

ACOUSTIC TELEMETRY FROM FISH

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ABSTRACT

Methods are described for monitoring physiological parameters such as temperature and electrocardiogram from free swimming fish. Information is telemetered as sound radiating from an acoustic transmitter implanted on the fish. Limitations of the technique and construction details of representative devices are covered. Uses in both behavior and physiology are considered.

Acoustic telemetry allows an investigator to study the behavior and physiology of fish under conditions which approximate their natural state. Improvements in electronic techniques permit construction of devices the size of one's little finger; these devices can transmit data such as heartbeat and temperature over ranges of several hundred meters for as long as a month. We describe here the use and constraints on sound as a means of transmitting these data. We then discuss, in detail sufficient for duplication, the construction of sample devices for transmitting, receiving, and interpreting the data. Finally, we show how these devices have been applied to specific experimental problems, and discuss the results we have obtained.

SOUND AS A TELEMETRY MEDIUM

For ranges beyond a few meters through water, sound is the only practical form of energy for telemetry. It travels with little loss, whereas radio waves and light are rapidly absorbed. Several properties of sound in water are important. For example greater ranges are possible in fresh water than salt (one rarely has a choice in this). Low frequencies transmit further than high. For ranges up to several hundred meters, any frequency below 100 kHz is suitable. If a range of several kilometers is needed, the frequency should be less than 20 kHz. Low frequencies, however, involve longer wave lengths which implies larger transducers. In the small devices

necessary for fish work these are difficult to use. Thus we most frequently employ frequencies between 40 and 80 kHz. Only in large tuna could we use a transmitter big enough to work efficiently at 20 kHz. It had an open sea range of 8 km.

The interfering background noise, which tends to obscure the signal, varies greatly at different places. In general, the shallow water tropics are noisiest. At Coconut Island in Hawaii the natural acoustic energy may be 100 times greater than that at Friday Harbor in Puget Sound. Most of the noise appears to be from bottom animals such as snapping shrimp. Man-made noise, like that from boat motors, can also be troublesome.

Relative motion between a sound source and the receiver produces a Doppler shift in the apparent frequency such that

$$\frac{\Delta f}{f} = \frac{\text{relative velocity}}{\text{velocity of sound in water}}$$

The velocity of sound in water is 1,500 m/s. A relative velocity of 1 knot shifts frequency 0.03%. This is only significant when frequency is interpreted critically, as in the depth transmitter to be described.

Additional complications arise from the interference effects due to multiple sound paths between transmitter and receiver. These are frequently troublesome in small enclosures where sound reflects from the walls. Nulls in the sound field are produced which represent momentary loss of signal. The ear has little trouble interpreting periodic signals such as electrocardiogram (EKG), but in a transcribed record these effects can be confusing (see Figure 2).

These remarks are meant to make one's ambitions more modest when considering acoustic

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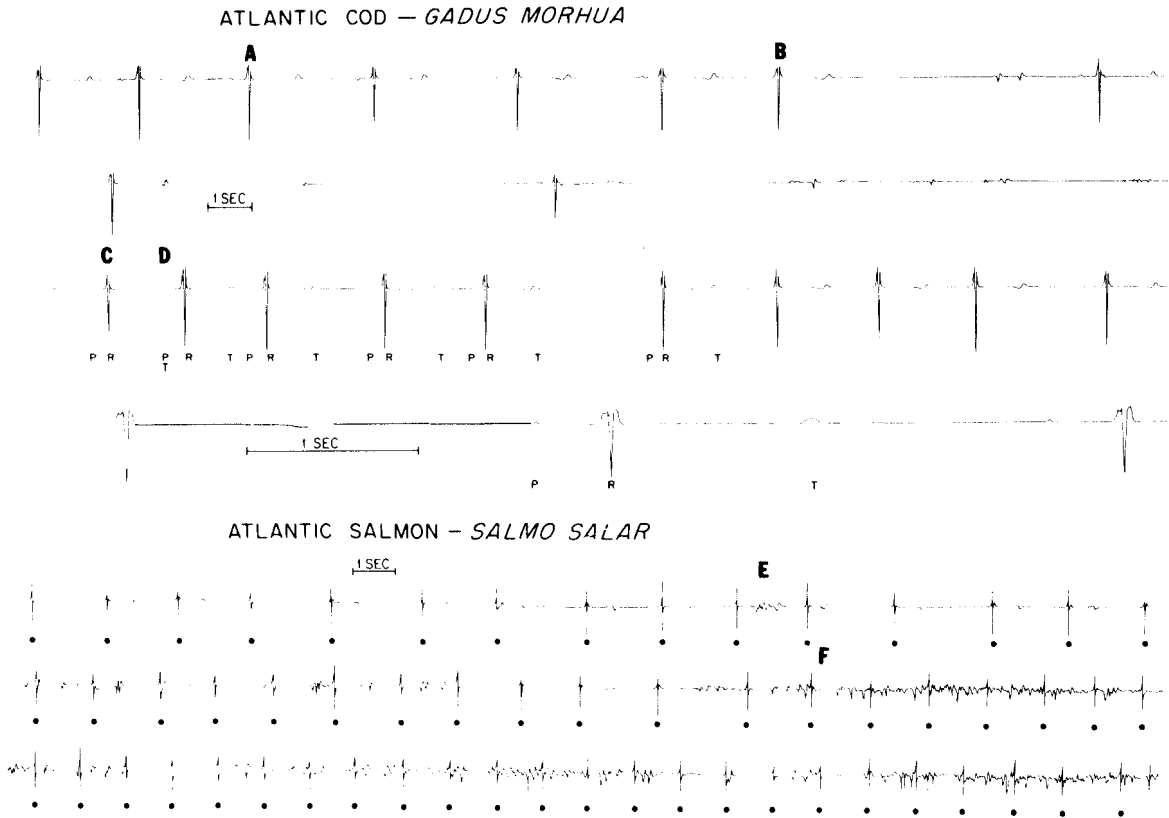


FIGURE 2.—Examples of electrocardiogram from free swimming Atlantic cod and Atlantic salmon. The experimenter approached the aquarium at A and looked over at B, slowing the heart rate. When he went away the heart started at the maximum rate at C, since the T wave is piled on the next P wave at D. The Atlantic salmon also showed a slowing at E from the same source. It was chased at F, resulting in a quickly accelerating heart rate from exercise. Noise while swimming is an acoustic artifact from reflections in the tank.

ment has an operating life of 1 wk. We are using it to study gas pressure in swim bladders. With a less sensitive sensor we can determine pressures at depths equal to 1,000 m.

Receiver

Much of our work has been done with tunable superheterodyne receivers. These employ a mechanical filter to set bandpass. Nearly equivalent results can be had from the simpler circuit of Figure 5. The hydrophone contains a frequency selective preamplifier with a voltage gain of 100. Amplification within the hydrophone is important to eliminate interference from motor ignition and radio stations. Power for this preamplifier comes down the same wire that carries signals to the receiver.

The preamplified signal is amplified another 100 times in A_1 ($\frac{1}{2}$ of a 1437 dual operational

amplifier). Its output is mixed with a local oscillator in Q_3 to produce a signal at the audio difference frequency. This is amplified 10 times in A_2 and used to drive headphones. A 1- μ v signal at the receiving hydrophone is clearly audible.

RESULTS

General

We originally developed our telemetry so it could be used with ease for human cardiac monitoring. Work with fish only required miniaturization. The usual method is to have the receiver output played through a speaker in the laboratory. This allows one to notice occasional events of interest. Such more or less casual monitoring has greatly reduced the need for observational patience. In this way we have obtained cues related to feeding and behavioral in-

