</p>
UNLOCK	<i>Key</i>	<p><i>Key</i> = a 12 digit ASCII hex key provided by CSL to unlock pay-for features</p>
VIS	<i>Cap</i>	<p><i>Cap</i> is the vertical visibility maximum range 100 to 10000 in metres or 328 to 32808 in feet (default 2000 m or 6561 ft).</p>

Note (1)

If AUTO is set then the heater / blower will heat to 80 °C if (sky condition > 1 okta coverage) or (cloud height < 3 km (9842 ft) AND sky condition > 1 okta coverage) OR window Tx < 80% OR precipitation detected. When the event has passed, the blower/heater will remain active at 80 °C for a further 15 minutes before going into a fan-off state and the heater temperature drops to an average of approximately 40 °C, ready to be activated again.

5.1.4 MCFG command message types

The MCFG commands “Message_ID_x” parameter defines the following output types. Refer to [Section 6](#) for further information on message output types.

Table 5.2 Summary of message ID and descriptions

Message_ID_x type	Description
000	No message
001 (default)	Campbell Scientific Message 1, no sky condition, no profile data
002	Campbell Scientific Message 2, no sky condition, profile data, 1600 range bins, 5 m resolution
003	Campbell Scientific Message 3, sky condition, no profile data
004	Campbell Scientific Message 4, sky condition and profile data, 1600 range bins, 5 m resolution
101	CL31 Message 1, 770 range bins, 10 m resolution
102	CL31 Message 1, 385 range bins, 20 m resolution
103	CL31 Message 1, 1500 range bins, 5 m resolution
104	CL31 Message 1, 770 range bins, 5 m resolution
105	CL31 Message 1, No profile data
106	CL31 Message 1, Full SkyVUE™8 output, 1600 range bins, 5 m resolution
107	CL31 Message 2, 770 range bins, 10 m resolution
108	CL31 Message 2, 385 range bins, 20 m resolution
109	CL31 Message 2, 1500 range bins, 5 m resolution
110	CL31 Message 2, 770 range bins, 5 m resolution
111	CL31 Message 2, No profile data
112	CL31 Message 2, Full SkyVUE™8 output, 1600 range bins, 5 m resolution
113	CT25K message 1
114	CT25K message 6

5.1.5 Measurement and message intervals

The message interval is the time, in seconds, between the automatic message transmissions. It can be set between 2-600s (“0” gives polled messages). The default is 10, meaning a message will be sent automatically every 10 seconds. The message interval must be a multiple of the measurement period.

The backscatter average time, BS_Av_Time, is the period over which the laser is firing and taking measurements.


The measurement period is the time interval between the start of backscatter average time (BS_Av_Time), during which the laser fires, and the start of the next measurement period. The measurement period must be long enough to include the backscatter average time and some processing time. The minimum measurement period is 2 seconds, which assumes the backscatter average time is 1 second. The measurement period can be set between 2 to 600s (default is 10s). If it is set to 0 then measurements must be polled.

The rolling average (1-29, default 3) is the number of periods used to calculate each scatter value that is either used in a profile message or in a calculation of cloud height.

The message interval chosen may affect measurement parameters allowed within the “BS” command, which can be used to set non-standard measurement parameters) as follows:


If message interval = measurement period = 2 (the lowest values allowed)
 Then the backscatter average time (BS_Av_Time) must equal 1 and the rolling average must equal 1.

If the message interval is between 3 and 9s then the measurement period must be the same as the message interval.

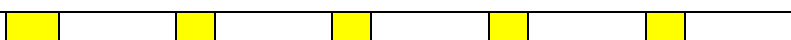
 In the following examples Yellow means laser firing.

To comply with the requirements for Sky Condition the total measurement period for rolling averages should not exceed 30 seconds.

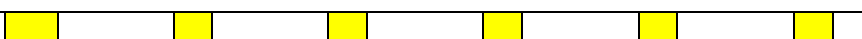
In this case the SkyVUE™8 sends a message every 2 seconds based on one measurement averaged over 1 second. Therefore, each message is based on a single 1 second period of backscatter average data.

Laser firing (yellow)	
(BS_AV_Time) = 1s	1s
Measurement Period = 2s	2s
Message Interval = 2s	2s

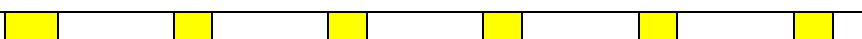
In this case, with the rolling average set to 1, the SkyVUE™8 sends a message every 30 seconds. It takes three, 2 second, measurements at 10 second intervals. Only the last measurement is used in the output message but all three are used for calculating sky condition. Therefore, each message is based on a single 2 second period of backscatter average data.

Laser firing (yellow)			
(BS_AV_Time) = 2s	2s		
Measurement Period = 10s	10s	10s	10s
Message Interval = 30s	30s		

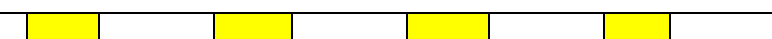
In this case, with the rolling average set to 3 (default), the SkyVUE™8 sends a message every 30 seconds that contains the average of the latest three measurements. Therefore, each message is based on three, 10 second measurement periods, with each containing 2 seconds of backscatter average data.

Laser firing (yellow)			
(BS_AV_Time) = 2s	2s		
Measurement Period = 10s	10s	10s	10s
Message Interval = 30s	30s		

In this case, with the rolling average set to 3 (default), the SkyVUE™8 sends a message every 10 seconds that contains the average of the latest three measurements. Therefore, each message is based on three, 10 second measurement periods, with each containing 2 seconds of backscatter average data.

Laser firing (yellow)			
(BS_AV_Time) = 2s	2s		
Measurement Period = 10s	10s	10s	10s
Message Interval = 10s	10s	10s	10s

In this case, the SkyVUE™8 sends a message every 14 seconds based on one measurement taking 4 seconds over a 14 second interval. Therefore, each message is based on a single 4 second period of average data.

Laser firing (yellow)				
(BS_AV_Time) = 4s	4s			
Measurement Period = 14s	14s	14s	14s	14s
Message Interval = 14s	14s	14s	14s	14s

This message cannot be set up using the MCFG command alone. The BS command has to be used as follows:
BS_Av_Time (averaging period) has to be set to 4, not the default value.

5.1.6 STATUS command

The STATUS command returns the following information:

Line	Example line output
1	Identification CS136 SN1000 ID 0
Description of the line sections	
Section	Description
CS136	Product name
SN1000	Sensor serial number
ID 0	Sensor identification number

Line	Example line output
2	Date Time 2012/01/10 11:39:46
Description of the line sections	
Section	Description
2012/01/10	Date in the format yyyy/mm/dd
11:39:46	Time in the format hh:mm:ss

Line	Example line output
3	DSP_OS A
Description of the line sections	
Section	Description
A	DSP OS revision number

Line	Example line output
4	TOP_OS_HW 8 2
Description of the line sections	
Section	Description
A	TOP board OS revision number and hardware revision

Line	Example line output
5	PSU_OS 1 PS136
Description of the line sections	
Section	Description
A	PSU board OS revision number

Line	Example line output
6	Watchdog A
Description of the line sections	
Section	Description
A	Watchdog counter for unscheduled system resets

Line	Example line output
7	Serial A B C D
Description of the line sections	
Section	Description
A	Serial mode (<i>Note: Refer to the SERIAL command</i>)
B	Serial baud rate (<i>Note: Refer to the SERIAL command</i>)
C	Parity and stop bits (<i>Note: Refer to the SERIAL command</i>)
D	Receive to transmit delay time in RS-485 mode (<i>Note: Refer to the SERIAL command</i>)

Line	Example line output
8	Heaters A B C D
Description of the line sections	
Section	Description
A	Hood blower mode
B	Internal heater mode
C	Laser heater mode
D	Heater/blower test interval in hours

Line	Example line output
9	MCFG X A B C D E
Description of the line sections	
Section	Description
X	Message interval <i>(Note: Refer to the MCFG command)</i>
A	Message ID A <i>(Note: Refer to the MCFG command)</i>
B	Message ID B <i>(Note: Refer to the MCFG command)</i>
C	Message ID C <i>(Note: Refer to the MCFG command)</i>
D	Message ID D <i>(Note: Refer to the MCFG command)</i>
E	Message ID E <i>(Note: Refer to the MCFG command)</i>

Line	Example line output
10	Angle A B C
Description of the line sections	
Section	Description
A	X axis tilt
B	Y axis tilt
C	Beam angle from vertical

Line	Example line output
11	Units A
Description of the line sections	
Section	Description
A	Measurement units and tilt correction. <i>(Note: Refer to the UNITS command)</i>

Line	Example line output
12	TRH A B C
Description of the line sections	
Section	Description
A	Sensor internal temperature reading in degrees Celsius
B	Sensor internal humidity reading as a percentage
C	Sensors internal dew point value in degrees Celsius

Line	Example line output
13	T A B C D E F G
Description of the line sections	
Section	Description
A	External fan blower assembly temperature in degrees Celsius
B	PSU internal temperature in degrees Celsius
C	TOP board laser monitor temperature in degrees Celsius
D	TOP board calibration LED temperature in degrees Celsius
E	Laser module temperature in degrees Celsius
F	Photo diode module temperature in degrees Celsius
G	Internal heater temperature in degrees Celsius

Line	Example line output
14	SupplyVoltage A B C D E
Description of the line sections	
Section	Description
A	DSP board supply voltage
B	PS136E internal supply voltage
C	Cyclic power cycle counter. Resets after 31 cycles
D	Hood heater voltage
E	Internal heater voltage

Line	Example line output
15	HOffset A
Description of the line sections	
Section	Description
A	Height offset reported in feet or metres dependent upon the UNITS command

Line	Example line output
16	Visibility Cap A
Description of the line sections	
Section	Description
A	Vertical visibility maximum range

Line	Example line output
17	LaserRunDays A
Description of the line sections	
Section	Description
A	Number of days that the laser module has been active for

Line	Example line output
18	WindowTX A
Description of the line sections	
Section	Description
A	Window transmittance %

Line	Example line output
19	BS A B C D E F (<i>Note: refer to the BS command</i>)
Description of the line sections	
Section	Description
A	Attenuated scale
B	Averaging time
C	Noise Gate
D	Measurement period
E	Rolling average
F	Message interval

Line	Example line output
21	Features A
Description of the line sections	
Section	Description
A	List of features enabled

Line	Example line output
22	Flags 0000 0000 0000
Description of the most significant alarm word (left side, bits going left to right). Each alarm word is a hexadecimal sum of all the error bits.	
Bit	Description
8000 XXXX XXXX	Units. feet = 0, metres = 8
4000 XXXX XXXX	<i>Reserved for future use</i>

2000 XXXX XXXX	<i>Reserved for future use</i>
1000 XXXX XXXX	<i>Reserved for future use</i>
0800 XXXX XXXX	DSP clock out of specification
0400 XXXX XXXX	Laser shut down due to operating temperature out of range
0200 XXXX XXXX	The lead acid battery voltage is reading low
0100 XXXX XXXX	Mains supply has failed (Required a PSU to be present)
0080 XXXX XXXX	The external heater blower assembly temperature is out of bounds
0040 XXXX XXXX	External heater blower failure
0020 XXXX XXXX	The PSUs internal temperature is high
0010 XXXX XXXX	PSU OS has failed its signature check
0008 XXXX XXXX	No communications between DSP and PSU
0004 XXXX XXXX	Photo diode and Laser windows are dirty. This can only be set if the laser is on
0002 XXXX XXXX	Tilt beyond limit set by user, default 45 degrees
0001 XXXX XXXX	No communications between DSP and inclinometer board

Description of the middle alarm word (middle word, bits going left to right)	
Bit	Description
XXXX 8000 XXXX	The sensors internal humidity is high
XXXX 4000 XXXX	Communications to the DSP boards temperature and humidity chip have failed
XXXX 2000 XXXX	DSP input supply voltage is low
XXXX 1000 XXXX	Self-test active
XXXX 0800 XXXX	Watch dog counter updated
XXXX 0400 XXXX	User setting stored in flash failed their signature checks
XXXX 0200 XXXX	DSP factory calibration stored in flash has failed its signature check
XXXX 0100 XXXX	DSP board OS signature test failed
XXXX 0080 XXXX	DSP board RAM test failed
XXXX 0040 XXXX	DSP boards on board PSUs are out of bounds
XXXX 0020 XXXX	TOP board non-volatile storage is corrupt
XXXX 0010 XXXX	TOP board OS signature test has failed
XXXX 0008 XXXX	TOP boards ADC and DAC are not within specifications
XXXX 0004 XXXX	TOP boards on board PSUs are out of bounds
XXXX 0002 XXXX	Communications have failed between TOP board and the DSP
XXXX 0001 XXXX	Photo diode background radiance is out of range

Description of the least significant alarm word (right side, bits going left to right)	
Bit	Description
XXXX XXXX 8000	Photo diode temperature is out of range
XXXX XXXX 4000	Photo diode is saturated
XXXX XXXX 2000	Photo diode calibrator temperature is out of range
XXXX XXXX 1000	Photo diode calibrator has failed
XXXX XXXX 0800	The sensor could not reach the desired gain levels
XXXX XXXX 0400	Laser run time has been exceeded
XXXX XXXX 0200	Laser temperature out of range
XXXX XXXX 0100	Laser thermistor failure
XXXX XXXX 0080	Laser is obscured. This can only be set if the laser is on
XXXX XXXX 0040	Laser did not achieve significant output power
XXXX XXXX 0020	Laser max power exceeded
XXXX XXXX 0010	Laser max drive current exceeded
XXXX XXXX 0008	Laser power monitor temperature out of range
XXXX XXXX 0004	Laser power monitor test fail
XXXX XXXX 0002	Laser shutdown by top board
XXXX XXXX 0001	Laser is off

5.1.7 Message Polling

The command 'POLL *Sensor_ID* *Message_ID*' requests the message *Message_ID* from sensor *Sensor_ID*.

Where *Message_ID* is a SkyVUE™8 message type as defined in [Section 5.1.4](#).

The following example shows to use the SkyVUE™8 POLL command to request preconfigured message outputs.

First configure the SkyVUE™8 to use polling mode from the terminal interface via the “MCFG” command as follows:

```
“CS136> MCFG 0”  
“0 1 0 0 0 0”
```

This configures the SkyVUE™8 into polling mode leaving your message output configurations unchanged. Exit the terminal by typing the “close” command. This will save the changes you just made.

```
“CS136> CLOSE”  
“COMMAND CLOSED”
```

Any automatic message outputs should not have stopped. Type the “POLL” command as shown below to verify that the system is working as expected.

NOTE

Once you have exited, the terminal characters will not be automatically echoed back to you.

```
“POLL 0”
```

This should return all messages you have set via the MCFG command. In this example, only one message output was set, the default message. So the POLL command will return text similar to that shown below. Note: If you have no message configured (i.e. MCFG returned 0 0 0 0 0 0) then nothing will be returned from the command you just typed.

```
“CS0100001  
10 100 12345 // // // // 000000000000”  
abcd
```

The following example shows how to use the POLL command to request a specific message output type.

First configure the SkyVUE™8 into polling mode as shown in the example above and exit the terminal interface. To poll the SkyVUE™8 for a particular message type, type the following.

```
“POLL 0 113”
```

The example text above will request the “CT25K Message 1” and should look similar to the text below.

```
“CT00010  
10 12345 // // // // 00000f80”
```

5.1.8 Loading a New Operating System (OS)

A new OS can be entered with the LOADOS command.

NOTE

The new OS must be sent using xmodem protocol using Tera Term. See [Section 5.1.2](#).

To load a new operating system:

Enter terminal mode by typing “Open 0” (for a sensor with the default ID “0”)

This will return the prompt “CS136>”

Type the command “LOADOS”

The SkyVUE™8 will respond:

```
“Load OS into DSP
DO NOT REMOVE POWER DURING OS UPDATE!!!
Waiting for xmodem”
```

At this point use your terminal emulator to send the appropriate file.
Loading the OS could take a few minutes.

When the process is complete the SkyVUE™8 will return the message:

```
“Updating DSP OS, please wait....PASS
Updating TOP OS, please wait....PASS
Updating PSU OS, please wait....PASS
```

Wait 40 sec for OS to restart”

after which it will resume operation according to the previously set operating parameters. It will no longer be in terminal mode.

5.1.9 Stratocumulus backscatter calibration

The command “SCCAL” allows a simple Stratocumulus backscatter calibration of the scatter coefficient measurements. This requires a human observer to confirm a stable Stratocumulus cloud layer between 250 m (820 ft) to 2500 m (8202 ft) without holes, precipitation or reduced visibility and has been stable for at least 10 minutes prior to running this command.

Measurement_Period should be set to 10s. See [Table 5.1](#).

A detailed description of this technique is given in: Ewan J. O’Connor, Anthony J. Illingworth, and Robin J. Hogan, 2004: A Technique for Autocalibration of Cloud Lidar. *Journal of Atmospheric and Ocean Technology*, **21**, pp 777 – 786.

Enter terminal mode by typing “Open 0” (for a sensor with the default ID “0”)

This will return the prompt “CS136>”

Type the command “SCCAL”

The SkyVUE™8 will respond:

```
“Stratocumulus calibration.
Enter height above sea level (m)? Press enter to continue:”
```

Enter the sensor height above sea level, for example 70 m and type return.

The SkyVUE™8 will respond “70 m entered, is this correct? “Y”, “N” or “Q” ”

Type “Y” to confirm or if you have entered an incorrect number type “N” and you will be able to replace it. Typing “Q” will quit the calibration and return to the terminal command prompt.

The SkyVUE™8 will now respond:

“For correct calibration a trained human observer must confirm that the layer is between 250 m (820 ft) to 2500 m (8200 ft) and has been stable for at least 10 minutes without drizzle. Has the Stratocumulus been stable for at least 10 minutes? “Y” or “N” ”

To confirm type “Y”

The SkyVUE™8 will respond:

“Old Stratocumulus calibration = 0.0282
 New Stratocumulus calibration parameters = 0.0258 70 1328
 Do you want to apply this calibration? “Y” or “N” ”

In this example 70 is the height of the sensor above sea level previously entered and 1210 is the cloud base in metres above the sensor.

As a very rough guide if the calibration factor has changed by less than 20% there is probably no need to change. If it has changed by a factor of 2 it is wise to run the service routine on the sensor ([See 5.1.11](#)).

Type “Y” to confirm and the SkyVUE™8 will respond:

“Calibration saved.”

The following error messages may appear during the process.

- Error ... Time out
- Error ... Cloud not detected or height not within limits (250 m to 2500 m / 820 ft to 8200 ft)
- Try again when layer is stable
- Error ... Not enough data available try again in 10 minutes.

5.1.10 CRC-16 Codes on terminal commands

If CRC-16 on mode is set using the “Terminal” command, all terminal commands need a CRC-16. A semi-colon is used to indicate start of the CRC-16 in 4 byte ASCII hex, for example “open 0;d2d5”. The CRC-16 is calculated either from the start of a new line or after a [STX] up to but not including the semi-colon. ETX can follow the CRC-16 if required.

The valid CRC-16 can be found for any command by entering the command with the 4 character CRC-16 after the semi-colon replaced with “????”. For example entering “open 0;????” gives the response “[CRLF]CRC>D2D5<CRC[CRLF]” so d2d5 is the CRC-16.

The CRC-16 is not case sensitive.

The table below gives some commonly used CRC-16 codes.

Terminal Command	CRC-16
Open 0	233A
Close	D94E
Status	7CE5
Password	DF20
Terminal 0 (this command will remove CRC-16 checking)	B576
Defaults	7D8E
Serial	7FCE

5.1.11 Service command

The service command triggers the SkyVUE™8 to go through a series of tests including tests that require the white test surface (ceilometer calibration plate supplied) to be placed on the SkyVUE™8 windows.

The service command results in the following procedures:

- System noise level including noise spike test
- Detector maximum gain test
- Simulates a clear night sky for calibration offset
- Window contamination functionality test
- Laser function and monitoring alarm check
- Thermistor fault alarm check
- Calibrator LED alarm check
- PSU supply alarm check
- Temperature RH% sensor alarm check
- Inclinator alarm check
- Heater/blower alarm check
- Internal clocks alarm check
- Top board and PSU communications alarm check.

If any test or check has failed then full instrument status and debug information is output with a fault summary at the end.

The response is similar to the following:

Initially the SkyVUE™8 will output a “STATUS” message. It will then go through various self-test routines and before requesting a white test surface to be placed over each of the windows in turn. This process is as follows:

```
self test, please wait
wait for new measurement.....
Place white test surface onto detector window (left hand side fan at the top)
Press enter key to continue
```

At this point cover the detector window and press the “Enter” key.

```
wait for new measurement.....
Place white test surface onto laser window (right hand side fan at the top)
Press enter key to continue
```

At this point cover the laser window and press the “Enter” key.

```
wait for new measurement.....
Remove white test surface from laser window. Press enter key to continue
```

When this is complete the SkyVUE™8 will output a string of diagnostic data similar. This can be very useful for a Campbell Scientific engineer investigating problems with the SkyVUE™8.

Finally the SkyVUE™8 will list any faults found as shown below:

```
***** CS136 FAULT list *****
FAULT - external heater/blower thermistor
```

FAULT - detector dirty windows with white test surface
FAULT - max APD gain not achieved

Otherwise it will report the following message:
***** CS136 has PASSED all tests *****

5.1.12 Locked features

Optional features are protected by a “key”. They are enabled by typing the command “UNLOCK” followed by the key. This is specific to the individual SkyVUE™8 and only has to be entered once.

5.2 Restoring Factory Defaults

Factory defaults can be restored using the terminal mode command “DEFAULTS”.

Hard Reset

Alternatively, factory defaults can be restored by using the RESET push switch on the DSP, as shown in [Fig 5.1](#).

The access door must first be opened.

WARNING **Opening the access door MUST be carried out by a competent person, who has sufficient training, experience and knowledge both in electrical safety and the detail and operation of the sensor.**

WARNING **Opening the access door may expose hot surfaces.**

The reset switch is recessed and can only be reached using a narrow tool.

If the reset switch is pushed for four seconds the SkyVUE™8 will reboot in exactly the same way as the REBOOT terminal command. If it is held closed while the SkyVUE™8 is powered off and on again it will return to factory defaults. Note that to power cycle the SkyVUE™8 the battery has to be disconnected as well as switching the main power off and on.

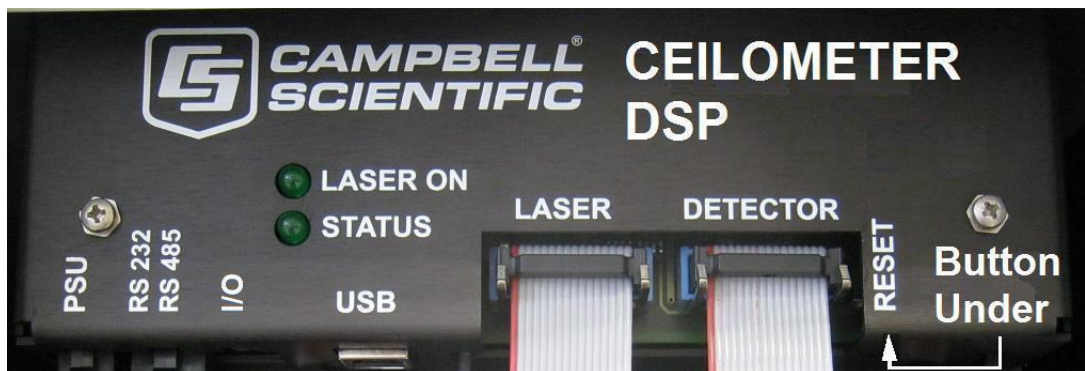


Fig 5.1 Restoring Factory Defaults

5.3 LED Indicator



Figure 5.2 LED indicator

A green LED is visible through the window, see [Fig 5.2](#). It will give 0.5 second flashes as follows:

- Permanently on = top board firmware fault
- 1 flash every 10 seconds = OK, no fault
- 2 flashes every 10 seconds = warning (possible degraded performance)
- 3 flashes every 10 seconds = alarm (measurements not possible)

6. Messages

6.1 Data Messages General

The SkyVUE™8 can provide a variety of data message types to allow efficient output of data. Not all messages provide the full information available but these messages may be more efficient in terms of data storage and transmission.

CL31 and CT25K messages follow formats used by common existing CL31 and CT25K sensors allowing easier replacement or network expansion.

6.2 Checksums used in SkyVUE™8 messages

This is based on the CCITT-16 CRC-16 with the output XOR'd with Hex 0xFFFF and outputs a two byte CRC-16 in hex format (four ASCII characters). The CRC-16 is calculated on all characters after the SOH character up to and including the ETX character.

The following example “C” code calculates the SkyVUE™8 checksum.

NOTE

“Shorts” are 16 bits long and “ints” are 32 bits long.

```
// -----  
-----  
// Calculate CRC-16  
// buf is a pointer to the input string  
// len is the length of the input string  
// -----  
-----  
unsigned short crc16(char *buffer, int length)  
{  
    unsigned short crc;  
    unsigned short m;  
    int i, j;  
  
    crc = 0xFFFF;  
  
    for (i=0; i < length; ++i)  
    {  
        crc ^= buffer[i] << 8;  
  
        for (j=0; j<8; ++j){  
            m = (crc & 0x8000) ? 0x1021 : 0;  
            crc <<= 1;  
            crc ^= m;  
        }  
    }  
    crc ^= 0xFFFF;  
    return crc;  
}
```

6.3 CS Messages

Message 001 (no profile, no sky condition) – Default message

Example message line outputs

```
CS0001001
10 087 00139 //// //// //// 800000000000
942f
```

LINE 1

SOH CS ID OS N STX CR LF

where

SOH = Start-of-Heading character

CS = Always "CS"

ID(1 character) = A single ASCII character, 0-9, a - z or A - Z, case sensitive. Default ID = 0

OS (3 characters) = Operating system, 001 ... 999

N (3 characters) = Message number

STX = Start-of-Text Character

CR LF = Carriage Return + Line Feed

LINE 2

S WA_tr_h1_h2_h3_h4_flags CR LF

where

S (1 character) = detection status:

0 = No significant backscatter

1 = One cloud base detected

2 = Two cloud bases detected

3 = Three cloud bases detected

4 = Four cloud bases detected

5 = Full obscuration determined but no cloud base detected

6 = Some obscuration detected but determined to be transparent

/ = Raw data input to algorithm missing or suspect

WA (1 character) = Warning or alarm status:

0 = No alarm or warning

W = Warning

A = Alarm

tr (3 characters) = Window transmission, %

h1 (5 characters) = 1st Height

If detection status is 1, 2, 3 or 4 *h1* = Lowest cloud base reported

If detection status is 5 *h1* = Vertical visibility as calculated

If detection status is 0 or 6 *h1* = "/////"

h2 (5 characters) = 2nd Height

If detection status is 2, 3 or 4 *h2* = Second cloud base reported

If detection status is 5 *h2* = Highest signal received

If detection status is 0, 1, or 6 *h2* = "/////"

h3 (5 characters) = 3rd Height

If detection status is 3 or 4 *h3* = Third cloud base reported

If detection status is 0, 1, 2, 5 or 6 *h3* = "/////"

h4 (5 characters) = 4th Height

If detection status is 4 *h4* = Fourth cloud base reported

If detection status is 0, 1, 2, 3 or 5 *h4* = "/////"

flags (12 characters in 3 groups of 4) = Alarm or warning information

Description of the most significant alarm word (left side, bits going left to right). Each alarm word is a hexadecimal sum of all the error bits.	
Bit	Description
8000 XXXX XXXX	Units. Feet = 0, metre = 1.
4000 XXXX XXXX	<i>Reserved for future use</i>
2000 XXXX XXXX	<i>Reserved for future use</i>
1000 XXXX XXXX	<i>Reserved for future use</i>
0800 XXXX XXXX	DSP clock out of specification
0400 XXXX XXXX	Laser shut down due to operating temperature out of range
0200 XXXX XXXX	The lead acid battery voltage is reading low
0100 XXXX XXXX	Mains supply has failed (Required a PSU to be present)
0080 XXXX XXXX	The external heater blower assembly temperature is out of bounds
0040 XXXX XXXX	External heater blower failure
0020 XXXX XXXX	The PSUs internal temperature is high
0010 XXXX XXXX	PSU OS has failed its signature check
0008 XXXX XXXX	No communications between DSP and PSU
0004 XXXX XXXX	Photo diode and Laser windows are dirty. This can only be set if the laser is on
0002 XXXX XXXX	Tilt beyond limit set by user, default 45 degrees
0001 XXXX XXXX	No communications between DSP and inclinometer board

Description of the middle alarm word (middle word, bits going left to right)	
Bit	Description
XXXX 8000 XXXX	The sensors internal humidity is high
XXXX 4000 XXXX	Communications to the DSP board temperature and humidity chip have failed
XXXX 2000 XXXX	DSP input supply voltage is low
XXXX 1000 XXXX	Self-test active
XXXX 0800 XXXX	Watch dog counter updated
XXXX 0400 XXXX	User setting stored in flash failed their signature checks
XXXX 0200 XXXX	DSP factory calibration stored in flash has failed its signature check
XXXX 0100 XXXX	DSP board OS signature test failed
XXXX 0080 XXXX	DSP board RAM test failed
XXXX 0040 XXXX	DSP boards on board PSUs are out of bounds
XXXX 0020 XXXX	TOP board non-volatile storage is corrupt
XXXX 0010 XXXX	TOP board OS signature test has failed
XXXX 0008 XXXX	TOP boards ADC and DAC are not within specifications
XXXX 0004 XXXX	TOP boards on board PSUs are out of bounds
XXXX 0002 XXXX	Communications have failed between TOP board and the DSP
XXXX 0001 XXXX	Photo diode background radiance is out of range

Description of the least significant alarm word (right side, bits going left to right)	
Bit	Description
XXXX XXXX 8000	Photo diode temperature is out of range
XXXX XXXX 4000	Photo diode is saturated
XXXX XXXX 2000	Photo diode calibrator temperature is out of range
XXXX XXXX 1000	Photo diode calibrator has failed
XXXX XXXX 0800	The sensor could not reach the desired gain levels
XXXX XXXX 0400	Laser run time or maximum laser drive current has been exceeded
XXXX XXXX 0200	Laser temperature out of range
XXXX XXXX 0100	Laser thermistor failure
XXXX XXXX 0080	Laser is obscured. This can only be set if the laser is on
XXXX XXXX 0040	Laser did not achieve significant output power
XXXX XXXX 0020	Laser max power exceeded
XXXX XXXX 0010	Laser max drive current exceeded
XXXX XXXX 0008	Laser power monitor temperature out of range
XXXX XXXX 0004	Laser power monitor test fail
XXXX XXXX 0002	Laser shutdown by top board
XXXX XXXX 0001	Laser is off

CR LF = Carriage Return and Line Feed

LINE 3

ETX CRC-16 EOT CR LF

where

ETX = End-of-Text character

CRC-16 (4 characters) = CRC-16 Checksum

EOT = End-of-Transmission character

CRLF = Carriage Return + Line Feed

MESSAGE 002 (Profile, no sky condition)

Example message line outputs

```
CS0001002
10 085 01123 //// //// //// 800000000000
00100 05 2048 100 +40 02 0074 0070 30 000
0c5df047.....00000 (Line output cropped for clarity)
9f68
```

LINE 1

SOH CS ID OS N STX CR LF

where

SOH = Start-of-Heading character

CS = Always "CS"

ID (1 character) = A single ASCII character, 0-9, a - z or A - Z, case sensitive. Default ID = 0

OS (3 characters) = Operating system, 001 ... 999

N (3 characters) = Message number

STX = Start-of-Text Character

CR LF = Carriage Return + Line Feed

LINE 2

S WA_tr_h1_h2_h3_h4_flags CR LF

where

S (1 character) = detection status:

0 = No significant backscatter

1 = One cloud base detected

2 = Two cloud bases detected

3 = Three cloud bases detected

4 = Four cloud bases detected

5 = Full obscuration determined but no cloud base detected

6 = Some obscuration detected but determined to be transparent

/ = Raw data input to algorithm missing or suspect

WA (1 character) = Warning or alarm status:

0 = No alarm or warning

W = Warning

A = Alarm

tr (3 characters) = Window transmission, %

h1 (5 characters) = 1st Height

If detection status is 1, 2, 3 or 4 *h1* = Lowest cloud base reported

If detection status is 5 *h1* = Vertical visibility as calculated

If detection status is 0 or 6 *h1* = "/////"

h2 (5 characters) = 2nd Height

If detection status is 2, 3 or 4 *h2* = Second cloud base reported

If detection status is 5 *h2* = Highest signal received

If detection status is 0, 1, or 6 *h2* = "/////"

h3 (5 characters) = 3rd Height

If detection status is 3 or 4 *h3* = Third cloud base reported

If detection status is 0, 1, 2, 5 or 6 *h3* = "/////"

h4 (5 characters) = 4th Height

If detection status is 4 *h4* = Fourth cloud base reported

If detection status is 0, 1, 2, 3 or 5 *h4* = "/////"

flags (12 characters in 3 groups of 4) = Alarm or warning information.

Refer to Message 001 for a breakdown of the flags.

CR LF = Carriage Return and Line Feed

LINE 3

scale_res_n_energy_lt_ti_bl_pulse_rate_sum CR LF

where

scale (5 characters) = Attenuated_SCALE parameter, %, 0 ... 99999. 100% is default

res (2 characters) = Backscatter profile resolution in metres

n (4 characters) = Profile length

energy (3 characters) = Laser pulse energy, %.

lt (3 characters including leading +/-) = Laser temperature, degrees C

ti (2 characters) = Total tilt angle, degrees

bl (4 characters) = Background light, millivolts at internal ADC input (0 ... 2500)

MESSAGE 003 (no profile, sky condition)**Example message line outputs**

```

CS0001003
10 091 00828 // // // // 800000000000
99 // // 0 // // 0 // // 0 // //
f62a

```

LINE 1

SOH CS ID OS N STX CR LF

where

SOH = Start-of-Heading character

CS = Always "CS"

ID(1 character) = A single ASCII character, 0-9, a - z or A - Z, case sensitive. Default ID = 0

OS (3 characters) = Operating system, 001 ... 999

N (3 characters) = Message number

STX = Start-of-Text Character

CR LF = Carriage Return + Line Feed

LINE 2

S WA_tr_h1_h2_h3_h4_flags CR LF

where

S (1 character) = detection status:

0 = No significant backscatter

1 = One cloud base detected

2 = Two cloud bases detected

3 = Three cloud bases detected

4 = Four cloud bases detected

5 = Full obscuration determined but no cloud base detected

6 = Some obscuration detected but determined to be transparent

/ = Raw data input to algorithm missing or suspect

WA (1 character) = Warning or alarm status:

0 = No alarm or warning

W = Warning

A = Alarm

tr (3 characters) = Window transmission, %

h1 (5 characters) = 1st Height

If detection status is 1, 2, 3 or 4 *h1* = Lowest cloud base reported

If detection status is 5 *h1* = Vertical visibility as calculated

If detection status is 0 or 6 *h1* = "/////"

h2 (5 characters) = 2nd Height

If detection status is 2, 3 or 4 *h2* = Second cloud base reported

If detection status is 5 *h2* = Highest signal received

If detection status is 0, 1, 5 or 6 *h2* = "/////"

h3 (5 characters) = 3rd Height

If detection status is 3 or 4 *h3* = Third cloud base reported

If detection status is 0, 1, 2, 5 or 6 *h3* = "/////"

h4 (5 characters) = 4th Height

If detection status is 4 *h4* = Fourth cloud base reported

If detection status is 0, 1, 2, 3 or 5 *h4* = "/////"

flags (12 characters in 3 groups of 4) = Alarm or warning information.

Refer to Message 001 for a breakdown of the flags.

CR LF = Carriage Return and Line Feed

LINE 3

_d_h1__d2_h2__d3_h3__d4_h4__d5_h5 CR LF

(note spaces)

where

d (2 characters) = Data available

_0 to _8 Amount of lowest layer in oktas

_9 Vertical visibility only available

-1 No sky condition data available

99 Insufficient data

h1 (4 characters) = Height of the lowest cloud layer in 10s of metres or 100s of feet

d2 (1 character) = Cloud amount of the 2nd layer in oktas

h2 (4 characters) = Height of the 2nd cloud layer in 10s of metres or 100s of feet, if no 2nd layer is reported *h2* = "////".

d3 (1 character) = Cloud amount of the 3rd layer in oktas

h3 (4 characters) = Height of the 3rd cloud layer in 10s of metres or 100s of feet, if no 3rd layer is reported *h3* = "////".

d4 (1 character) = Cloud amount of the 4th layer in oktas

h4 (4 characters) = Height of the 4th cloud layer in 10s of metres or 100s of feet, if no 4th layer is reported *h4* = "////".

d5 (1 character) = Cloud amount of the 5th layer in oktas

h5 (4 characters) = Height of the 5th cloud layer in 10s of metres or 100s of feet, if no 5th layer is reported *h5* = "////".

CR LF = Carriage Return + Line Feed

Note cloud amounts and heights cannot be reported until the SkyVUE™8 has been in operation for 30 minutes.

LINE 4

ETX CRC-16 EOT CR LF

where

ETX = End-of-Text character

CRC-16 (4 characters) = CRC-16 Checksum

EOT = End-of-Transmission character

CR LF = Carriage Return + Line Feed

MESSAGE 004 (profile, sky condition)

Example message line outputs

```
CS0001004
10 092 00698 //// //// //// 800000000000
99 //// 0 //// 0 //// 0 //// 0 ////
00100 05 2048 100 +40 02 0074 0070 30 000
071fc024d.....000 (Line output cropped for clarity)
6212
```

LINE 1

SOH CS ID OS N STX CR LF

where

SOH = Start-of-Heading character

CS = Always "CS"

ID (1 character) = A single ASCII character, 0-9, a - z or A - Z, case sensitive. Default ID = 0

OS (3 characters) = Operating system, 001 ... 999

N (3 characters) = Message number

STX = Start-of-Text Character

CR LF = Carriage Return + Line Feed

LINE 2

S WA_tr_h1_h2_h3_h4_flags CR LF

where

S (1 character) = detection status:

0 = No significant backscatter

1 = One cloud base detected

2 = Two cloud bases detected

3 = Three cloud bases detected

4 = Four cloud bases detected

5 = Full obscuration determined but no cloud base detected

6 = Some obscuration detected but determined to be transparent

/ = Raw data input to algorithm missing or suspect

WA (1 character) = Warning or alarm status:

0 = No alarm or warning

W = Warning

A = Alarm

Tr (3 characters) = Window transmission, %

h1 (5 characters) = 1st Height

If detection status is 1, 2, 3 or 4 h1 = Lowest cloud base reported

If detection status is 5 h1 = Vertical visibility as calculated

If detection status is 0 or 6 h1 = "/////"

h2 (5 characters) = 2nd Height

If detection status is 2, 3 or 4 h2 = Second cloud base reported

If detection status is 5 h2 = Highest signal received

If detection status is 0, 1, or 6 h2 = "/////"

h3 (5 characters) = 3rd Height

If detection status is 3 or 4 h3 = Third cloud base reported

If detection status is 0, 1, 2, 5 or 6 h3 = "/////"

h4 (5 characters) = 4th Height

If detection status is 4 h4 = Fourth cloud base reported

If detection status is 0, 1, 2, 3 or 5 h4 = "/////"

flags (12 characters in 3 groups of 4) = Alarm or warning information.

Refer to Message 001 for a breakdown of the flags.

CR LF = Carriage Return + Line Feed.

LINE 3

_d_h1h1h1__d2_h2h2h2__d3_h3h3h3__d4_h4h4h4__d5_h5h5h5 CR LF

(note spaces)

where

d (2 characters) = Data available

_0 to _8 Amount of lowest layer in oktas

_9 Vertical visibility only available

-1 No sky condition data available

99 Insufficient data

h1 (4 characters) = Height of the lowest cloud layer in 10s of metres or 100s of feet

d2 (1 character) = Cloud amount of the 2nd layer in oktas

h2 (4 characters) = Height of the 2nd cloud layer in 10s of metres or 100s of feet, if no 2nd layer is reported h2 = "////".

d3 (1 character) = Cloud amount of the 3rd layer in oktas

h3 (4 characters) = Height of the 3rd cloud layer in 10s of metres or 100s of feet, if no 3rd layer is reported *h3* = "////".

d4 (1 character) = Cloud amount of the 4th layer in oktas

h4 (4 characters) = Height of the 4th cloud layer in 10s of metres or 100s of feet, if no 4th layer is reported *h4* = "////".

d5 (1 character) = Cloud amount of the 5th layer in oktas

h5 (4 characters) = Height of the 5th cloud layer in 10s of metres or 100s of feet, if no 5th layer is reported *h5* = "////".

CR LF = Carriage Return + Line Feed

Note cloud amounts and heights cannot be reported until the SkyVUE™8 has been operating for 30 minutes.

LINE 4

scale_res_n_energy_lt_tr_ti_bl_pulse_rate_sum CR LF

where

scale (5 characters) = Scale parameter, %, 0 ... 99999. 100% is default

res (2 characters) = Backscatter profile resolution in metres

n (4 characters) = Profile length

energy (3 characters) = Laser pulse energy, %.

lt (3 characters including leading +/-) = Laser temperature, degrees C

ti (2 characters) = Total tilt angle, degrees

bl (4 characters) = Background light, millivolts at internal ADC input (0 ... 2500)

pulse (4 characters) = Pulse quantity x 1000 (0000-9999)

rate (2 characters) = Sample rate, MHz, (00-99)

sum = (3 characters) Sum of detected and normalized backscatter, 0 ... 999. Multiplied by scaling factor times 10^4 . At scaling factor 100 the SUM range 0 ... 999 corresponds to integrated backscatter 0 ... 0. srad^{-1} .

CR LF = Carriage Return + Line Feed

6.4 CL31 Messages

MESSAGES 101 - 106, (CL31 MESSAGE 1)

Example message 101 line outputs

```
CL017011
10 01128 ///// ///// 000000000E080
00100 10 0770 100 +40 094 02 0032 L0112HN30 000
036B200CC1002.....EEFFB3F           (Line output cropped for clarity)
e515
```

LINE 1

SOH CL ID OS 1 Samples STX CR LF

where

SOH = Start-of-Heading character

CL = Always CL

ID = A single ASCII character, 0-9, a - z or A - Z, case sensitive. Default ID = 0

OS = Operating system, 100 ... 999

1 = Always 1

Samples = backscatter resolution and number of samples

1 = MESSAGE 101, 10 m x 770 samples, range 7700 m

2 = MESSAGE 102, 20 m x 385 samples, range 7700 m

3 = MESSAGE 103, 5 m x 1500 samples, range 7500 m

4 = MESSAGE 104, 5 m x 770 samples, range 3850 m

5 = MESSAGE 105, no backscatter profile

0 = MESSAGE 106, extended range, 5 m x 2048 samples, range 10,240 m

STX = Start-of-Text Character

CR LF = Carriage Return + Line Feed

LINE 2

S WA_h1_h2_h3_flags CR LF

where

S (1 character) = detection status:

0 = No significant backscatter

1 = One cloud base detected

2 = Two cloud bases detected

3 = Three cloud bases detected

4 = Full obscuration determined but no cloud base detected

5 = Some obscuration detected but determined to be transparent

/ = Raw data input to algorithm missing or suspect

WA (1 character) = Warning or alarm status:

0 = No alarm or warning

W = Warning

A = Alarm

h1 (5 characters) = 1st Height

If detection status is 1, 2 or 3 *h1* = Lowest cloud base reported

If detection status is 4 *h1* = Vertical visibility as calculated

If detection status is 0 or 5 *h1* = "/////"

h2 (5 characters) = 2nd Height

If detection status is 2 or 3 *h2* = Second cloud base reported

If detection status is 4 *h2* = Highest signal received

If detection status is 0, 1 or 5 *h2* = "/////"

h3 (5 characters) = 3rd Height

If detection status is 3 *h3* = Third cloud base reported

If detection status is 0, 1, 2, 4 or 5 *h3* = "/////"

flags (12 characters) = Alarm or warning information

Description of the most significant alarm word (left word, bits going left to right)	
Bit	Description
8000 XXXX XXXX	Transmitter shut-off
4000 XXXX XXXX	Transmitter failure
2000 XXXX XXXX	Receiver failure
1000 XXXX XXXX	Reserved for future use
0800 XXXX XXXX	Reserved for future use
0400 XXXX XXXX	Memory error
0200 XXXX XXXX	Light path obstruction
0100 XXXX XXXX	Receiver saturation
0080 XXXX XXXX	Reserved for future use
0040 XXXX XXXX	Reserved for future use
0020 XXXX XXXX	Reserved for future use
0010 XXXX XXXX	Reserved for future use
0008 XXXX XXXX	Reserved for future use
0004 XXXX XXXX	Reserved for future use
0002 XXXX XXXX	Reserved for future use
0001 XXXX XXXX	Ceilorometer engine board failure

Description of the middle alarm word (middle word, bits going left to right)	
Bit	Description
XXXX 8000 XXXX	Window contamination
XXXX 4000 XXXX	Battery voltage low
XXXX 2000 XXXX	Transmitter expires
XXXX 1000 XXXX	High humidity
XXXX 0800 XXXX	Reserved for future use
XXXX 0400 XXXX	Blower failure
XXXX 0200 XXXX	Reserved for future use
XXXX 0100 XXXX	Humidity sensor failure
XXXX 0080 XXXX	Heater fault
XXXX 0040 XXXX	High background radiance
XXXX 0020 XXXX	Ceilometer engine board failure
XXXX 0010 XXXX	Reserved for future use
XXXX 0008 XXXX	Laser monitor failure
XXXX 0004 XXXX	Receiver warning
XXXX 0002 XXXX	Tilt beyond limit set by user, default 45 degrees
XXXX 0001 XXXX	Reserved for future use

Description of the least significant alarm word (right word, bits going left to right)	
Bit	Description
XXXX XXXX 8000	Blower is on
XXXX XXXX 4000	Blower heater is on
XXXX XXXX 2000	Internal heater is on
XXXX XXXX 1000	Working from battery
XXXX XXXX 0800	Reserved for future use
XXXX XXXX 0400	Self test in progress
XXXX XXXX 0200	Reserved for future use
XXXX XXXX 0100	Reserved for future use
XXXX XXXX 0080	Units are metres if on, else feet
XXXX XXXX 0040	Reserved for future use
XXXX XXXX 0020	Polling mode is on
XXXX XXXX 0010	Reserved for future use
XXXX XXXX 0008	Reserved for future use
XXXX XXXX 0004	Reserved for future use
XXXX XXXX 0002	Reserved for future use
XXXX XXXX 0001	Reserved for future use

CR LF = Carriage Return + Line Feed

LINE 3

scale_res_n_energy_lt_tr_ti_bl_L0112HN15_sum CR LF

where

scale (5 characters) = Scale parameter,%, 0 ... 99999. 100% is typical

res (2 characters) = Backscatter profile resolution in metres

n (4 characters) = Profile length 385, 770, 1400, or 1500 samples

energy (3 characters) = Laser pulse energy, %

MESSAGES 107 - 112, CL31 Message 2

Example message 107 line outputs

```
CL017021
10 01407 ///// ///// 00000000E080
99 /// 0 /// 0 /// 0 /// 0 ///
00100 10 0770 100 +40 095 02 0031 L0112HN30 000
03301009.....027F (Line output cropped for clarity)
e669
```

LINE 1

SOH CL ID OS 2 Samples STX CR LF

where

SOH = Start-of-Heading character

CL = Always CL

ID = A single ASCII character, 0-9, a - z or A - Z, case sensitive. Default ID = 0

OS = Operating system, 100 ... 999

2 = Always 2

Samples = backscatter resolution and number of samples

1 = MESSAGE 107, 10 m x 770 samples, range 7700 m

2 = MESSAGE 108, 20 m x 385 samples, range 7700 m

3 = MESSAGE 109, 5 m x 1500 samples, range 7500 m

4 = MESSAGE 110, 5 m x 770 samples, range 3850 m

5 = MESSAGE 111, no backscatter profile

0 = MESSAGE 112, extended range, 5 m x 2048 samples, range 8000 m (samples after 1600 are "00000")

STX = Start-of-Text Character

CR LF = Carriage Return + Line Feed

LINE 2

S WA_h1_h2_h3_flags CR LF

where

S (1 character) = detection status:

0 = No significant backscatter
 1 = One cloud base detected
 2 = Two cloud bases detected
 3 = Three cloud bases detected
 4 = Full obscuration determined but no cloud base detected
 5 = Some obscuration detected but determined to be transparent
 / = Raw data input to algorithm missing or suspect

WA (1 character) = Warning or alarm status:

0 = No alarm or warning
 W = Warning
 A = Alarm

h1 (5 characters) = 1st Height

If detection status is 1, 2 or 3 *h1* = Lowest cloud base reported

If detection status is 4 *h1* = Vertical visibility as calculated

If detection status is 0 or 5 *h1* = "/////"

h2 (5 characters) = 2nd Height

If detection status is 2 or 3 *h2* = Second cloud base reported

If detection status is 4 *h2* = Highest signal received

If detection status is 0, 1 or 5 *h2* = "/////"

h3 (5 characters) = 3rd Height

If detection status is 3 *h3* = Third cloud base reported

If detection status is 0, 1, 2, 4 or 5 *h3* = "/////"

flags (12 characters) = Alarm or warning information.

Same as for messages 101 – 106

CR LF = Carriage Return + Line Feed

LINE 3

__d_h1h1h1__d2_h2h2h2__d3_h3h3h3__d4_h4h4h4__d5_h5h5h5 CR LF

(note spaces)

where

d (1 character) = Data available

0 to 8 Amount of lowest layer in oktas
9 Vertical visibility only available
-1 No sky condition data available
99 Insufficient data

h1h1h1 (3 characters) = Height of the lowest cloud layer in 10s of metres or 100s of feet

d2 (1 character) = Cloud amount of the 2nd layer in oktas

h2h2h2 (3 characters) = Height of the 2nd cloud layer in 10s of metres or 100s of feet, if no 2nd layer is reported *h2h2h2* = "///".

d3 (1 character) = Cloud amount of the 3rd layer in oktas

h3h3h3 (3 characters) = Height of the 3rd cloud layer in 10s of metres or 100s of feet, if no 3rd layer is reported *h3h3h3* = "///".

d4 (1 character) = Cloud amount of the 4th layer in oktas

h4h4h4 (3 characters) = Height of the 4th cloud layer in 10s of metres or 100s of feet, if no 4th layer is reported *h4h4h4* = "///".

d5 (1 character) = Cloud amount of the 5th layer in oktas

h5h5h5 (3 characters) = Height of the 5th cloud layer in 10s of metres or 100s of feet, if no 5th layer is reported *h5h5h5* = "///".

CR LF = Carriage Return + Line Feed

NOTE Cloud amount and height cannot be reported until the SkyVUE™8 has been operating for 30 minutes.

LINE 4

scale_res_n_energy_lt_tr_ti_bl_L0112HN15_sum CR LF

where

scale (5 characters) = Scale parameter, %, 0 ... 99999. 100% is typical

res (2 characters) = Backscatter profile resolution in metres

n (4 characters) = Profile length 385, 770, 1400, or 1500 samples

energy (3 characters) = Laser pulse energy, %

lt (3 characters including leading +/-) = Laser temperature, degrees C

6.5 CT25K Messages

MESSAGE 113, CT25K Data Message No. 1

Example message line outputs

CT02010

20 01333 01523 ///// 00000F00

LINE 1

SOH CT ID 20 10 STX CR LF

where

SOH = Start-of-Heading character

CT = Always CT

ID (1 character) = Unit number 0 ... 9, A ... Z (capitals only) Default *ID* = 0

20 = Always “20”

10 = Always “10”

STX = Start-of-Text Character

CR LF = Carriage Return + Line Feed

LINE 2

S WA_h1_h2_h3_flags CR LF

where

S (1 character) = detection status:

0 = No significant backscatter

1 = One cloud base detected

2 = Two cloud bases detected

3 = Three cloud bases detected

4 = Full obscuration determined but no cloud base detected

5 = Some obscuration detected but determined to be transparent

/ = Raw data input to algorithm missing or suspect

WA (1 character) = Warning or alarm status:

0 = No alarm or warning

W = Warning

A = Alarm

h1 (5 characters) = 1st Height

If detection status is 1, 2 or 3 *h1* = Lowest cloud base reported

If detection status is 4 *h1* = Vertical visibility as calculated

If detection status is 0 or 5 *h1* = "/////"

h2 (5 characters) = 2nd Height

If detection status is 2 or 3 *h2* = Second cloud base reported

If detection status is 4 *h2* = Height of highest signal detected

If detection status is 0, 1 or 5 *h2* = "/////"

h3 (5 characters) = 3rd Height

If detection status is 3 *h3* = Third cloud base reported

If detection status is 0, 1, 2, 4 or 5 *h3* = "/////"

flags (8 characters) = Alarm or warning information 4-byte hex coded

Description of the most significant alarm word (left side, bits going left to right). Each alarm word is a hexadecimal sum of all the error bits.	
Bit	Description
8000 XXXX	Transmitter shut-off
4000 XXXX	Transmitter failure
2000 XXXX	Receiver failure
1000 XXXX	DSP, voltage or memory failure
0800 XXXX	Reserved for future use
0400 XXXX	Reserved for future use
0200 XXXX	Reserved for future use
0100 XXXX	Reserved for future use
0080 XXXX	Window contaminated
0040 XXXX	Battery low
0020 XXXX	Transmitter expire warning
0010 XXXX	Heater or humidity sensor failure
0008 XXXX	High radiance warning, also XXXX 0004
0004 XXXX	DSP, receiver, or laser monitor failure warning
0002 XXXX	Relative humidity > 85 %
0001 XXXX	Light path obstruction, receiver saturation or receiver failure

Description of the second alarm word (bits going left to right)	
Bit	Description
XXXX 8000	Blower failure
XXXX 4000	Reserved for future use
XXXX 2000	Reserved for future use
XXXX 1000	Reserved for future use
XXXX 0800	Blower on
XXXX 0400	Blower heater on
XXXX 0200	Internal heater on
XXXX 0100	Units metres if on, feet if off
XXXX 0080	Polling mode on
XXXX 0040	Working from battery
XXXX 0020	Always 0
XXXX 0010	Always 0
XXXX 0008	Tilt beyond limit set by user, default 45 degrees
XXXX 0004	High radiance warning, also 0008 XXXX
XXXX 0002	Reserved for future use
XXXX 0001	Reserved for future use

CR LF = Carriage Return + Line Feed

LINE 3

ETX CR LF

ETX = End-of-Text Character

CR LF = Carriage Return + Line Feed

MESSAGE 114, CT25K Data Message No. 6**Example message line outputs**

```
CT02060
10 01767 ///// ///// 00000F00
99 /// 0 /// 0 /// 0 ///
```

LINE 1

SOH CT ID 20 60 STX CR LF

where

SOH = Start-of-Heading character

CT = Always CT

ID (1 character) = Unit number 0 ... 9, A ... Z (capitals only) Default *ID* = 0

20 = always "20"

60 = always "60"

STX = Start-of-Text Character

CR LF = Carriage Return + Line Feed

LINE 2

S WA_h1_h2_h3_flags CR LF

where

S (1 character) = detection status:

0 = No significant backscatter

1 = One cloud base detected

2 = Two cloud bases detected

3 = Three cloud bases detected

4 = Full obscuration determined but no cloud base detected

5 = Some obscuration detected but determined to be transparent

/ = Raw data input to algorithm missing or suspect

WA (1 character) = Warning or alarm status:

0 = No alarm or warning

W = Warning

A = Alarm

h1 (5 characters) = 1st Height

If detection status is 1, 2 or 3 *h1* = Lowest cloud base reported

If detection status is 4 $h1$ = Vertical visibility as calculated

If detection status is 0 or 5 $h1$ = "////"

$h2$ (5 characters) = 2nd Height

If detection status is 2 or 3 $h2$ = Second cloud base reported

If detection status is 4 $h2$ = Height of highest signal detected

If detection status is 0, 1 or 5 $h2$ = "////"

$h3$ (5 characters) = 3rd Height

If detection status is 3 $h3$ = Third cloud base reported

If detection status is 0, 1, 2, 4 or 5 $h3$ = "////"

$flags$ (8 characters) = Alarm or warning information 4-byte hex coded

As for CT25K message 1.

$CR LF$ = Carriage Return + Line Feed

LINE 3 (Sky CONDITION)

$__d_h1h1h1_d2_h2h2h2_d3_h3h3h3_d4_h4h4h4$ $CR LF$

(note spaces)

where

d (1 character) = Data available

0 to 8 Amount of lowest layer in oktas

9 Vertical visibility only available

-1 No sky condition data available

99 Insufficient data

$h1h1h1$ (3 characters) = Height of the lowest cloud layer in 10s of metres or 100s of feet

$d2$ (1 character) = Cloud amount of the 2nd layer in oktas

$h2h2h2$ (3 characters) = Height of the 2nd cloud layer in 10s of metres or 100s of feet, if no 2nd layer is reported $h2h2h2$ = "///".

$d3$ (1 character) = Cloud amount of the 3rd layer in oktas

$h3h3h3$ (3 characters) = Height of the 3rd cloud layer in 10s of metres or 100s of feet, if no 3rd layer is reported $h3h3h3$ = "///".

$d4$ (1 character) = Cloud amount of the 4th layer in oktas

$h4h4h4$ (3 characters) = Height of the 4th cloud layer in 10s of metres or 100s of feet, if no 4th layer is reported $h4h4h4$ = "///".

$CR LF$ = Carriage Return + Line Feed

NOTE Cloud amount and height cannot be reported until the SkyVUE™8 has been operating for 30 minutes.

LINE 4

ETX CR LF

ETX = End-of-Text Character

CR LF = Carriage Return + Line Feed

7. Maintenance

7.1 General

The SkyVUE™8 is a robust weather resistant instrument and there is no need for routine maintenance other than cleaning. The instrument performance is monitored and any potential problems are indicated by error messages.

7.2 Cleaning

The SkyVUE™8 window will require cleaning from time to time. The frequency of required cleaning depends on the exposure of the instrument to contaminants such as salt and dust. This will vary depending on the site location. The SkyVUE™8 is capable of self diagnosing dirty lenses and will indicate in its output when the lenses are contaminated.

In any case we suggest six monthly intervals for locations not prone to contaminants and monthly intervals for those prone to contamination (coastal, roadside or airport use). In some cases more frequent cleaning may be required where there are high levels of contaminants and high dependency on the instrument output.

CAUTION If the window requires cleaning, it is very important that only a proper lens cloth or lens tissue is used. The use of inappropriate materials to clean the windows can permanently damage or reduce their effectiveness leading to reduced performance.

When the top cover is removed, avoid spraying the fan assembly with liquids. Use damp lens wipes or a clean soft cloth to clean the windows.

It is advisable to use an air duster to blow any loose dust and dirt from the window as a first step. Use a lint free lens cloth or lens tissue impregnated with a non-aggressive standard window cleaner. Clean the surface by dragging the cloth across it being careful not to apply excessive pressure.

Excessive pressure may lead to some types of contaminants scratching the window surface. Over time such scratches can lead to reduced sensitivity.

7.3 Diagnostic LED Indicators Within the Enclosure

Two green LEDs labelled "LASER ON" and "STATUS" are visible on the DSP (see [Fig 7.3](#)). Their function is as follows:

"LASER ON" LED:

- Off = laser off
- Flashing = laser fault
- On = laser on

"STATUS" LED

- 1 flash every 10 seconds = OK
- 2 flashes every 10 seconds = warning (possible degraded performance)
- 3 flashes every 10 seconds = alarm (measurements not possible)

The DSP "STATUS" LED duplicates the LED visible through the top window.

There is a red LED on the PSU. It will give 0.5 second flashes as follows:

- Permanently on = PSU firmware fault
- 1 flash every 10 seconds = PSU OK
- 2 flashes every 10 seconds = running in battery mode
- 3 flashes every 10 seconds = no communications to the DSP. This takes 60 seconds to start after a communications failure.

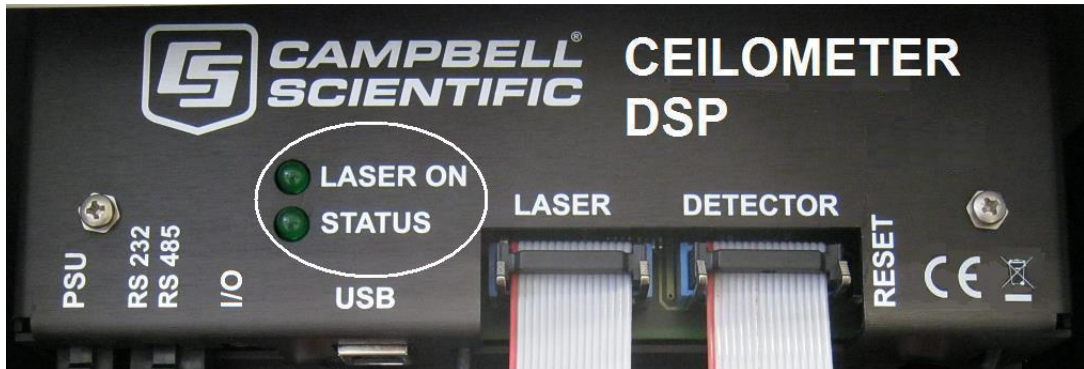


Fig 7.3 Diagnostic LED indicators

The red LED on the Laser module indicates:

- Off = Laser off
- On = Laser on

7.4 Electrical Safety Testing

NOTE If carrying out insulation tests do not use test voltages above 300V RMS because the sensor is designed to clamp any mains input voltages above this level. Voltage clamping can result in a false failure being detected.

Appendix A. Example CRBasic programs

A.1 Basic Logger program without CRC checking

This example is for use with the default message, CS message 1. For assistance with other messages please contact Campbell Scientific, UK.

```
'CR800 Series Datalogger
'Created by Sue Hill 18 July 2013

'SkyVUE8 Ceilometer connections
' Blue Tx C1
' White Rx C2
' Green G
'handshake lines shorted

SequentialMode

Const SOH = 1
Const STX = 2
Const ETX = 3
Const EOT = 4

Dim strInSkyVUE8 As String * 70
Dim Num_Bytes As Long
Dim strSkyVUE8_Message_Status As String * 1
Dim strSkyVUE8_Alarm_Status As String * 1

Dim SkyVUE8Lines(3) As String * 60
Dim CSLine2_Fields(7) As String * 20

Dim SkyVUE8_Unit_of_Measure As String * 3

Public strInformation As String * 100
Public strAlarm As String * 100
Public strError As String * 100

Alias CSLine2_Fields(1)=SkyVUE8_MessageAlarm_Status
Alias CSLine2_Fields(2)=SkyVUE8_Window_transmission
Alias CSLine2_Fields(3)=SkyVUE8_First_Height
Alias CSLine2_Fields(4)=SkyVUE8_Second_Height
Alias CSLine2_Fields(5)=SkyVUE8_Third_Height
Alias CSLine2_Fields(6)=SkyVUE8_Fourth_Height
Alias CSLine2_Fields(7)=SkyVUE8_Alarm_Flags

'Define Data Tables

DataTable(Ceilometer,True,-1)
  DataInterval(0,15,sec,10)
  Sample (1,strSkyVUE8_Message_Status,String)
  Sample (1,strSkyVUE8_Alarm_Status,String)
  Sample (1,SkyVUE8_First_Height, ieee4)
  Sample (1,SkyVUE8_Second_Height, ieee4)
  Sample (1,SkyVUE8_Third_Height, ieee4)
  Sample (1,SkyVUE8_Fourth_Height, ieee4)
  Sample(1,SkyVUE8_Alarm_Flags,String)
EndTable
```

```

'Main Program
BeginProg
  ' open the port to the SkyVUE8 Ceilometer
  'Assumes default serial settings, if not change baud rate & maybe format (2nd
& 3rd parameters)
  SerialOpen (Com1,115200,3,0,1000)
  SkyVUE8_Unit_of_Measure="ft"

  Scan(15,Sec,1,0)
  SerialInRecord (Com1,strInSkyVUE8,SOH,0,EOT,Num_Bytes,01)
  If Num_Bytes > 0 Then
    'Break up message on line feed separator
    SplitStr (SkyVUE8Lines,strInSkyVUE8,CHR(10),3,5)
    'Break up top line using space as separator
    SplitStr (CSLine2_Fields, SkyVUE8Lines(2)," ",7,5)
    'First character is msg status
    strSkyVUE8_Message_Status=Left (SkyVUE8_MessageAlarm_Status,1)
    'Last character is alarm status
    strSkyVUE8_Alarm_Status=Right (SkyVUE8_MessageAlarm_Status,1)
    If strSkyVUE8_Alarm_Status = "W" Then
      strAlarm = "Warning"
    ElseIf strSkyVUE8_Alarm_Status = "A" Then
      strAlarm = "Alarm"
    Else
      strAlarm = "OK"
    EndIf
    Select Case strSkyVUE8_Message_Status
    Case "0"
      strInformation = "No significant backscatter"
    Case "1"
      strInformation = "One cloud base detected"
    Case "2"
      strInformation = "Two cloud bases detected"
    Case "3"
      strInformation = "Three cloud bases detected"
    Case "4"
      strInformation = "Four cloud bases detected"
    Case "5"
      strInformation = "Full obscuration determined but no cloud base
detected"
    Case "6"
      strInformation = "Some obscuration detected but determined to be
transparent"
    Case "/"
      strInformation = "Raw data input to algorithm missing or suspect"
    Case Else
      strInformation = "Status of message unknown."
    EndSelect
    strError = ""
  Else
    strError = "COMMS ERROR - No Message received"
  EndIf

  'NOTE to be thorough we should really check message is complete & correct
by calculating CheckSum and comparing the checksum sent in the message (line
3), discarding the message if
  'there is no match.

  CallTable(Ceilometer)
NextScan
EndProg

```

A.2 Basic Logger program with CRC checking

```
'CR800 Series Datalogger
'Created by Sue Hill 18 July 2013

'SkyVUE8 Ceilometer connections
' Blue Tx C1
' White Rx C2
' Green G
'handshake lines shorted

SequentialMode

Const SOH = 1
Const STX = 2
Const ETX = 3
Const EOT = 4

Dim strInSkyVUE8 As String * 70
Dim Num_Bytes As Long
Dim strSkyVUE8_Message_Status As String * 1
Dim strSkyVUE8_Alarm_Status As String * 1
Dim lngCRCCalc As Long
Dim lngCRCMessage As Long
Dim DataOK As Boolean

Dim SkyVUE8Lines(3) As String * 60
Dim CSLine2_Fields(7) As String * 20

Dim SkyVUE8_Unit_of_Measure As String * 3

Public strInformation As String * 100
Public strAlarm As String * 100
Public strError As String * 100

Alias CSLine2_Fields(1)=SkyVUE8_MessageAlarm_Status
Alias CSLine2_Fields(2)=SkyVUE8_Window_transmission
Alias CSLine2_Fields(3)=SkyVUE8_First_Height
Alias CSLine2_Fields(4)=SkyVUE8_Second_Height
Alias CSLine2_Fields(5)=SkyVUE8_Third_Height
Alias CSLine2_Fields(6)=SkyVUE8_Fourth_Height
Alias CSLine2_Fields(7)=SkyVUE8_Alarm_Flags

'Define Data Tables

DataTable(Ceilometer,True,-1)
  DataInterval(0,15,sec,10)
  Sample (1,strSkyVUE8_Message_Status,String)
  Sample (1,strSkyVUE8_Alarm_Status,String)
  Sample (1,SkyVUE8_First_Height, ieee4)
  Sample (1,SkyVUE8_Second_Height, ieee4)
  Sample (1,SkyVUE8_Third_Height, ieee4)
  Sample (1,SkyVUE8_Fourth_Height, ieee4)
  Sample(1,SkyVUE8_Alarm_Flags,String)
EndTable

'Main Program
BeginProg
  ' open the port to the SkyVUE8 Ceilometer
  'Assumes default serial settings, if not change baud rate & maybe format
  (2nd & 3rd parameters)
  SerialOpen (Com1,115200,3,0,1000)
```

```

SkyVUE8_Unit_of_Measure="ft"

Scan(15,Sec,1,0)
SerialInRecord (Com1,strInSkyVUE8,SOH,0,EOT,Num_Bytes,01)
If Num_Bytes > 0 Then
  'Break up message on line feed separator
  SplitStr (SkyVUE8Lines,strInSkyVUE8,CHR(10),3,5)
  'Break up top line using space as separator
  SplitStr (CSLine2_Fields,SkyVUE8Lines(2)," ",7,5)
  'First character is msg status
  strSkyVUE8_Message_Status=Left (SkyVUE8_MessageAlarm_Status,1)
  'Last character is alarm status
  strSkyVUE8_Alarm_Status=Right (SkyVUE8_MessageAlarm_Status,1)
  If strSkyVUE8_Alarm_Status = "W" Then
    strAlarm = "Warning"
  ElseIf strSkyVUE8_Alarm_Status = "A" Then
    strAlarm = "Alarm"
  Else
    strAlarm = "OK"
  EndIf
  Select Case strSkyVUE8_Message_Status
  Case "0"
    strInformation = "No significant backscatter"
  Case "1"
    strInformation = "One cloud base detected"
  Case "2"
    strInformation = "Two cloud bases detected"
  Case "3"
    strInformation = "Three cloud bases detected"
  Case "4"
    strInformation = "Four cloud bases detected"
  Case "5"
    strInformation = "Full obscuration determined but no cloud base
detected"
  Case "6"
    strInformation = "Some obscuration detected but determined to be
transparent"
  Case "/"
    strInformation = "Raw data input to algorithm missing or suspect"
  Case Else
    strInformation = "Status of message unknown."
  EndSelect
  'Make sure message is complete & correct
  lngCRCCalc = CheckSum (Left(strInSkyVUE8,Num_Bytes-4),18,0) XOR &HFFFF
  lngCRCMessage = HexToDec (Mid(strInSkyVUE8,59,4))
  DataOK = (Num_Bytes = 62) AND (lngCRCCalc = lngCRCMessage)
  If NOT DataOK Then
    strError = "Data error, messages may be incomplete!"
  Else
    strError = ""
  EndIf
Else
  strError = "COMMS ERROR - No Message received"
EndIf
  CallTable(Ceilometer)
NextScan
EndProg

```


Appendix B. Measurement of the attenuated backscatter profile

B.1 Initial measurement

- Pulse the laser and measure the backscatter at optimal gains.
- Derive the impulse response and impulse correct the backscatter signal using the inverse filter derived.
- Remove the residual offset and slope from the impulse corrected backscatter.
- Apply an overlap correction based on the known generic overlap function of the SkyVUE™8.
- Apply the backscatter calibration constants.
- Remove the laser and electronic artefact signature. This is specific to the individual SkyVUE™8 and determined during calibration.

B.2 Backscatter onset height detection

- Filter the backscatter with 20 m (65.6 ft) and 300 m (984 ft) width filters.
- Look for a 1500 m (4921 ft) block width where the standard deviation is at a minimum for both the 20 m (65.6 ft) and 300 m (984 ft) width filtered backscatters.
- Create a detection threshold by multiplying the 20 m (65.6 ft) and 300 m (984 ft) standard deviations by a constant.
- Find the onset of backscatter height by working from the highest height bin downwards until the backscatter is above one or both of the two detection thresholds.

B.3 Produce attenuated backscatter output message

- Range correct the backscatter to produce the attenuated backscatter.
- Attenuated backscatter (output), calibrated, range corrected but not tilt corrected.
- Smooth with a 20 m (65.6 ft) width running average.
- A noise gate can be applied based on a multiple of the 20 m (65.6 ft) detection threshold – this is customer configurable.

- Note the lower height range bins do not gate noise until the backscatter reaches zero. This allows the full extent of mixing layers to be viewed in gating mode.

Appendix C. Cloud height calculation

The scatter profile is inverted (using the Klett inversion technique) and an extinction profile is calculated.

Cloud base heights are identified using two criteria as follows (cloud is detected if either of them is met).

Criterion 1: likely cloud bases are estimated based on increasing slope of the extinction profile of at least 7 m (22.9 ft) per bin (bin width is 5 m (16.4 ft) and an extinction threshold. This threshold is based on an extinction coefficient (EXCO) of 3, equivalent to a horizontal visibility (MOR) of 1000 m (3280 ft). This results in a number of possible cloud bases at different heights.

Criterion 2: horizontal visibility falls below an average of 4800 m (15,748 ft) over 300 m (984 ft) starting at an altitude of 1000 m (3280 ft).

To report a cloud layer above a lower one the scatter coefficient first has to fall below the extinction threshold used for cloud definitions (less a small hysteresis offset). The scatter profile must then again meet the criteria above.

If rain is detected the sensitivity of detection is increased by a factor of 3.

To avoid many very narrow close layers being reported when they have little significance a minimum separation based on WMO reporting intervals is applied. The separation is +/- 30 m (98 ft) below 1500 m (4921 ft) and 300 m (984 ft) above 1500 m (4921 ft). The lowest cloud height is used. If a thin cloud identified by Criterion 2 above is within +/-150 m (492 ft) of a cloud identified by criterion 1 then the thin cloud is ignored.

Appendix D. Sky condition algorithm description

The SkyVUE™8 sky condition algorithm follows guidance from ICAO and WMO documents* and is based on 30 minutes of data. For this reason sky condition is not available for 30 minutes after power cycling the sensor, a reboot or changing measurement parameters. The sky condition algorithm is as follows:

Each measured hit comprising the lowest cloud height, (vertical visibility + onset of backscatter) / 2 and a weighting of 1 or 2 is stored in a running half hour buffer.

The weighting is 2 for hits in the last 10 minutes and 1 for hits in the previous 20 minutes.

If >50% of the hits in the latest 10 minutes are vertical visibility then the vertical visibility averaged over the last 10 minutes is reported. Only hits below the vertical visibility height limit set are used.

The buffer is sorted in height order and hits combined into bins with the following widths:

Height	Bin width
0 - 5000 ft (0 - 1524 m)	100 ft (30.5 m)
5000 – 15,000 ft (1524 – 4572 m)	200 ft (61 m)
15,000 – 26,250 ft (4572 – 8000 m)	500 ft (152 m)

For each bin a mean height is calculated by the following:

$$H_i = \sum(h_i w_i) / \sum(w_i)$$

Where w_i is the weight (1 or 2) of the hit with height h_i

Bins are then reduced. A distance (D) between adjacent bins is calculated by the following equation:

$$D = N_i N_j (H_i - H_j)^2 / (N_i + N_j)$$

Where N_i and N_j are the sum of hits of each bin and H_i and H_j the respective heights.

Find the pair with the minimum distance D and combine into one bin with the height of the lowest and number of hits of the combined total.

*ICAO 9837 Manual on Automatic Meteorological Observing Systems at Aerodromes.
WMO – No. 306 Manual on Codes

This process is repeated until 5 or less bins remain. These are now taken as cloud layers.

Finally if cloud layers are closer than the distances below then they are merged with the height of the lowest and combined total number of hits.

Height range	Distance (D)
Height \leq 300 m (1000 ft)	\leq 90 m (300 ft)
300 m < Height \leq 900 m (1000 ft < Height \leq 3000 ft)	\leq 120 m (400 ft)
900 m < Height \leq 1500 m (3000 ft < Height \leq 5000 ft)	\leq 180 m (600 ft)
1500 m < Height \leq 2400 m (5000 ft < Height \leq 8000 ft)	\leq 300 m (1000 ft)
Height > 2400 m (8000 ft)	\leq 480 m (1600 ft)

Weights per layer are used to calculate number of oktas per layer.

If the total possible is W_{max} then the cover is $(W_i/W_{max}) \times 8$.

Cloud amounts are rounded up to the next highest whole oktas.

For layers above the lowest this is based on the maximum possible weights. If the lower layers have W_1 hits and the next layer has W_2 hits then the cover of the higher layer is given by:

$$(W_2/(W_{max}-W_1)) \times 8$$

For example, taking weighting into account, if lower layers of cloud only allow 4/8 of clear sky above and the cover is 2/8 out of those 4/8 then the layer above is taken as 4/8.

Finally, only layers meeting the following criteria are reported:

Layer 1 \geq 1/33 oktas

Layer 2 \geq 3 oktas

Layer 3 \geq 5 oktas

Layer 4 \geq 7 oktas

Layer 5 \geq 7 oktas

Any layer > $(8 - 1/33)$ oktas is reported as 8 oktas

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