

Water level, flow velocity BT2, RPM motor
 $\Delta x = 23.1$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 3.8$ m/s

Measurement
signals

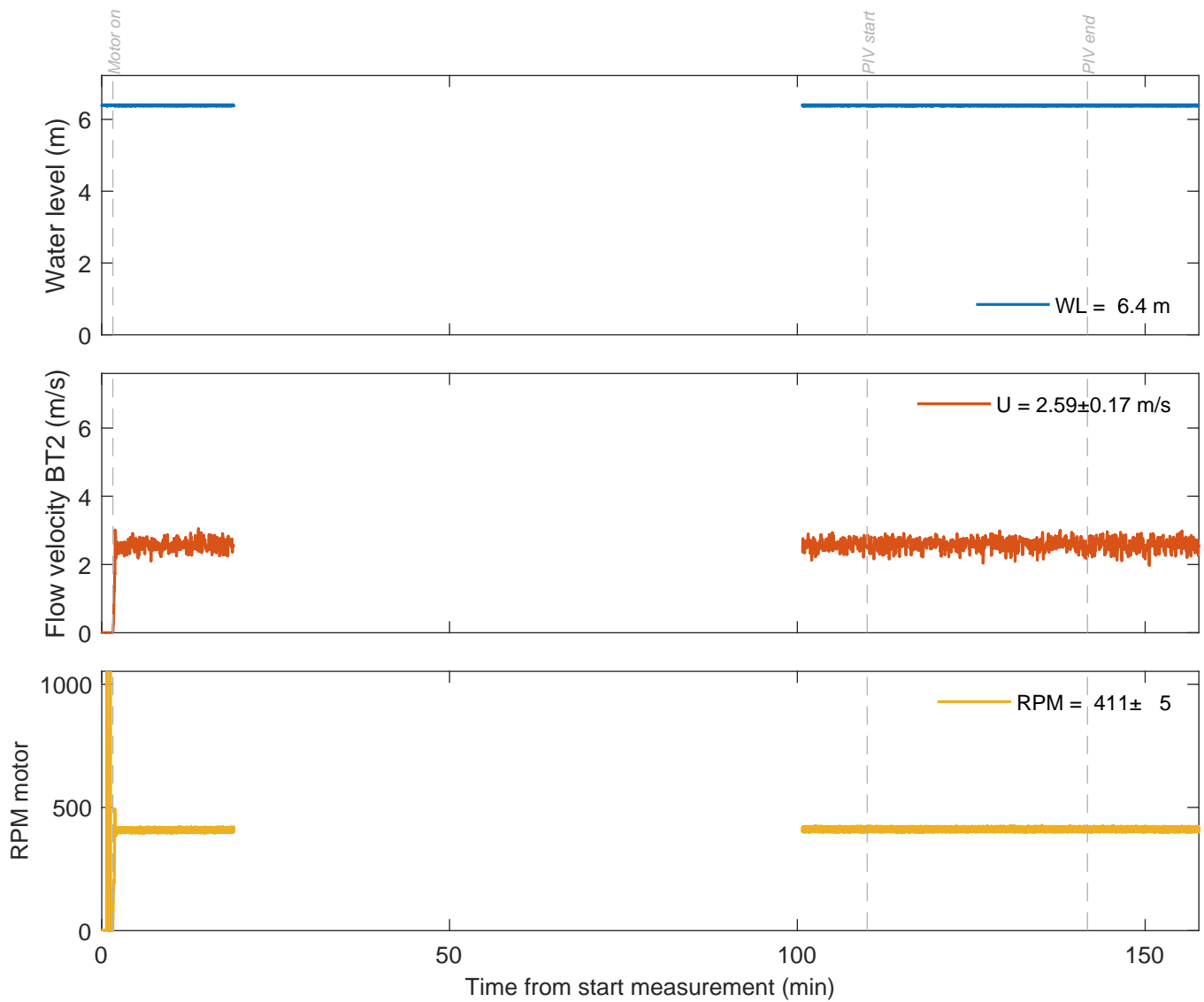
TKI-SOP

PIVSOP002

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 23.1 \text{ m}$, $\Delta y = 0.0 \text{ m}$, $UKC = 2.4$, $U_{BT2} = 2.6 \text{ m/s}$

Measurement
signals

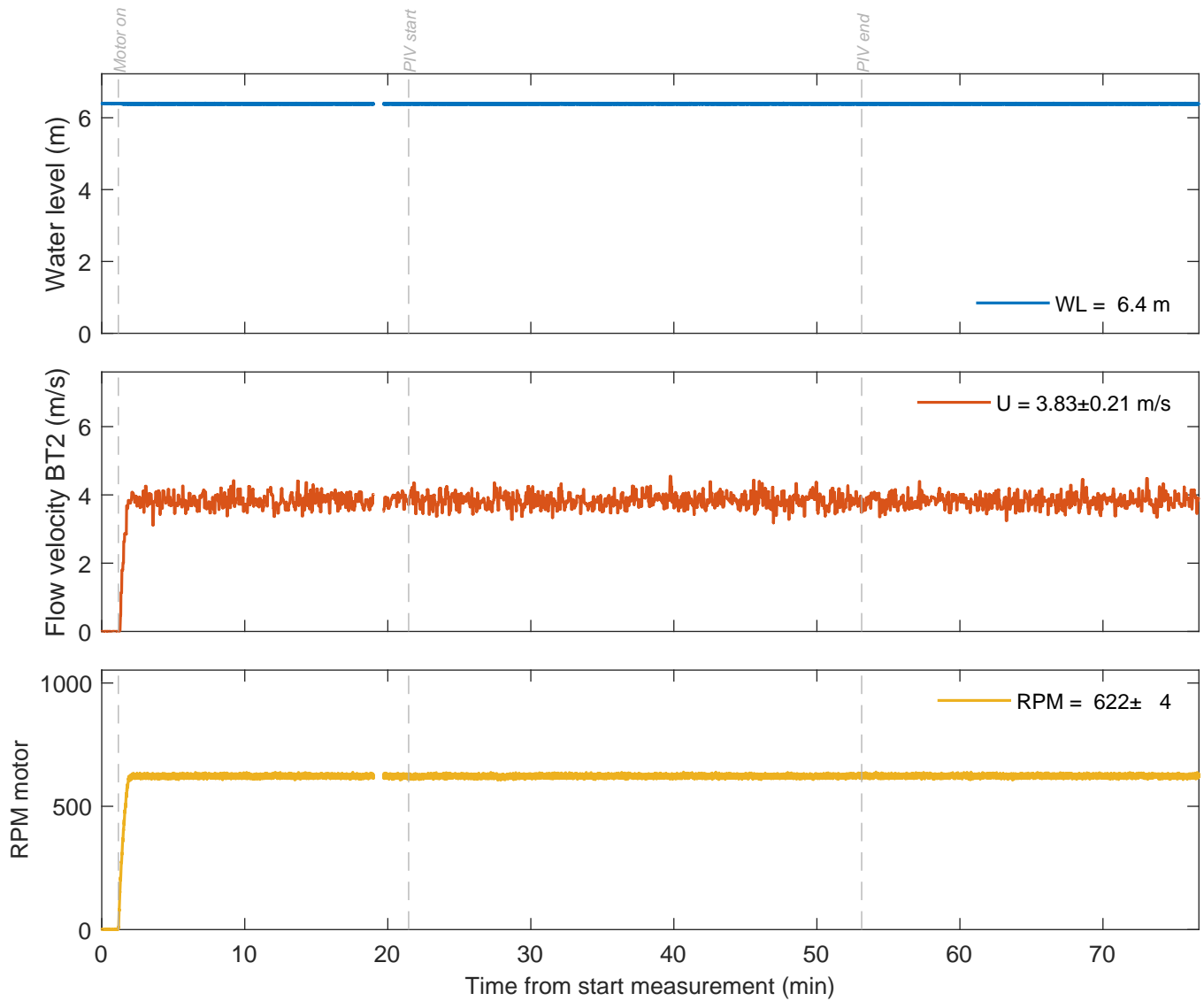
TKI-SOP

PIVSOP008

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 23.1 \text{ m}$, $\Delta y = 0.0 \text{ m}$, $UKC = 2.4 \text{ m}$, $U_{BT2} = 3.8 \text{ m/s}$

Measurement
signals

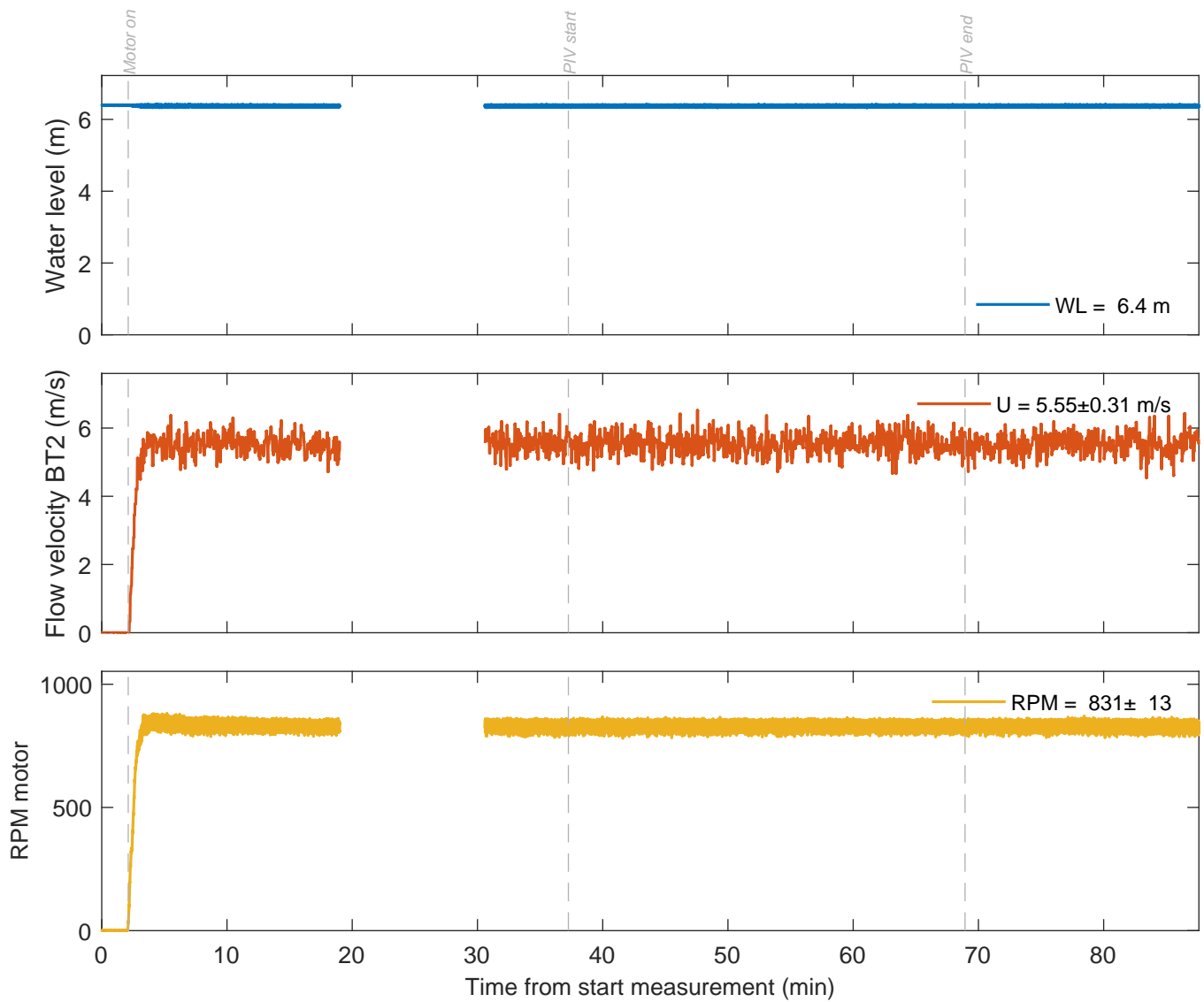
TKI-SOP

PIVSOP011

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 23.1$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 5.6$ m/s

Measurement
signals

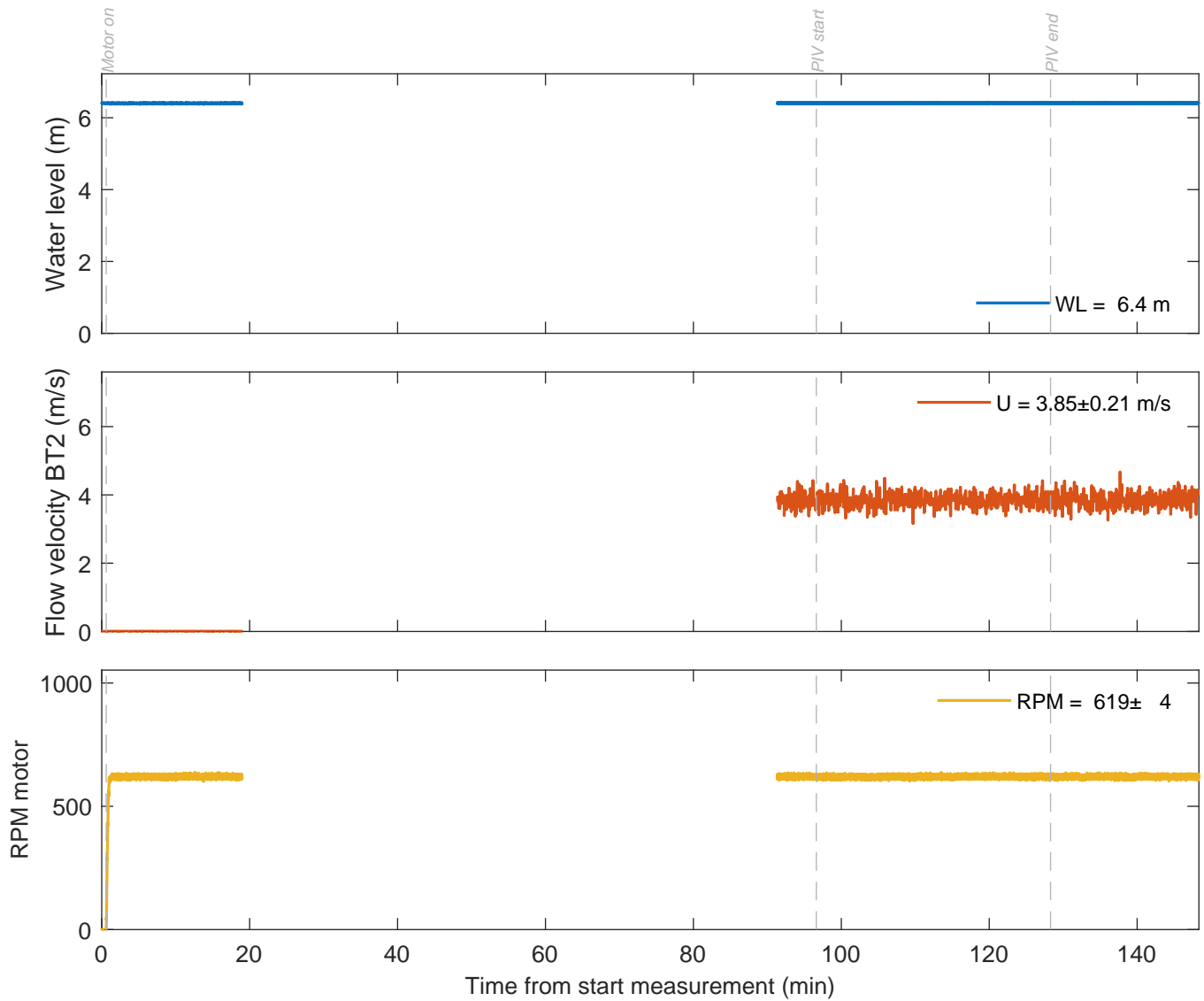
TKI-SOP

PIVSOP014

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 23.1$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 3.9$ m/s

Measurement
signals

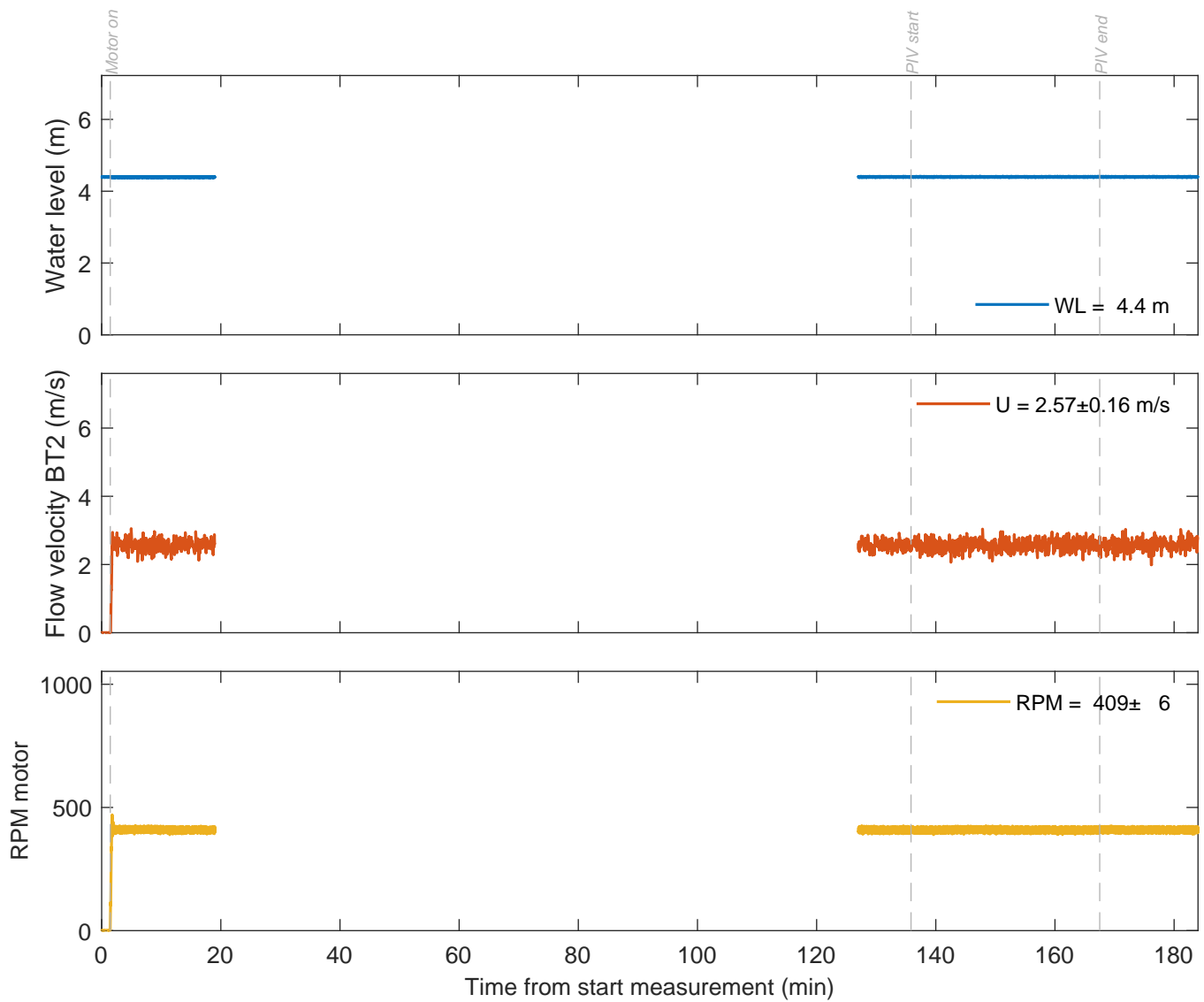
TKI-SOP

PIVSOP017

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 23.1$ m, $\Delta y = 0.0$ m, UKC = 0.5 m, $U_{BT2} = 2.6$ m/s

Measurement
signals

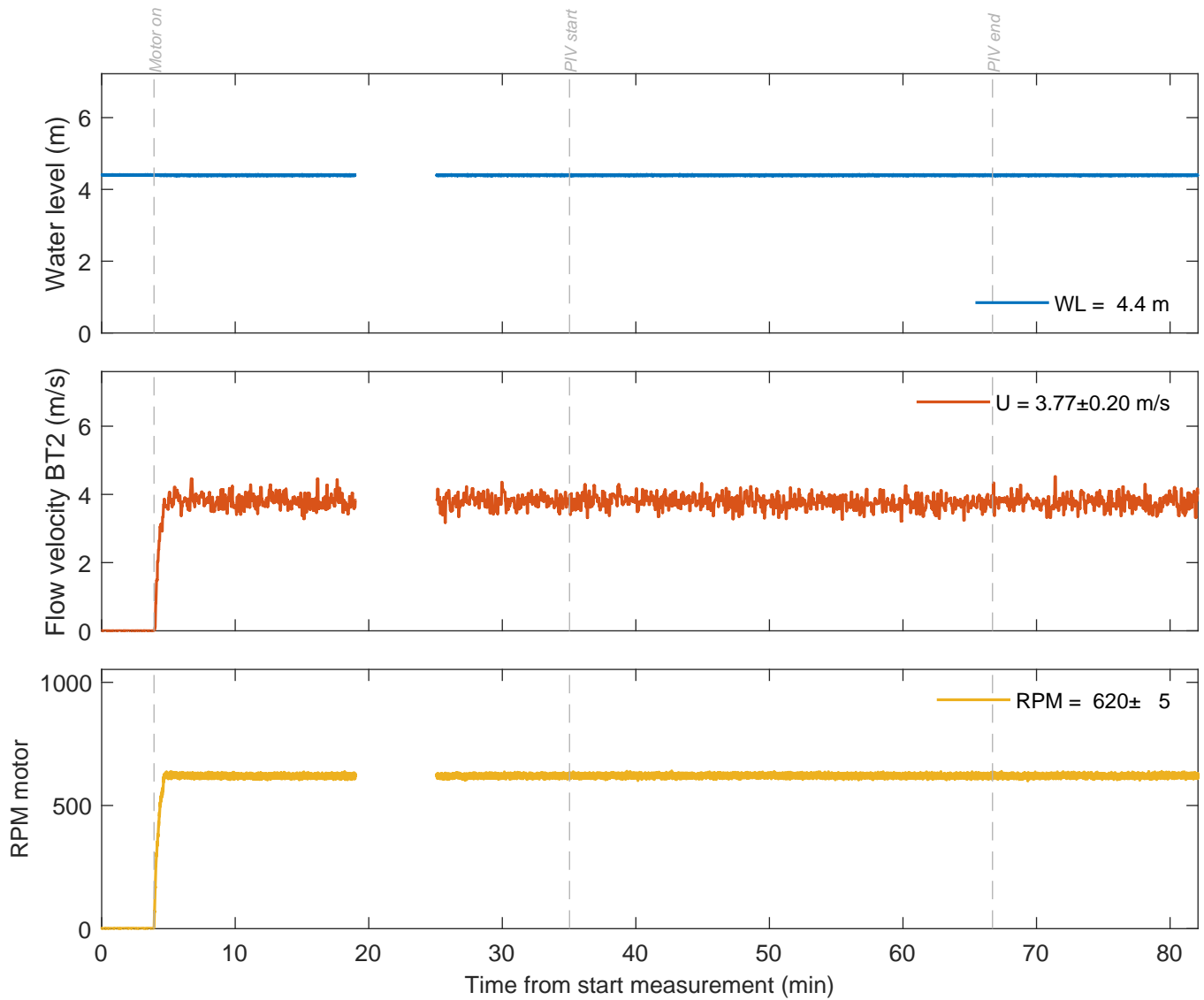
TKI-SOP

PIVSOP020

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 23.1 \text{ m}$, $\Delta y = 0.0 \text{ m}$, $UKC = 0.5 \text{ m}$, $U_{BT2} = 3.8 \text{ m/s}$

Measurement
signals

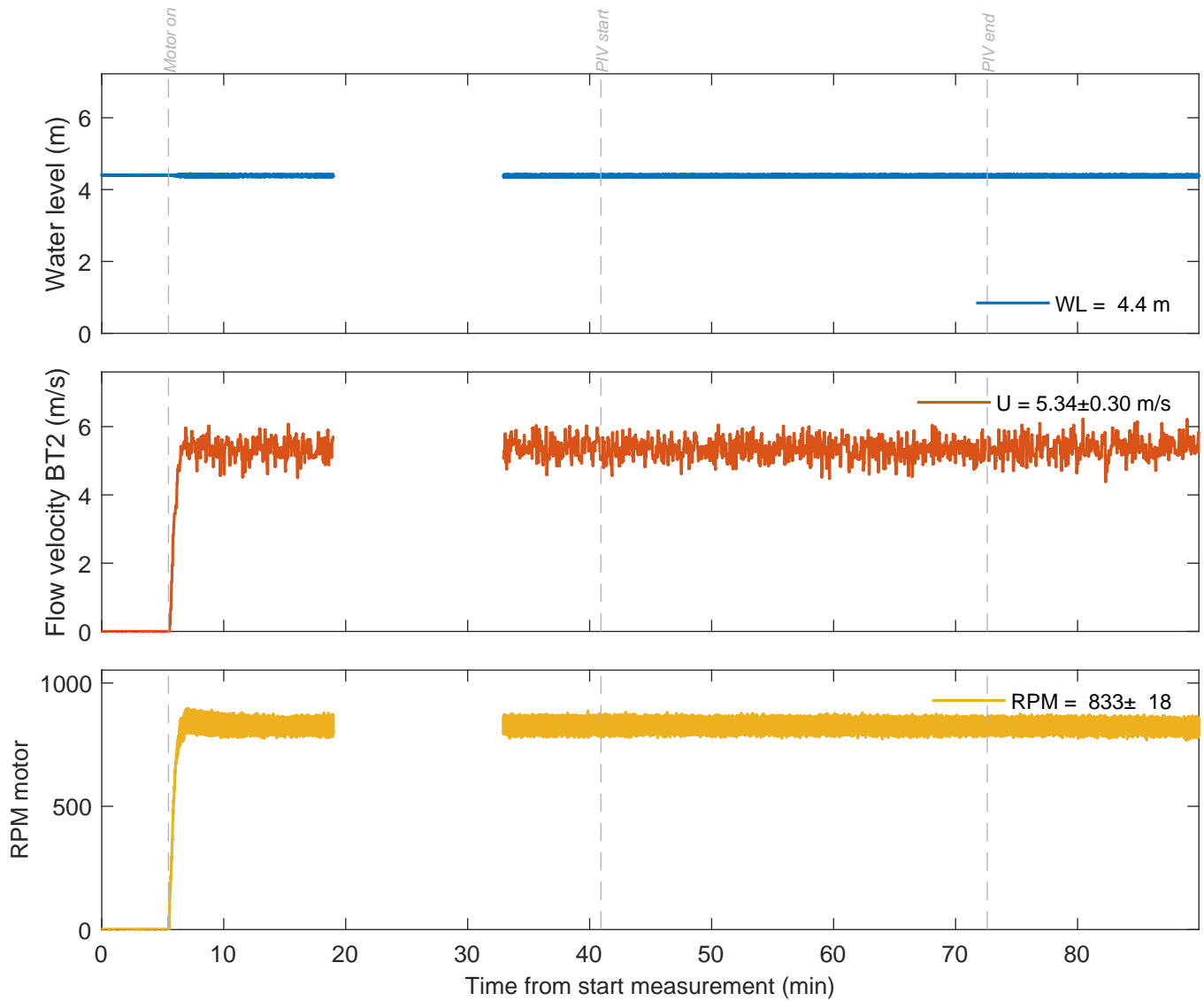
TKI-SOP

PIVSOP023

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 23.1$ m, $\Delta y = 0.0$ m, UKC = 0.5 m, $U_{\text{BT2}} = 5.3$ m/s

Measurement
signals

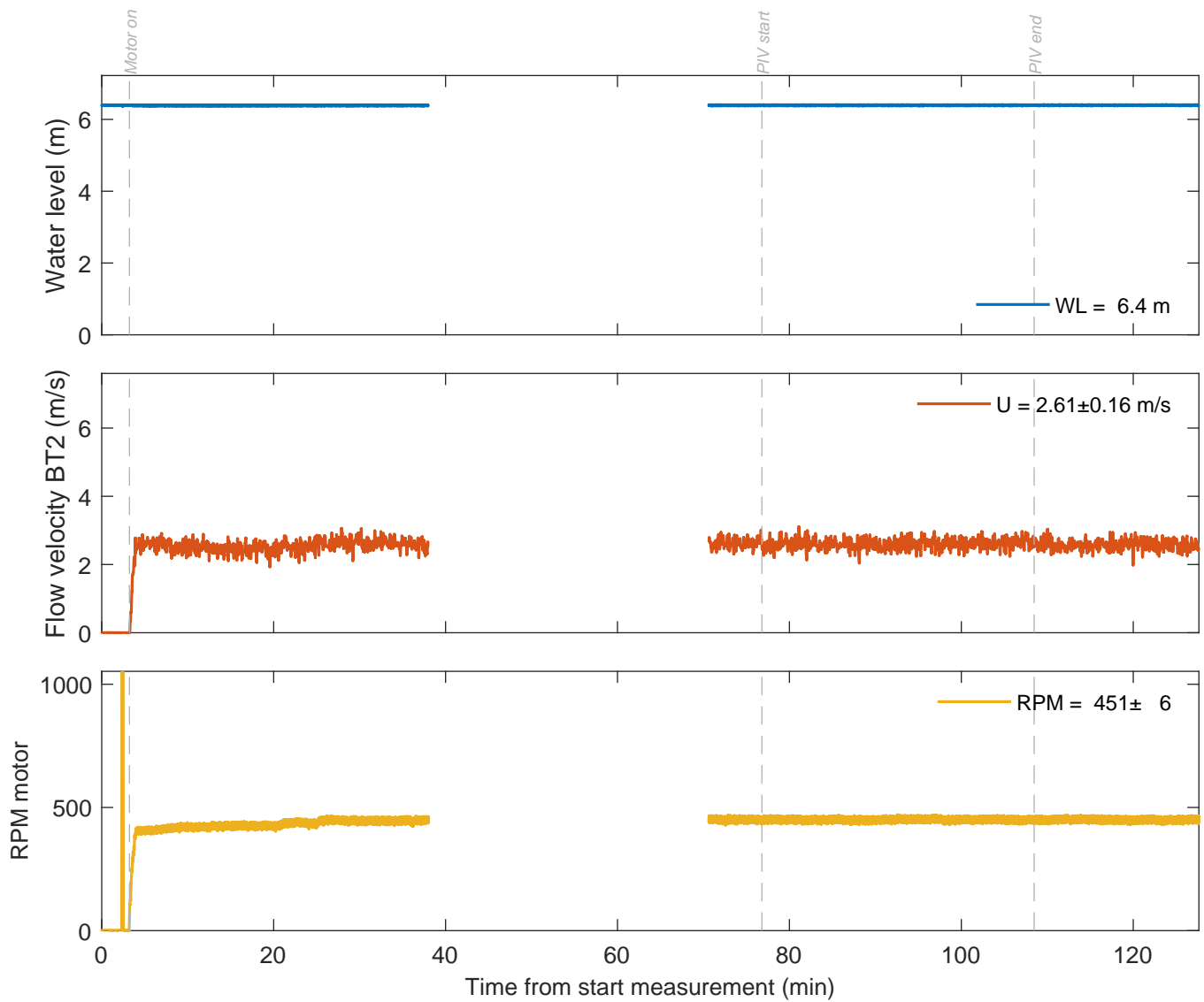
TKI-SOP

PIVSOP026

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 2.6$ m/s

Measurement
signals

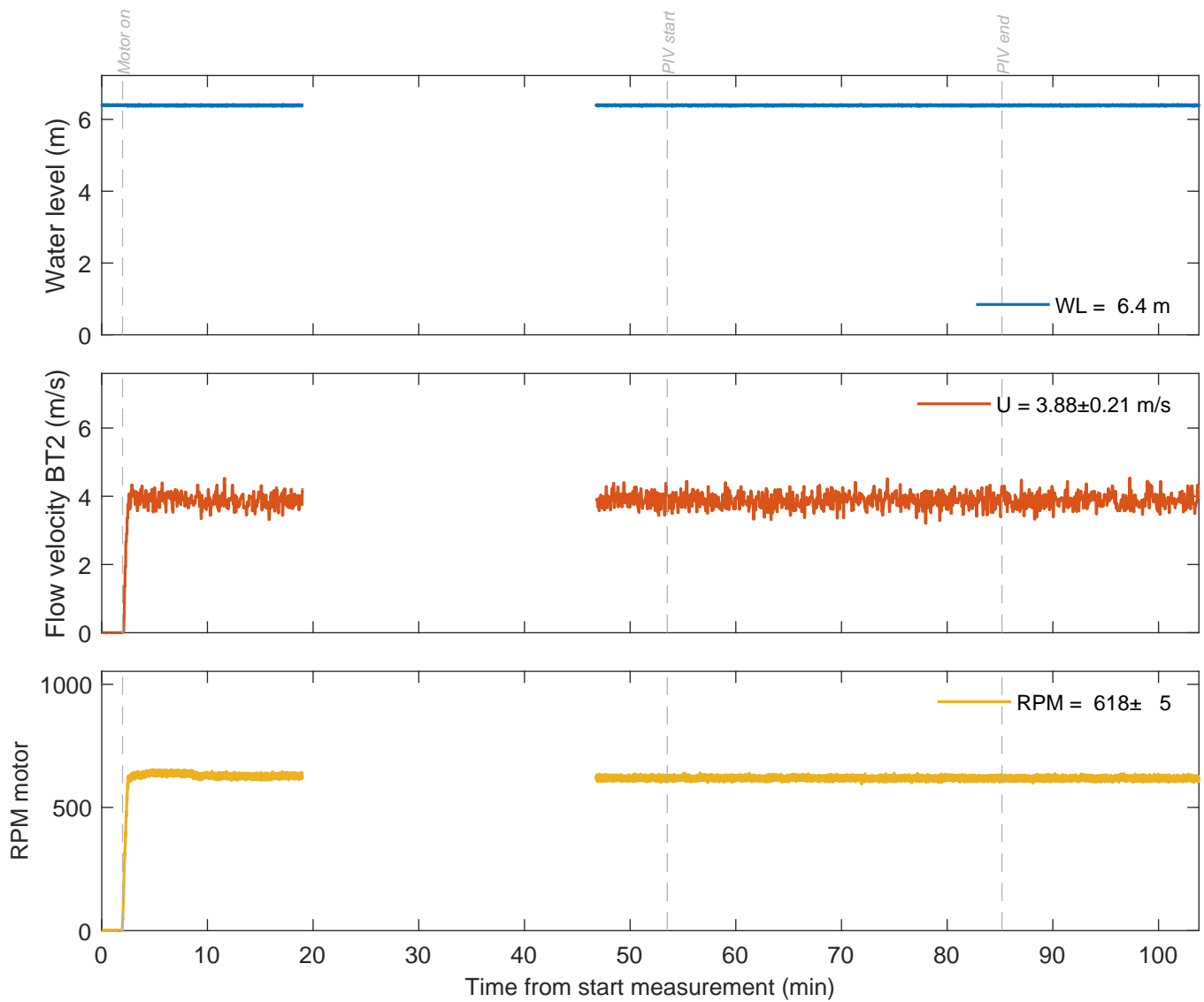
TKI-SOP

PIVSOP029

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8 \text{ m}$, $\Delta y = 0.0 \text{ m}$, UKC = 2.4 m, $U_{BT2} = 3.9 \text{ m/s}$

Measurement
signals

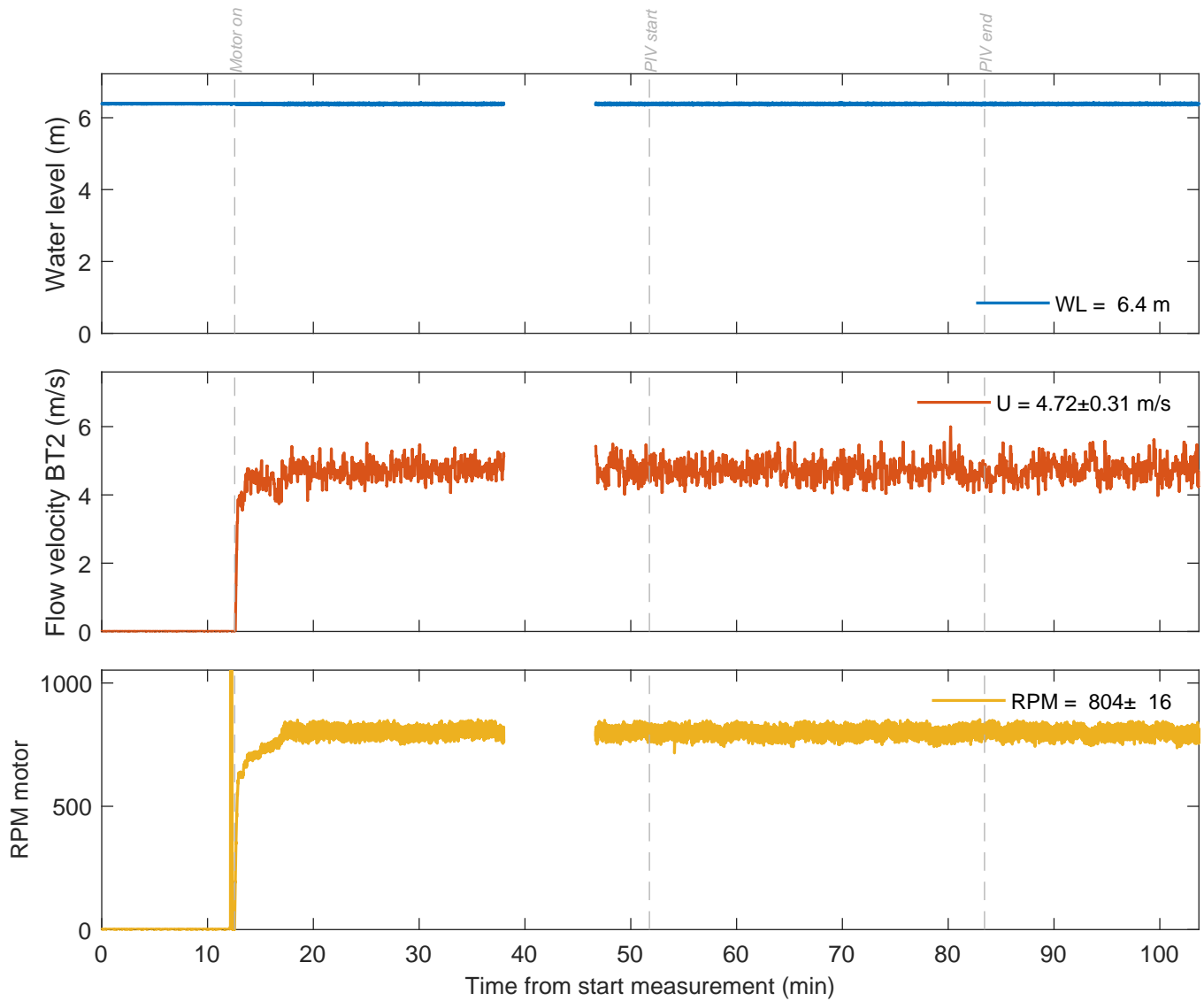
TKI-SOP

PIVSOP032

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8 \text{ m}$, $\Delta y = 0.0 \text{ m}$, UKC = 2.4 m, $U_{BT2} = 4.7 \text{ m/s}$

Measurement
signals

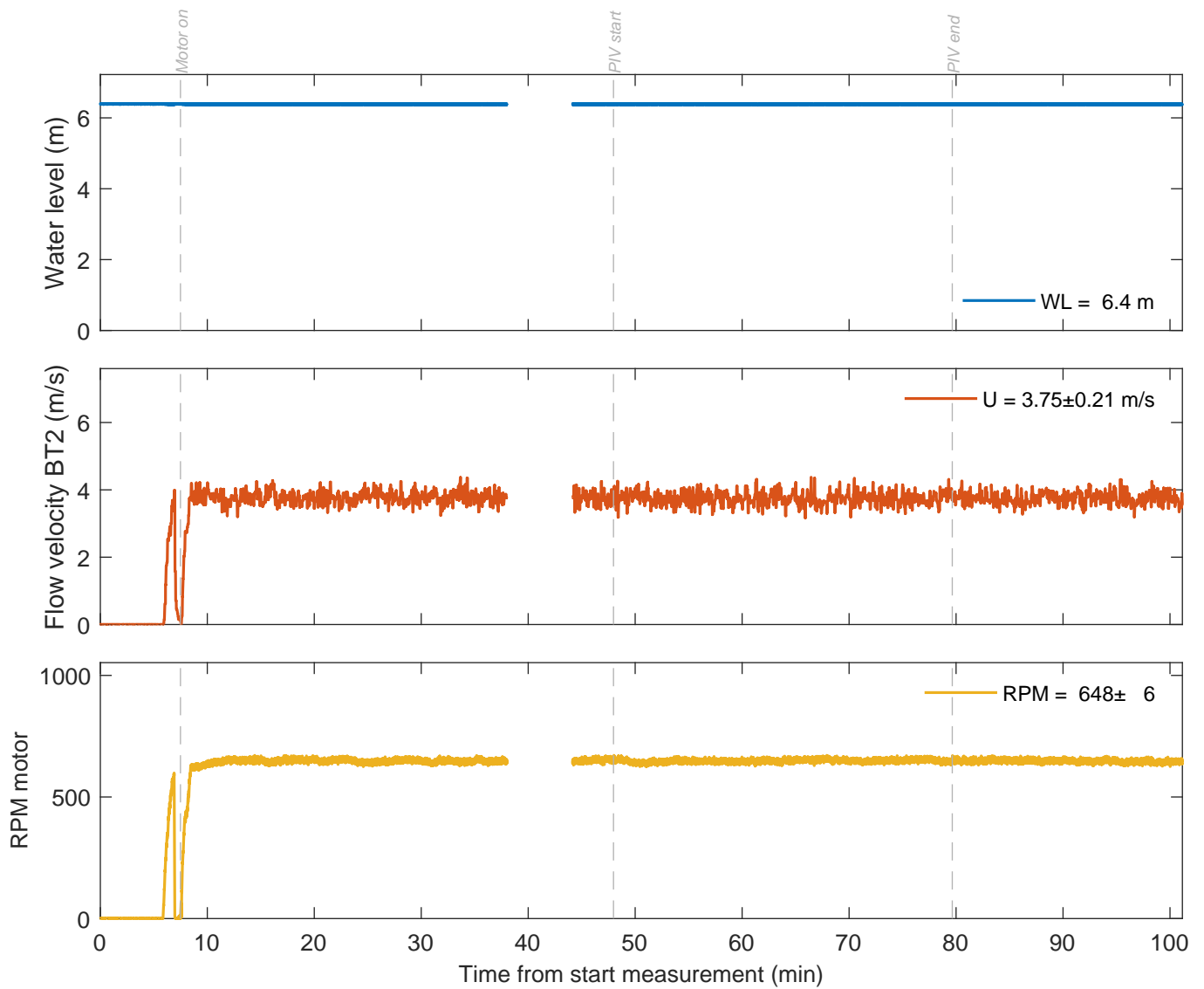
TKI-SOP

PIVSOP037

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 3.7$ m/s

Measurement
signals

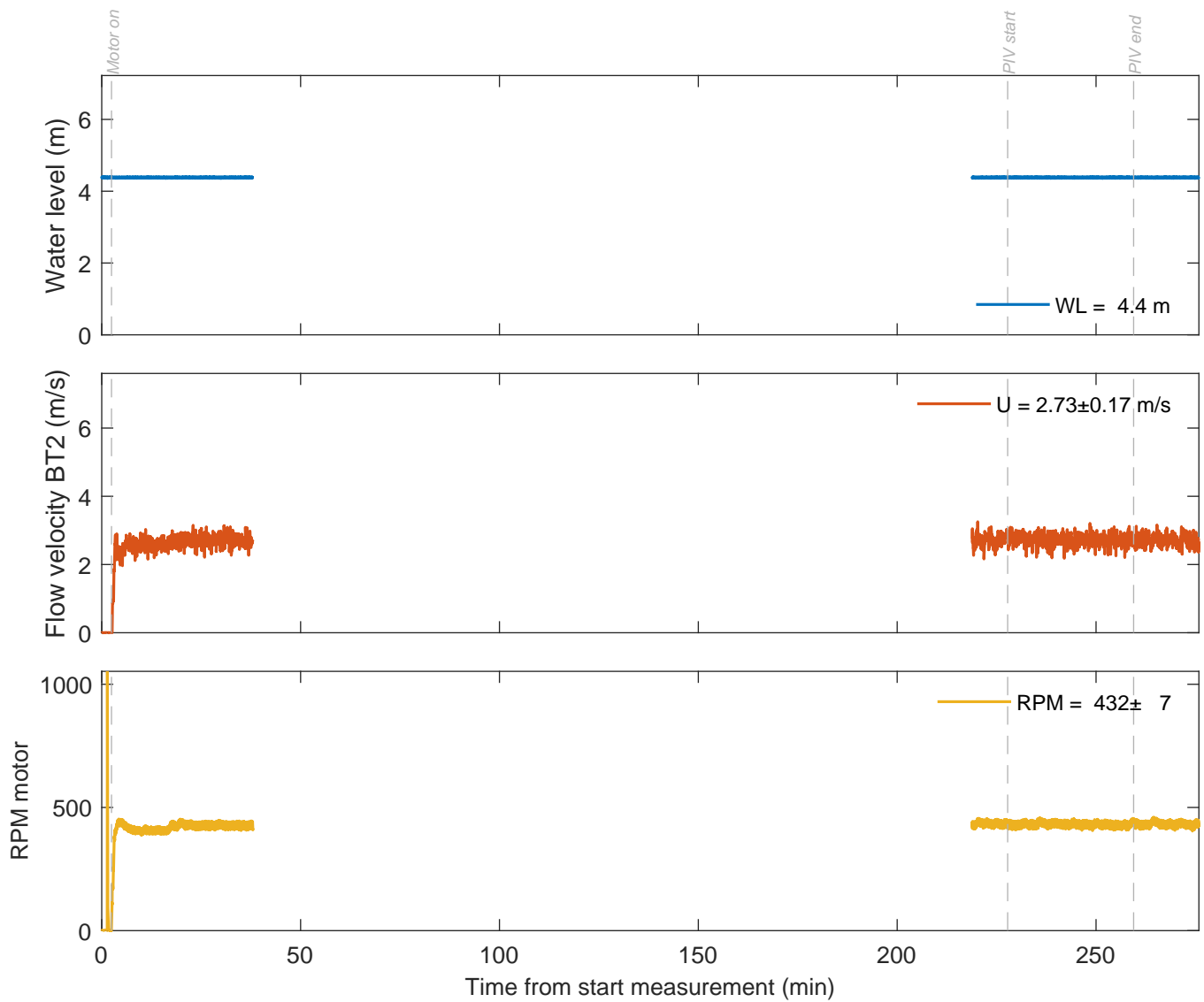
TKI-SOP

PIVSOP040

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 0.4 m, $U_{BT2} = 2.7$ m/s

Measurement
signals

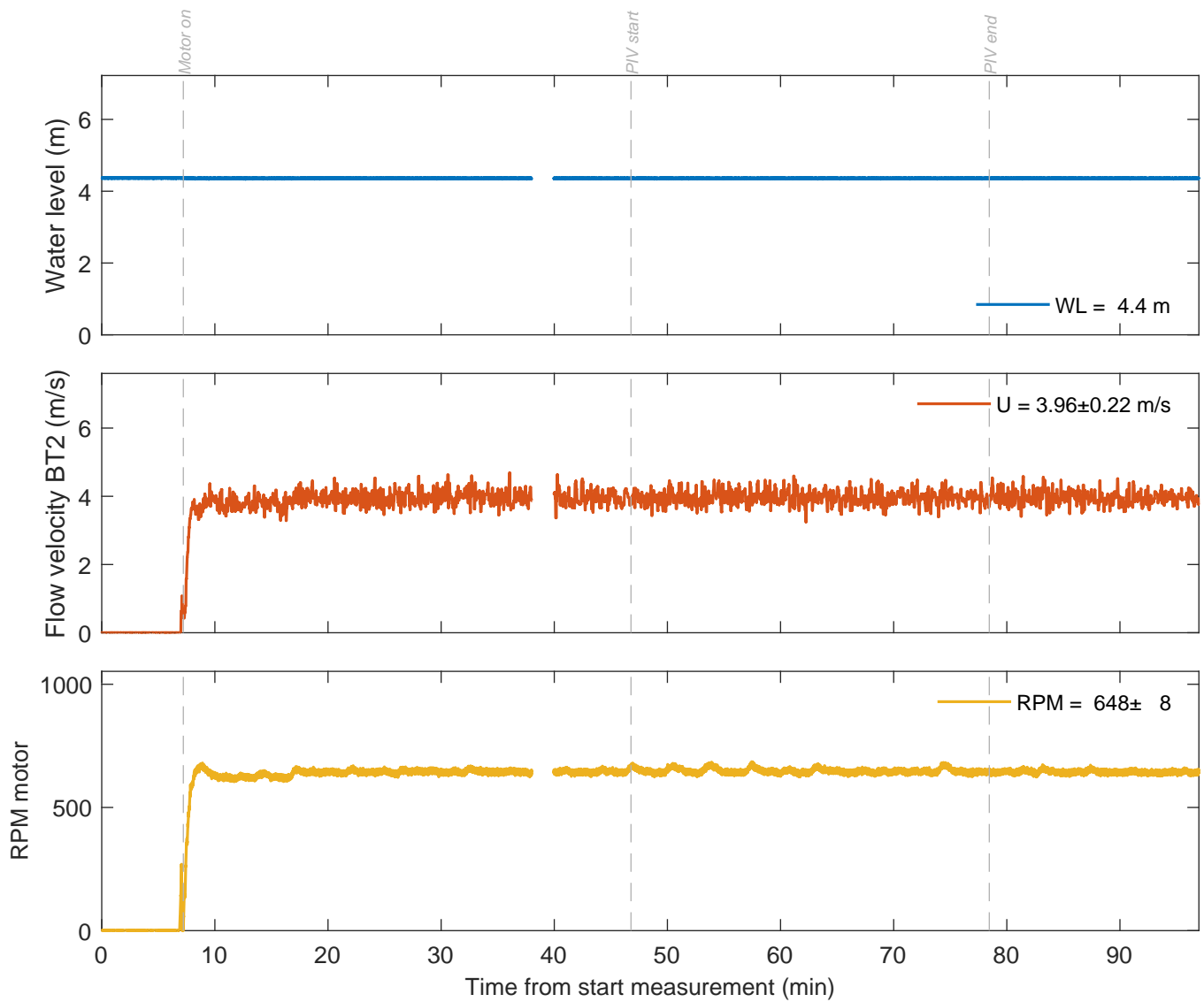
TKI-SOP

PIVSOP043

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 0.4 m, $U_{BT2} = 4.0$ m/s

Measurement
signals

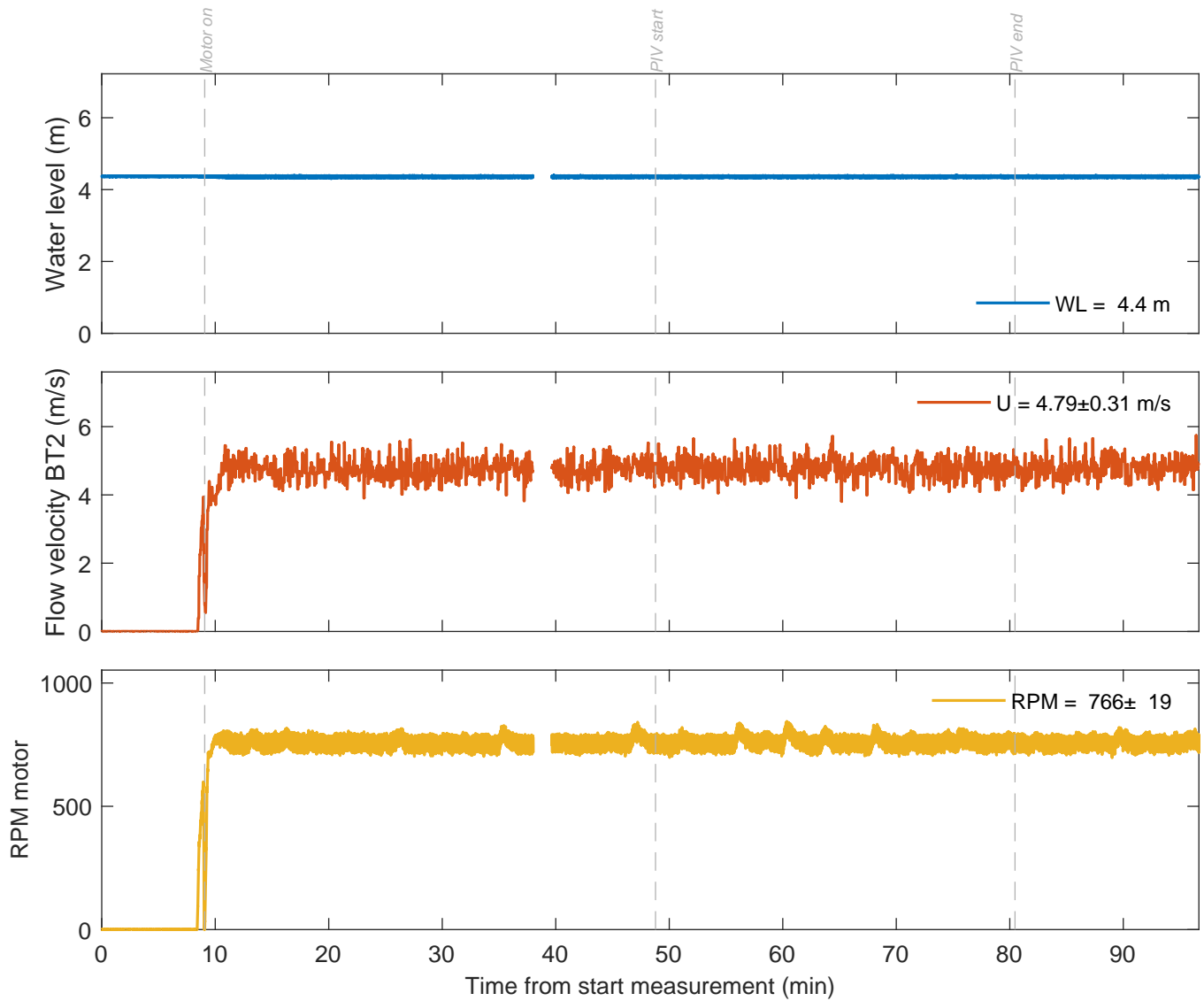
TKI-SOP

PIVSOP047

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 0.4 m, $U_{\text{BT2}} = 4.8$ m/s

Measurement
signals

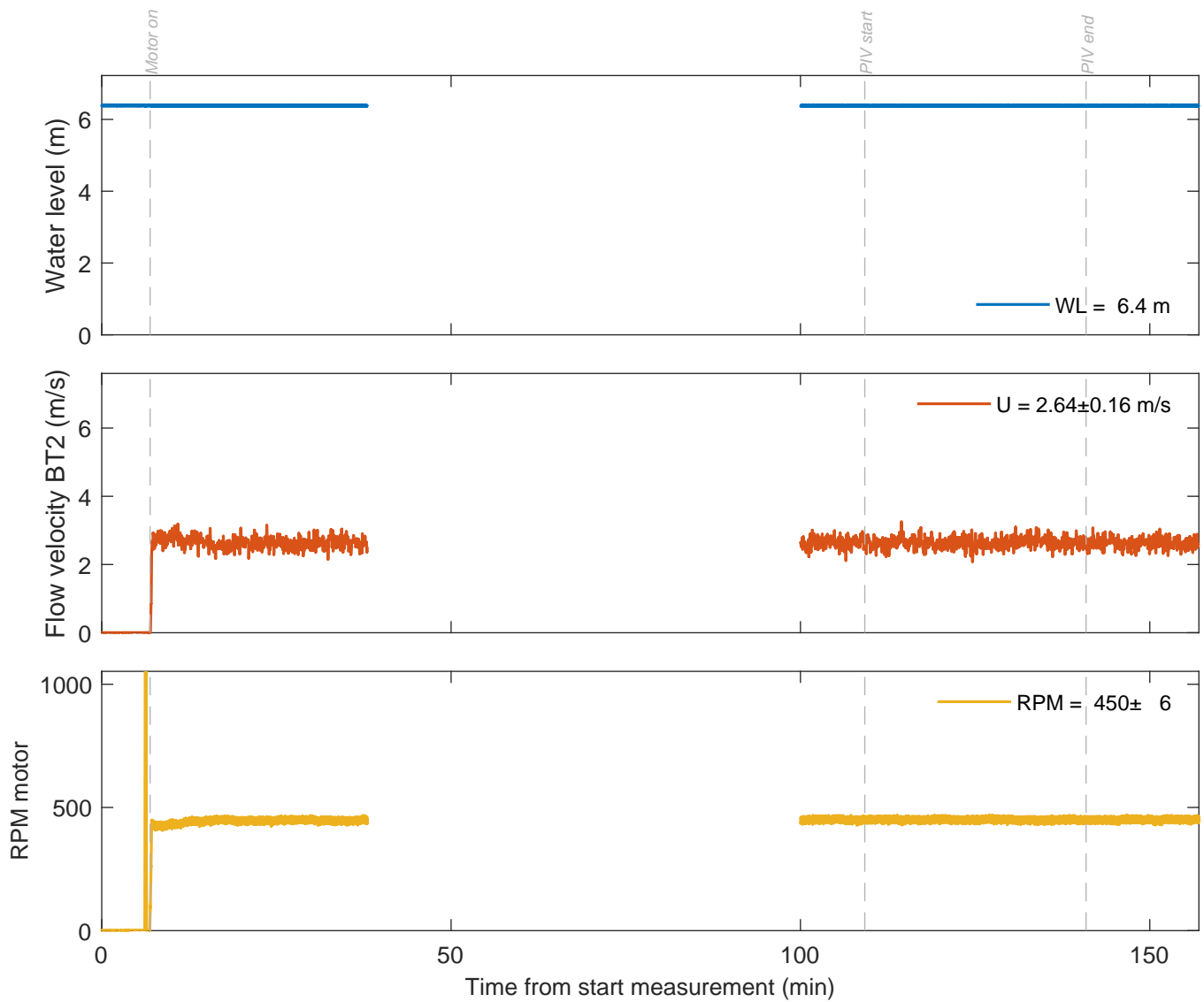
TKI-SOP

PIVSOP049

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 2.6$ m/s

Measurement
signals

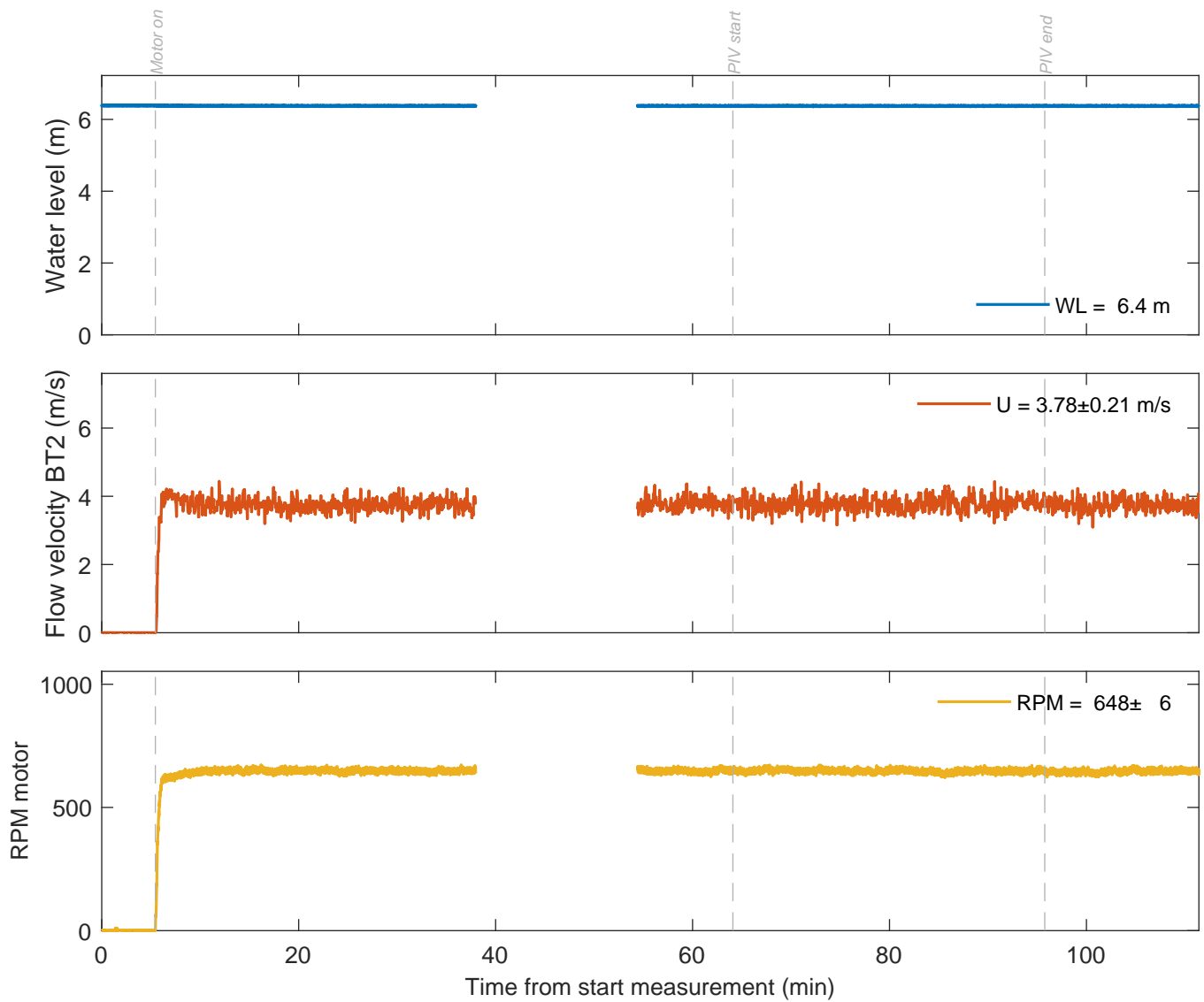
TKI-SOP

PIVSOP052

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 3.8$ m/s

Measurement
signals

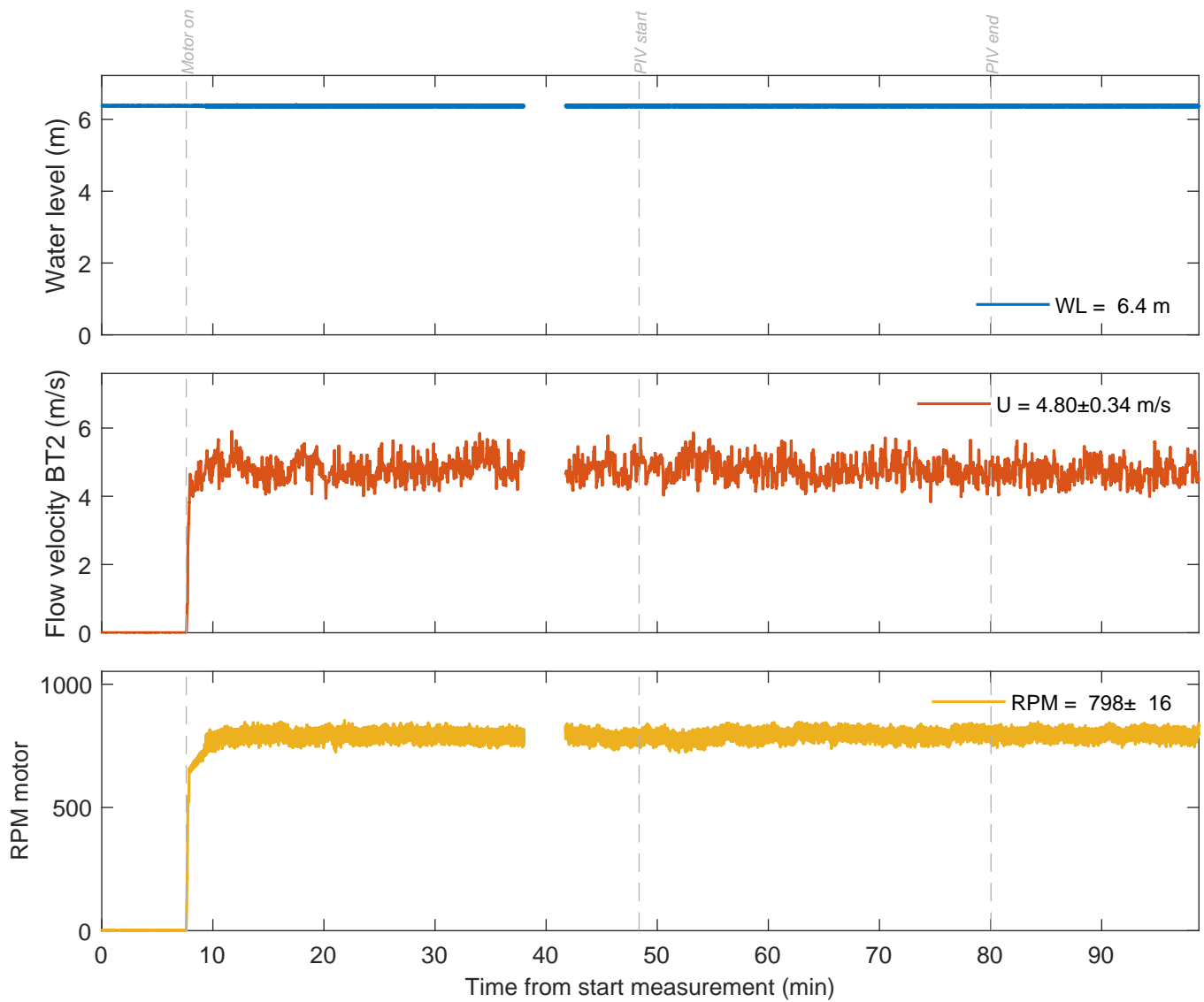
TKI-SOP

PIVSOP055

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 4.8$ m/s

Measurement
signals

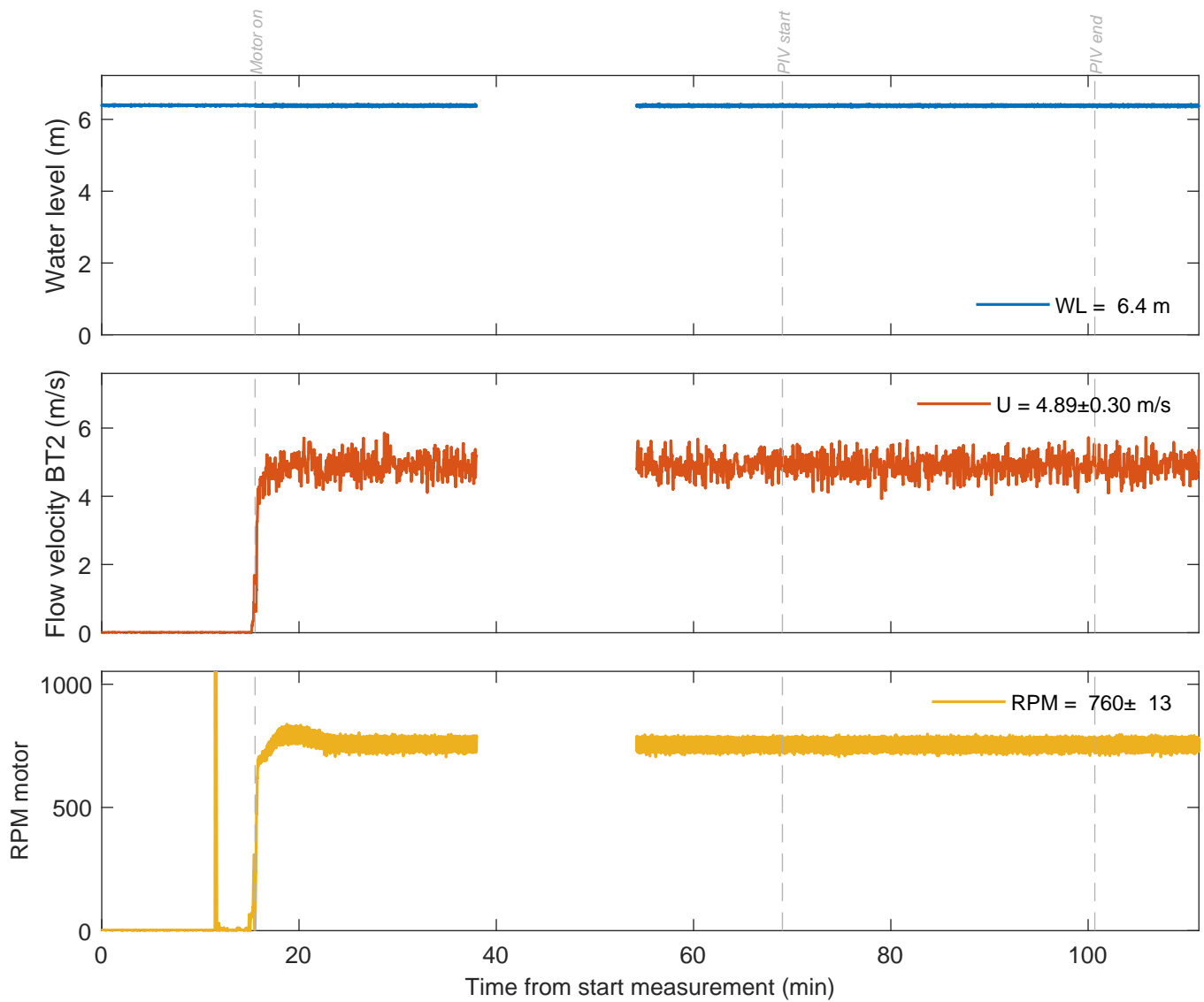
TKI-SOP

PIVSOP057

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 4.9$ m/s

Measurement
signals

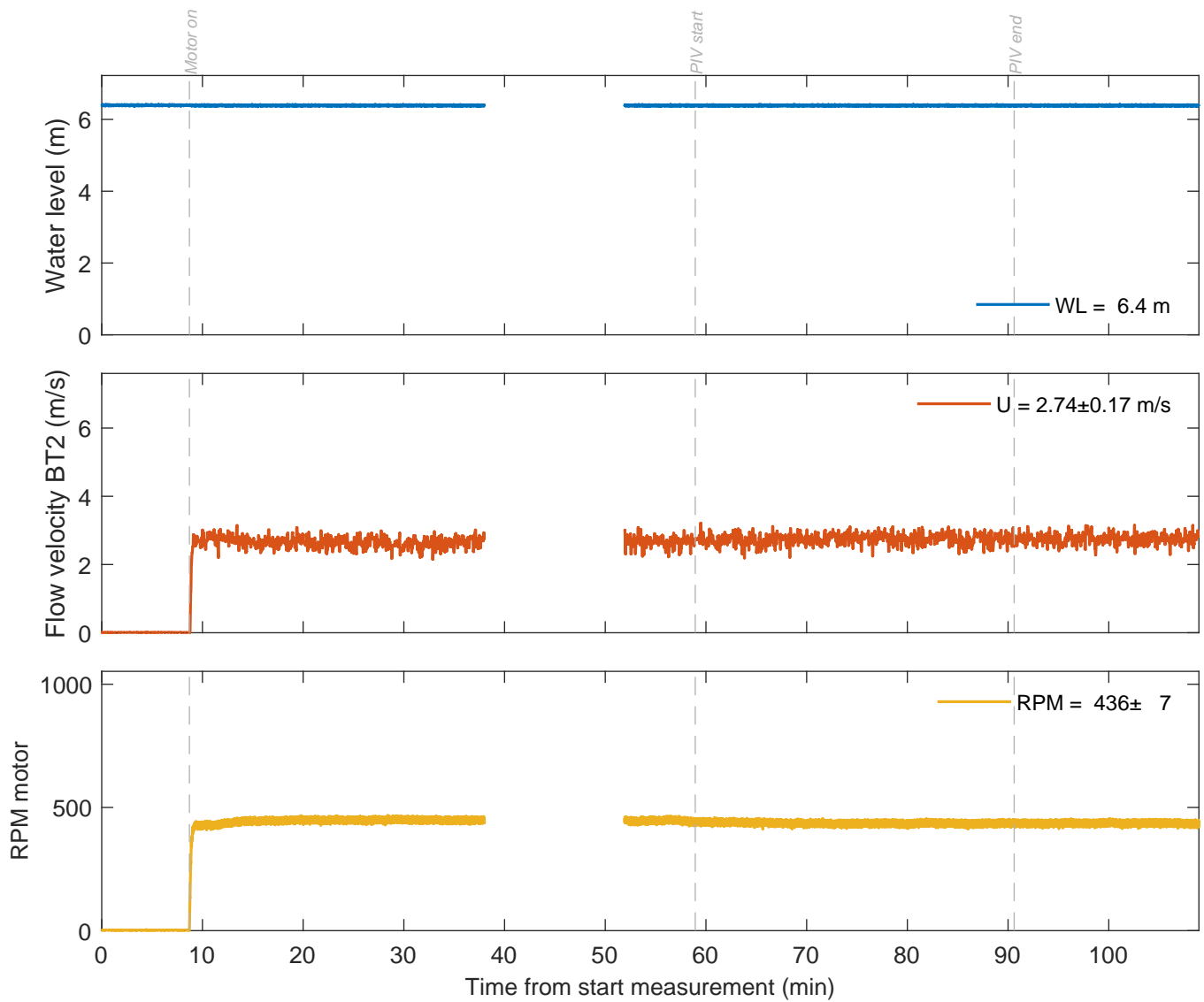
TKI-SOP

PIVSOP060

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 2.0$ m, UKC = 2.4 m, $U_{BT2} = 2.7$ m/s

Measurement
signals

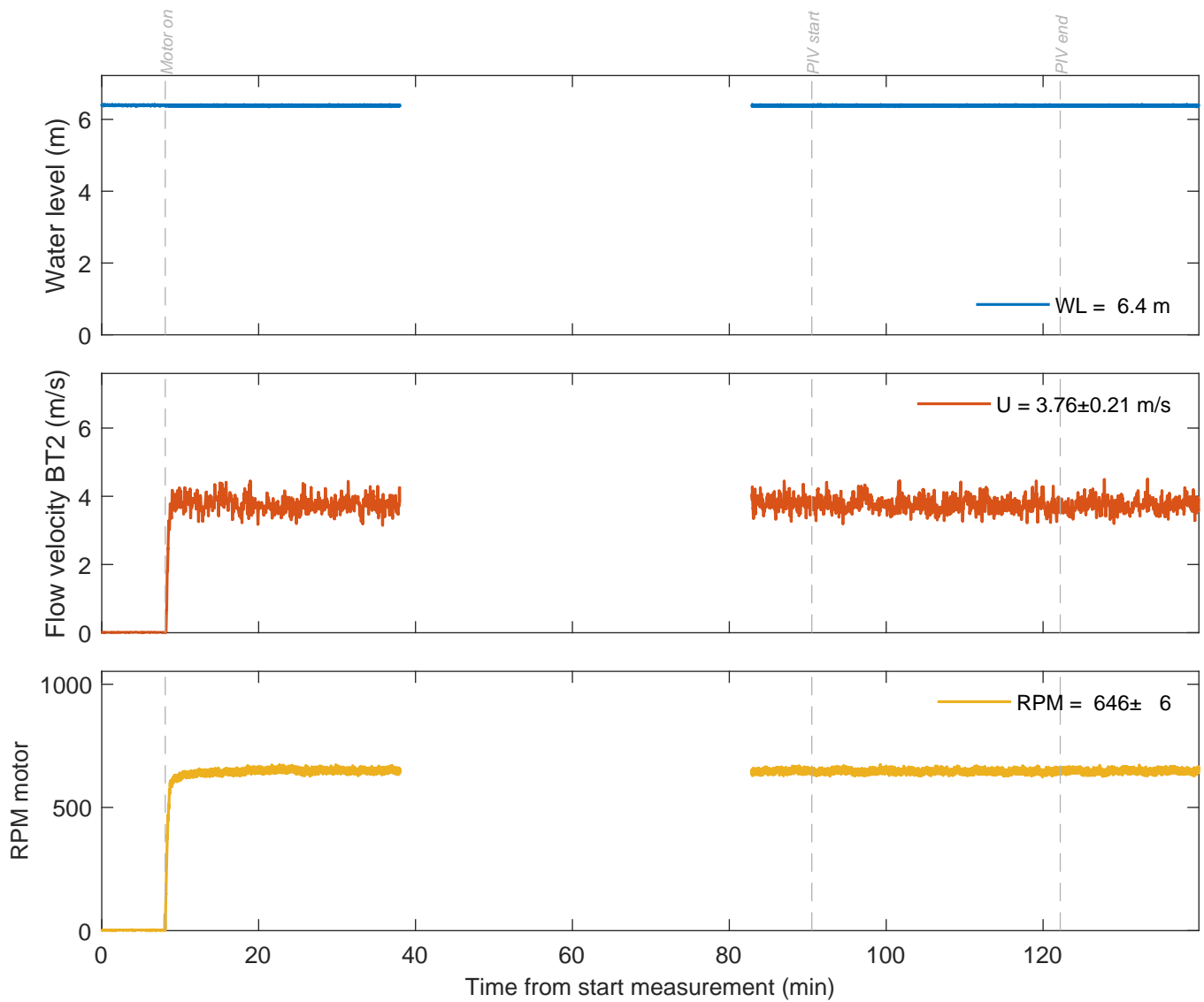
TKI-SOP

PIVSOP063

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 2.0$ m, UKC = 2.4 m, $U_{BT2} = 3.8$ m/s

Measurement
signals

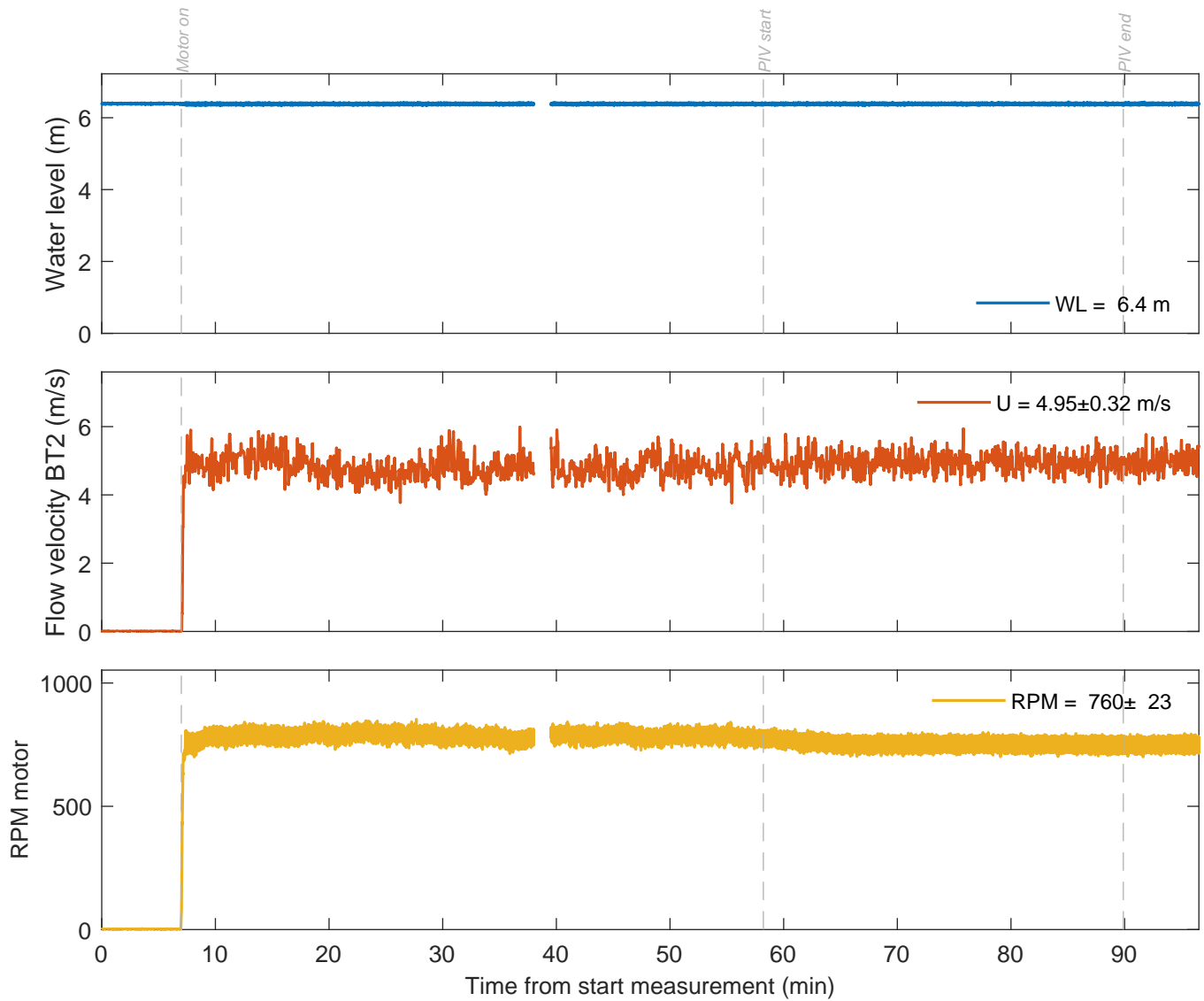
TKI-SOP

PIVSOP065

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 2.0$ m, UKC = 2.4 m, $U_{BT2} = 4.9$ m/s

Measurement
signals

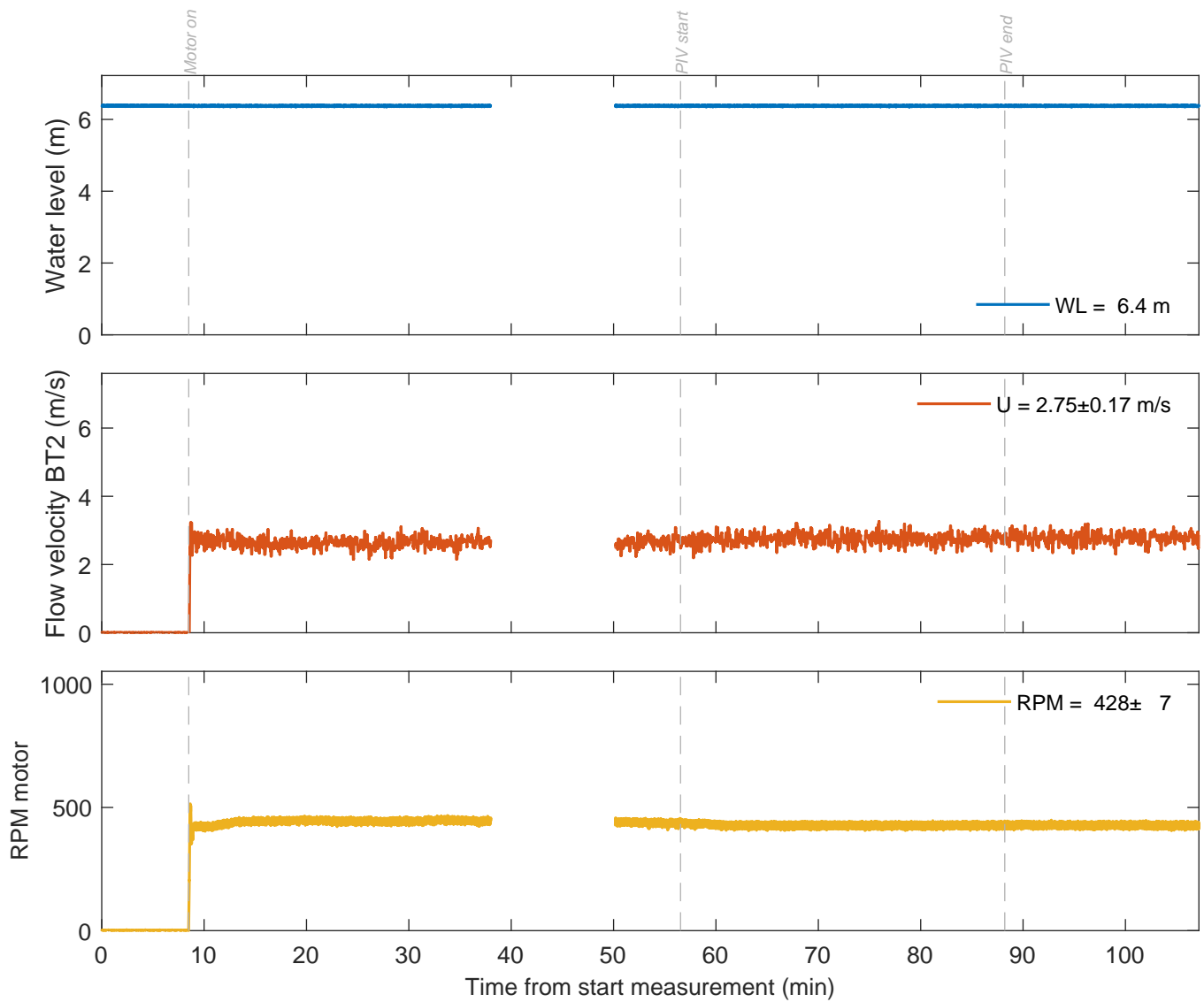
TKI-SOP

PIVSOP067

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8 \text{ m}$, $\Delta y = 3.5 \text{ m}$, UKC = 2.4 m, $U_{BT2} = 2.8 \text{ m/s}$

Measurement
signals

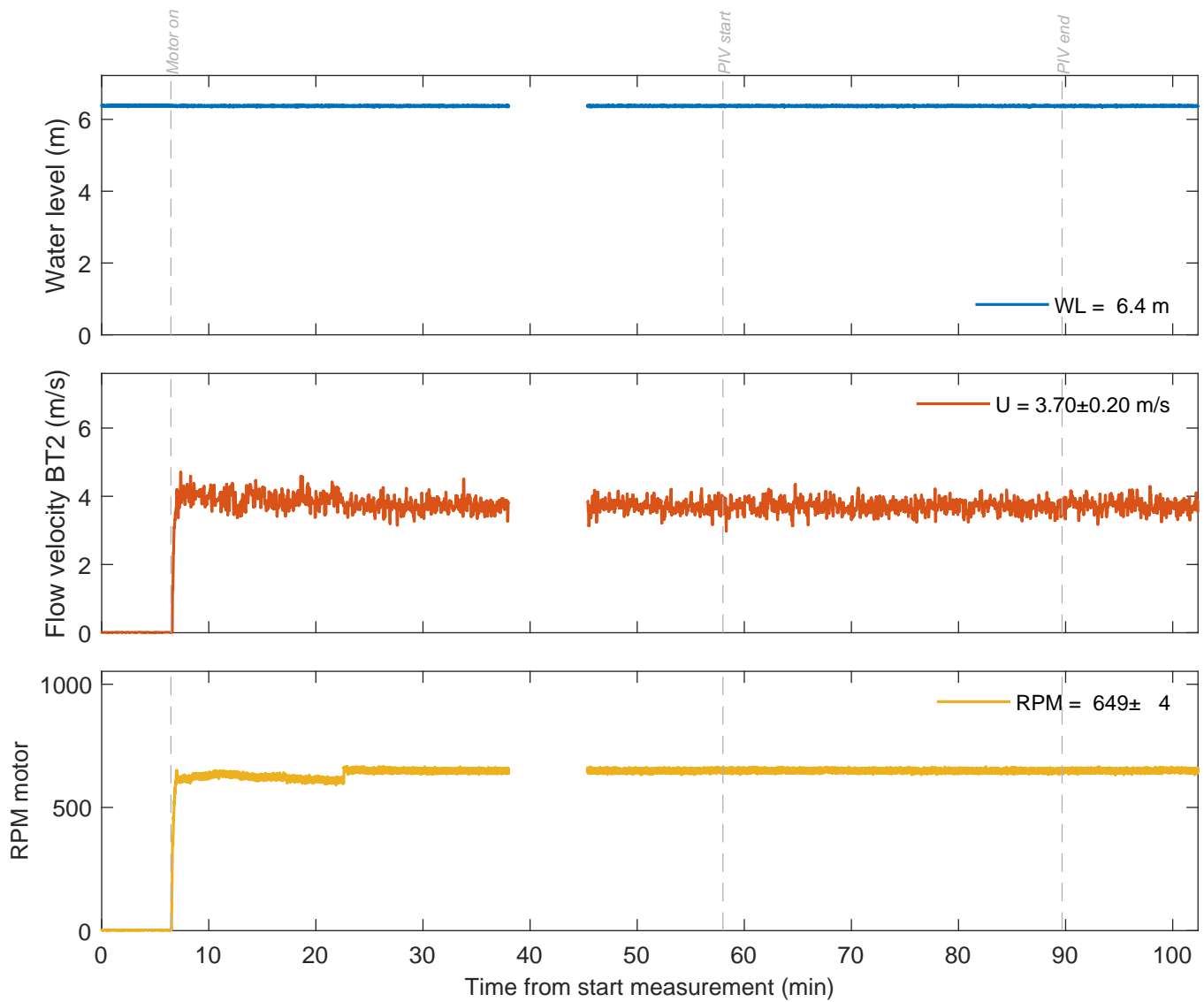
TKI-SOP

PIVSOP070

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 3.5$ m, UKC = 2.4 m, $U_{BT2} = 3.7$ m/s

Measurement
signals

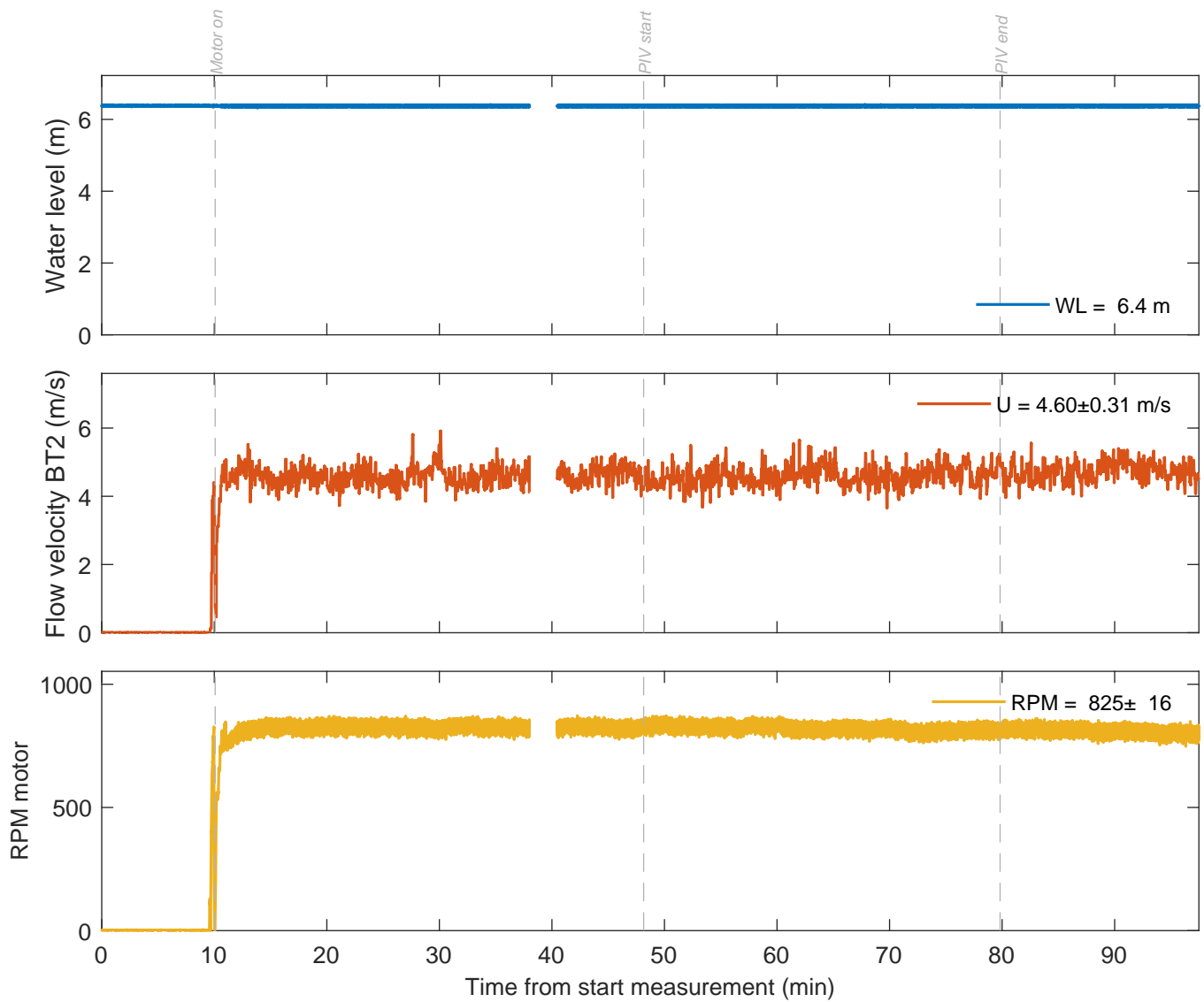
TKI-SOP

PIVSOP072

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 3.5$ m, UKC = 2.4 m, $U_{BT2} = 4.6$ m/s

Measurement
signals

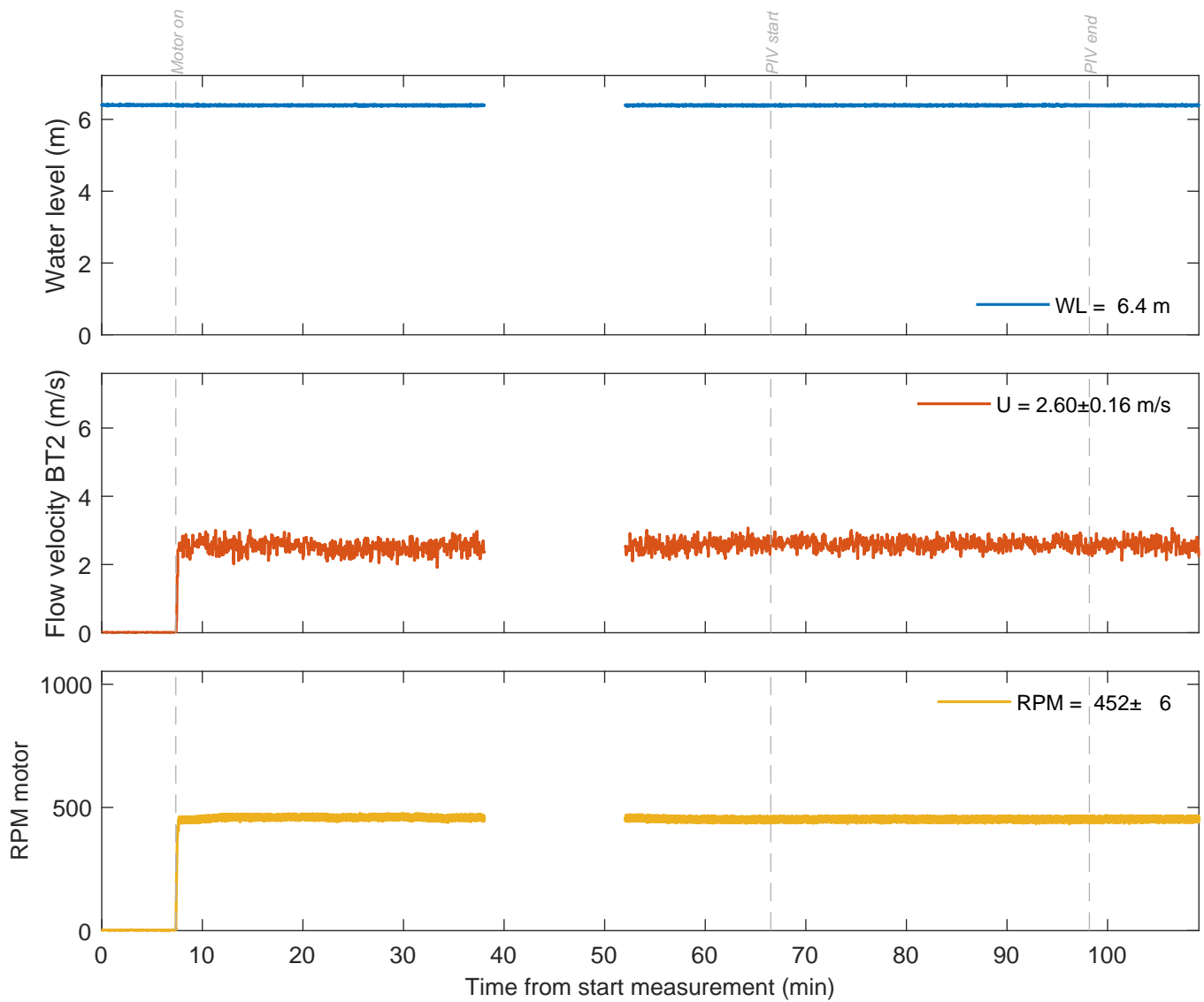
TKI-SOP

PIVSOP074

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = -2.0$ m, UKC = 2.5 m, $U_{BT2} = 2.6$ m/s

Measurement
signals

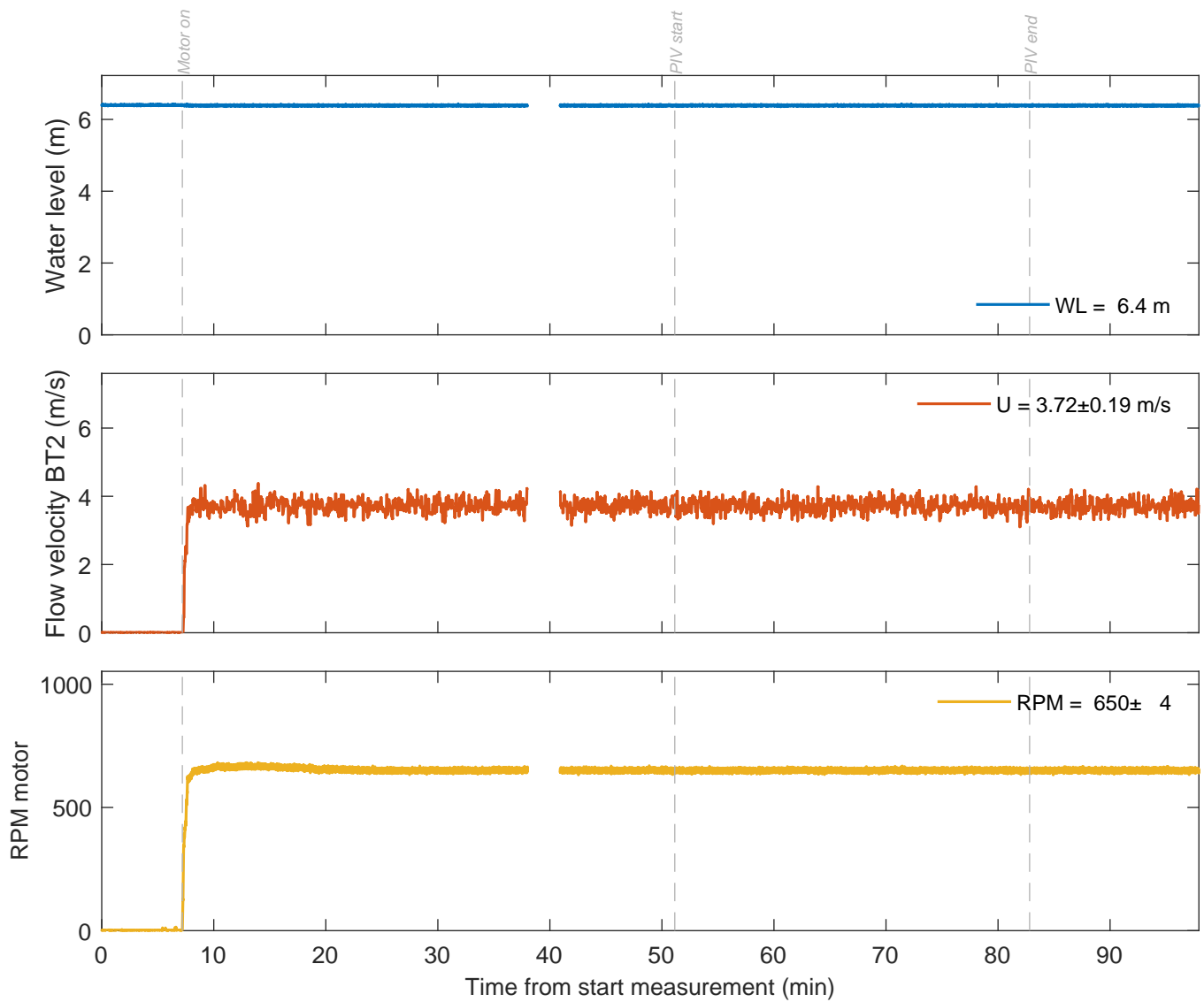
TKI-SOP

PIVSOP077

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = -2.0$ m, UKC = 2.5 m, $U_{BT2} = 3.7$ m/s

Measurement
signals

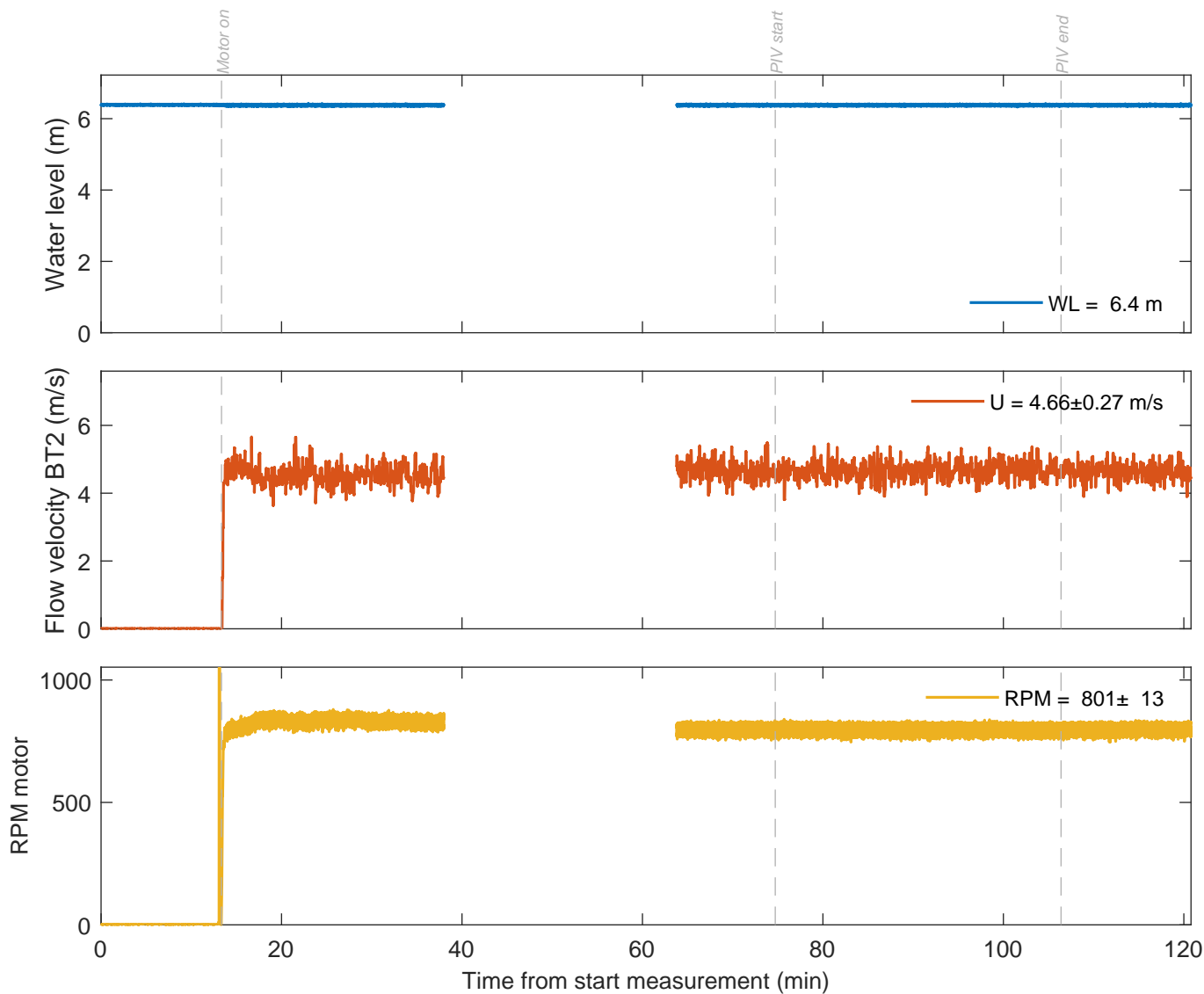
TKI-SOP

PIVSOP079

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = -2.0$ m, UKC = 2.5 m, $U_{\text{BT2}} = 4.7$ m/s

Measurement
signals

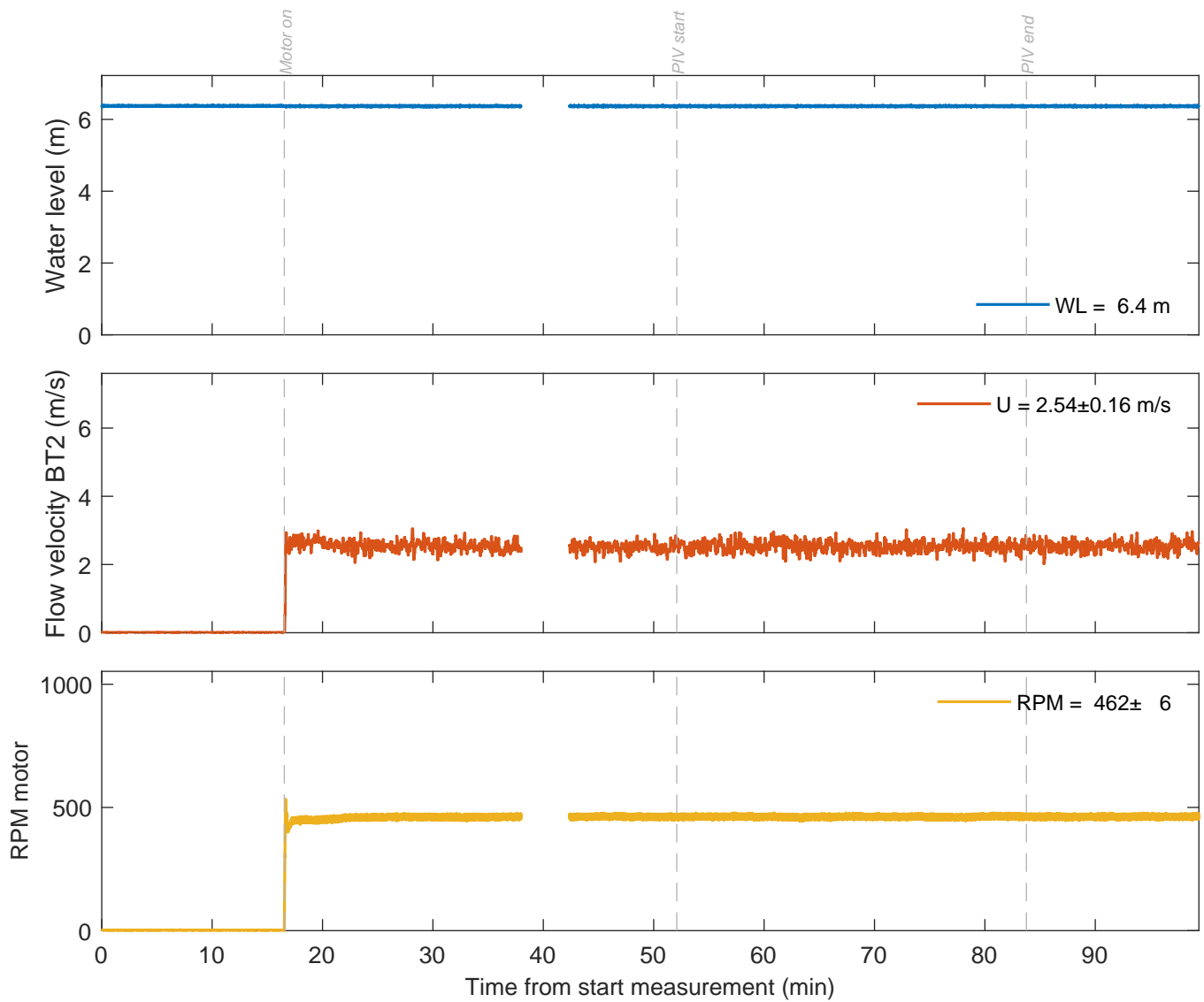
TKI-SOP

PIVSOP082

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = -4.0$ m, UKC = 2.5 m, $U_{BT2} = 2.5$ m/s

Measurement
signals

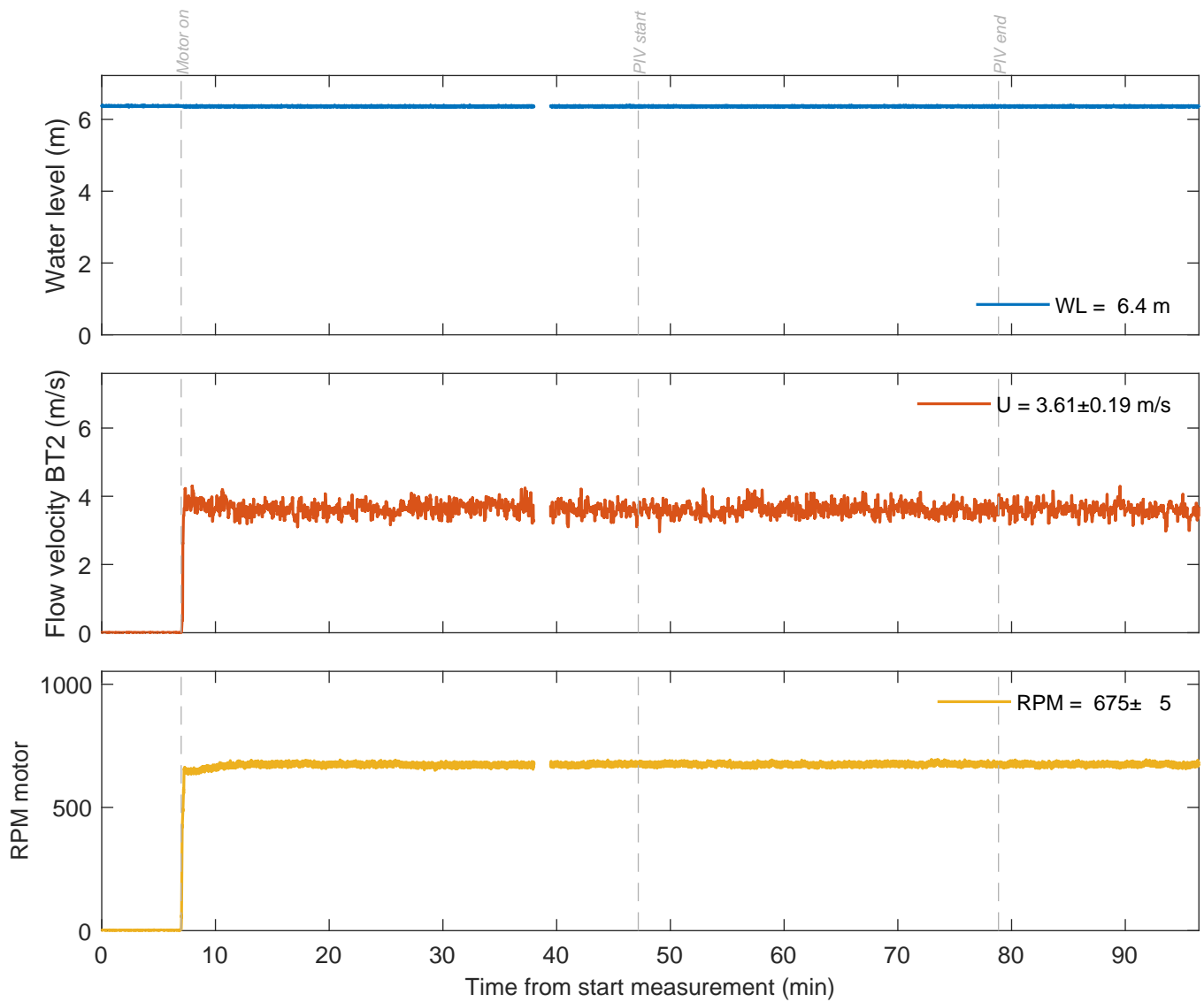
TKI-SOP

PIVSOP085

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = -4.0$ m, UKC = 2.5 m, $U_{BT2} = 3.6$ m/s

Measurement
signals

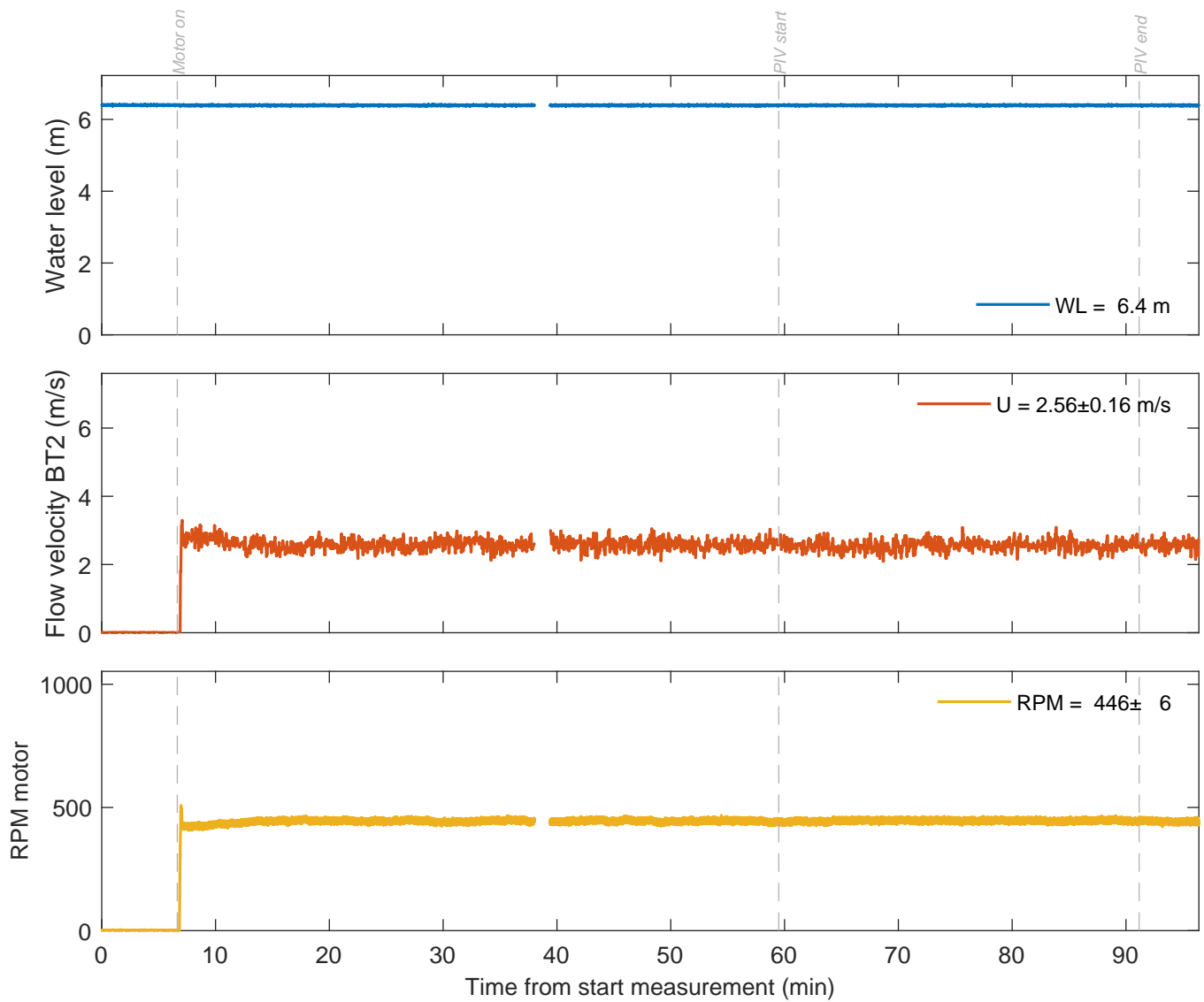
TKI-SOP

PIVSOP087

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8 \text{ m}$, $\Delta y = -4.0 \text{ m}$, $UKC = 2.5 \text{ m}$, $U_{BT2} = 2.6 \text{ m/s}$

Measurement
signals

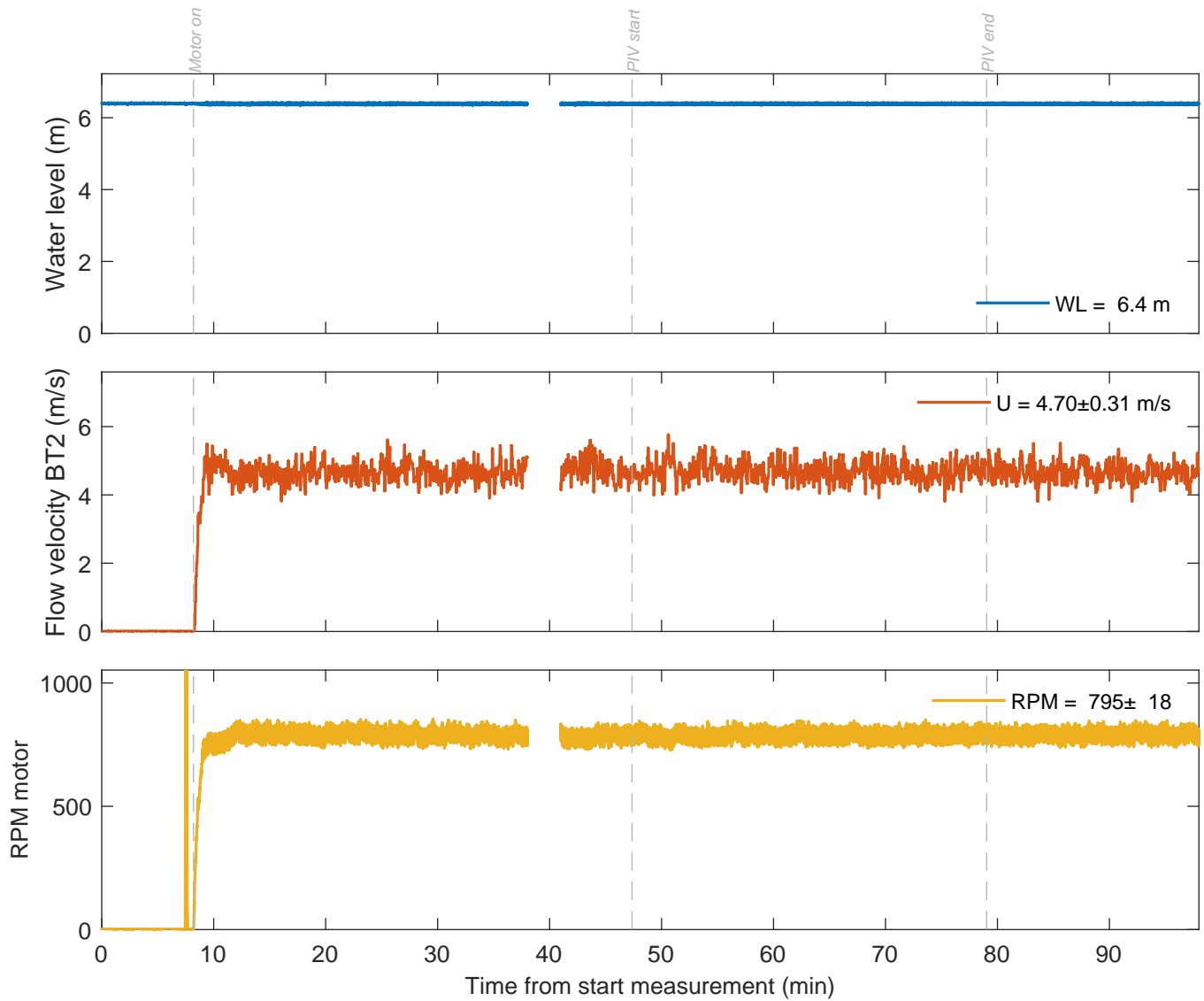
TKI-SOP

PIVSOP091

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = -4.0$ m, UKC = 2.5 m, $U_{BT2} = 4.7$ m/s

Measurement
signals

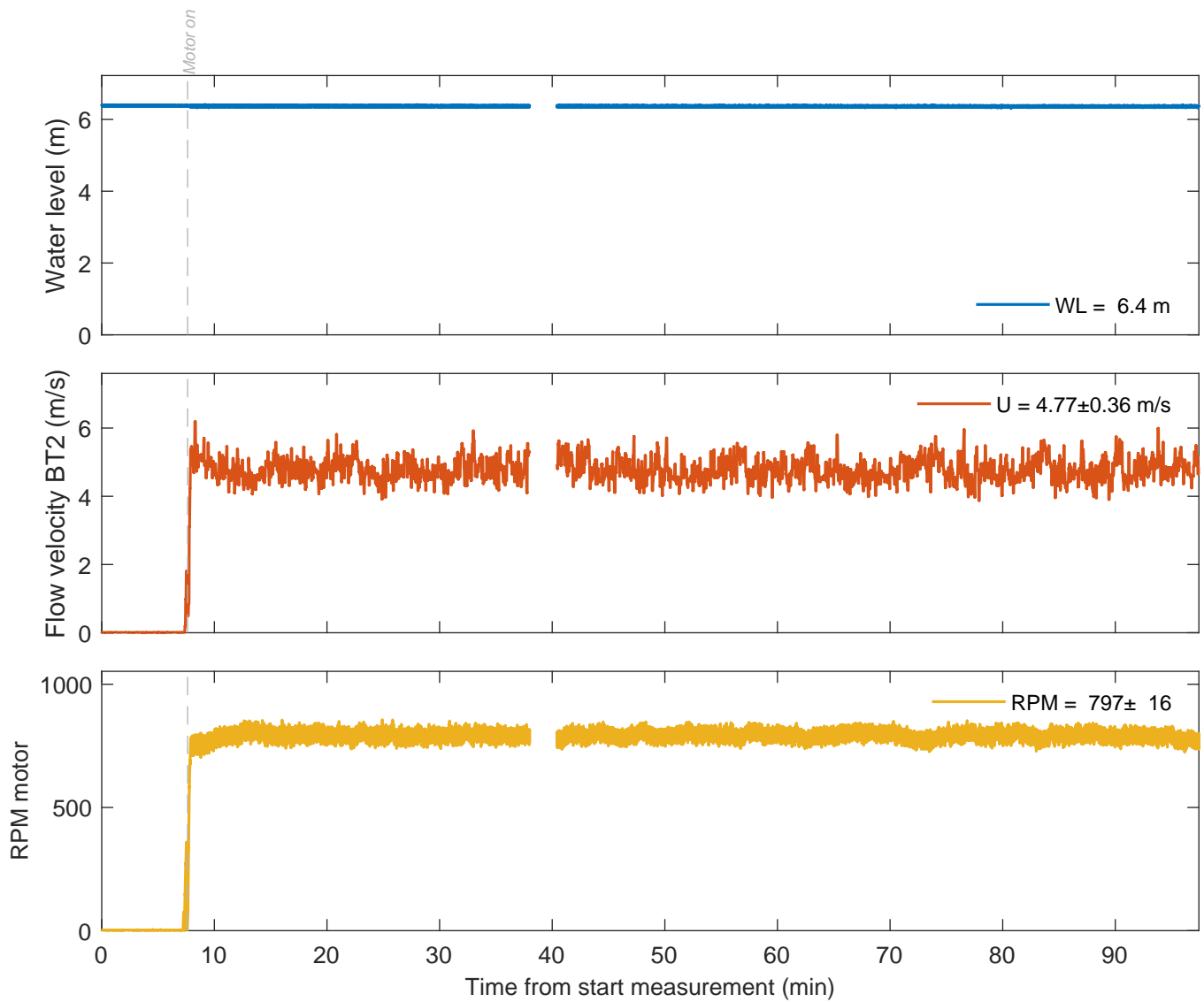
TKI-SOP

PIVSOP093

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = -2.0$ m, UKC = 2.4 m, $U_{BT2} = 4.8$ m/s

Measurement
signals

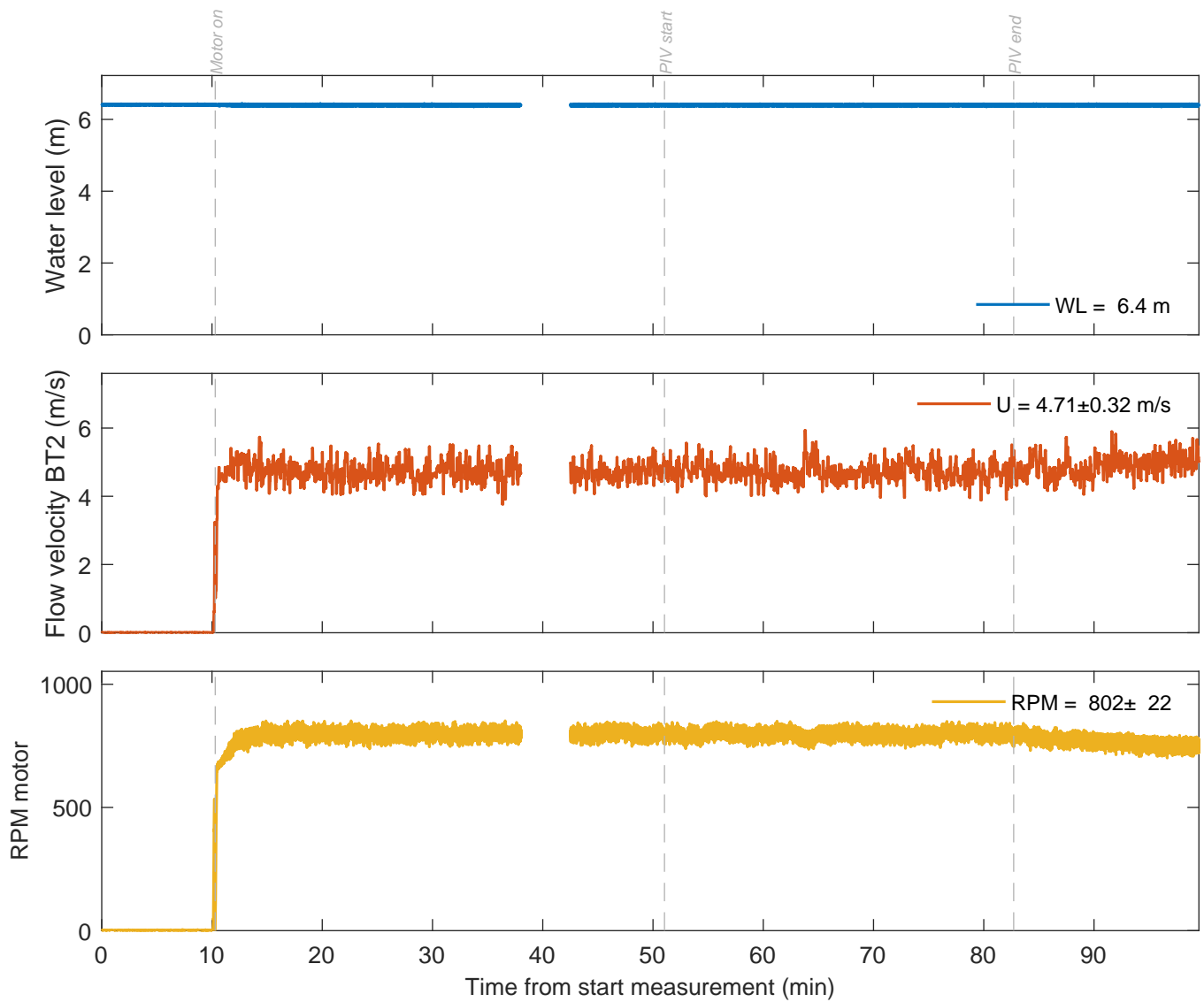
TKI-SOP

PIVSOP096

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 2.0$ m, UKC = 2.4 m, $U_{BT2} = 4.7$ m/s

Measurement
signals

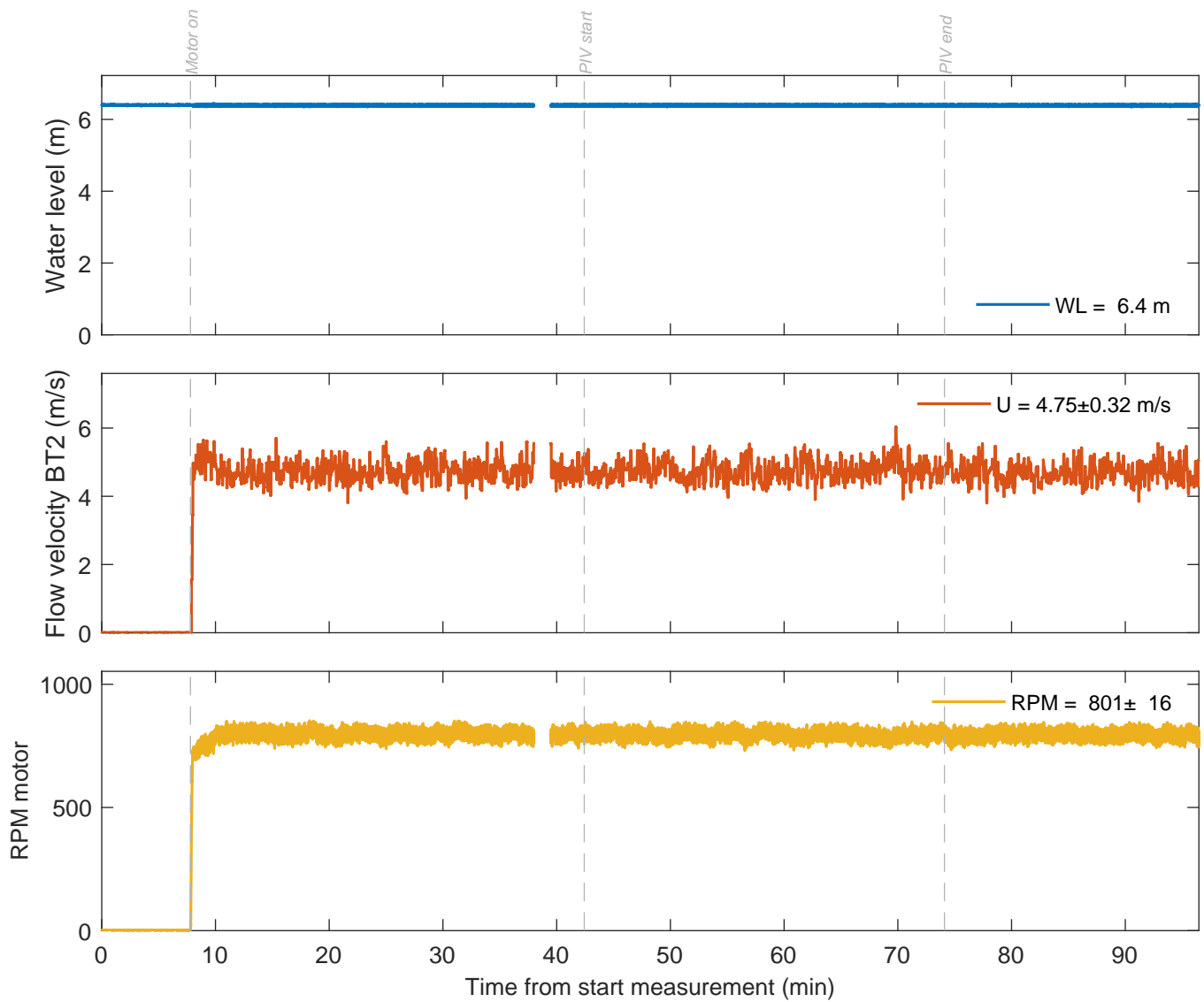
TKI-SOP

PIVSOP099

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 3.5$ m, UKC = 2.4 m, $U_{BT2} = 4.7$ m/s

Measurement
signals

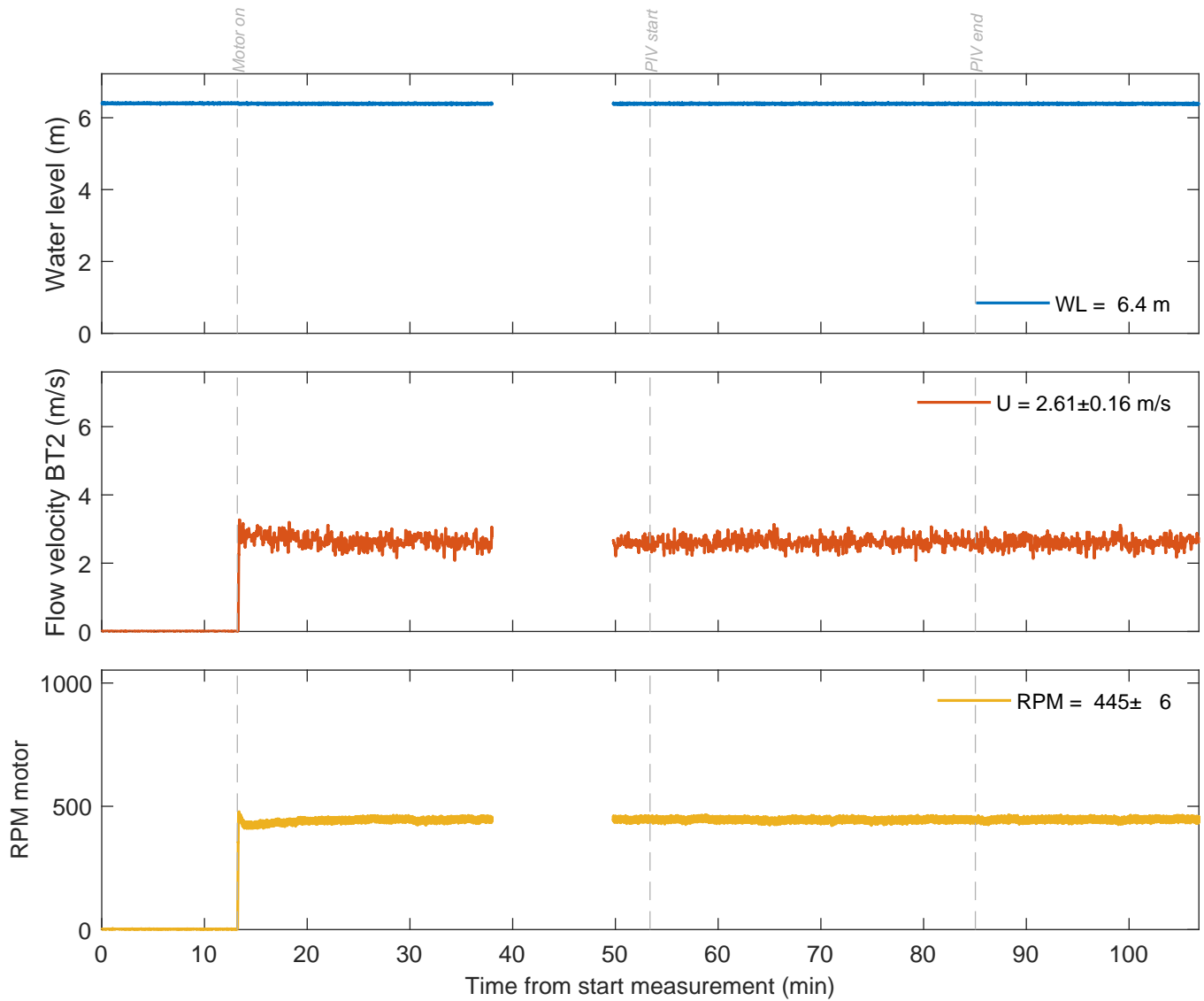
TKI-SOP

PIVSOP102

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 2.6$ m/s

Measurement
signals

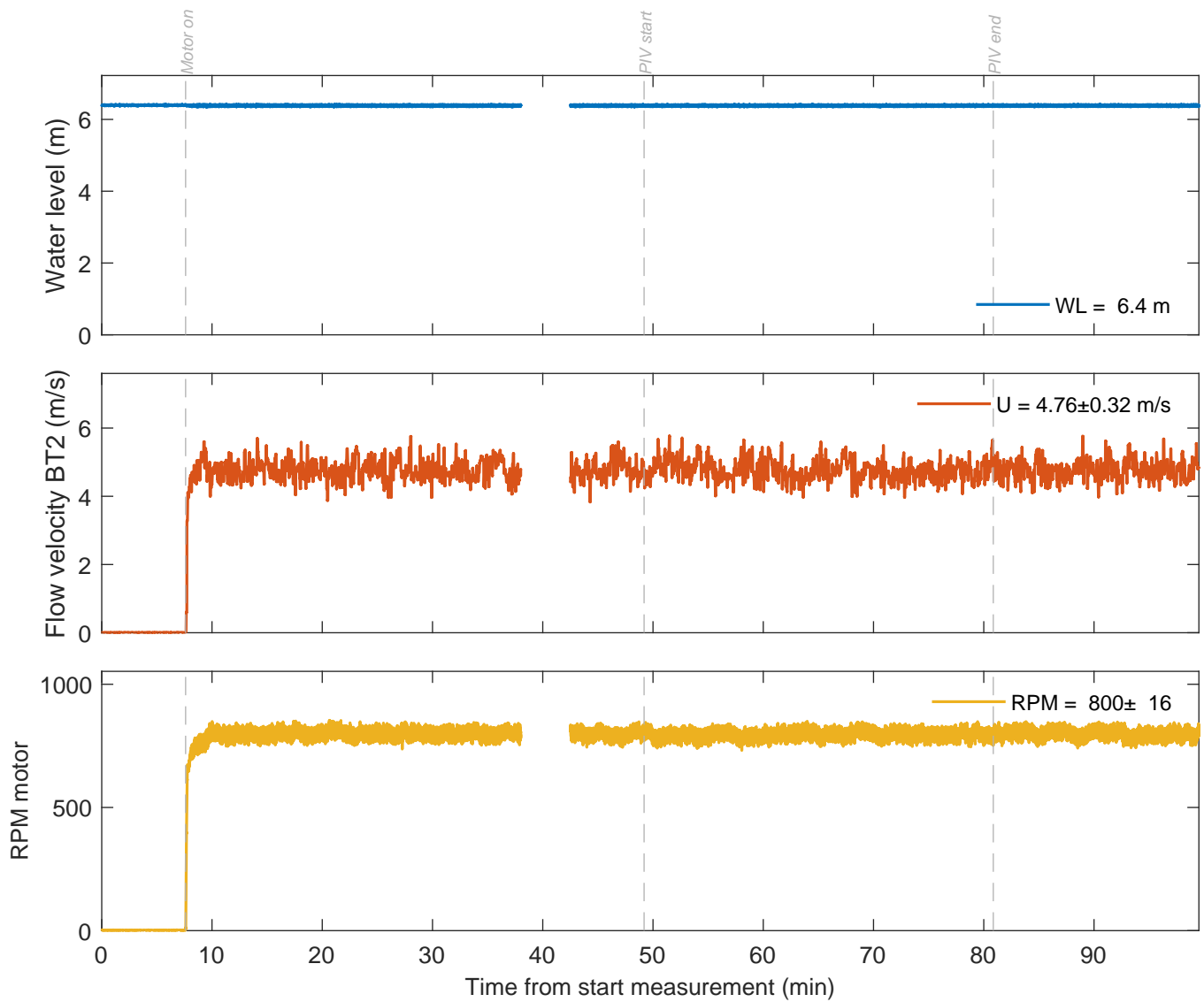
TKI-SOP

PIVSOP105

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 4.8$ m/s

Measurement
signals

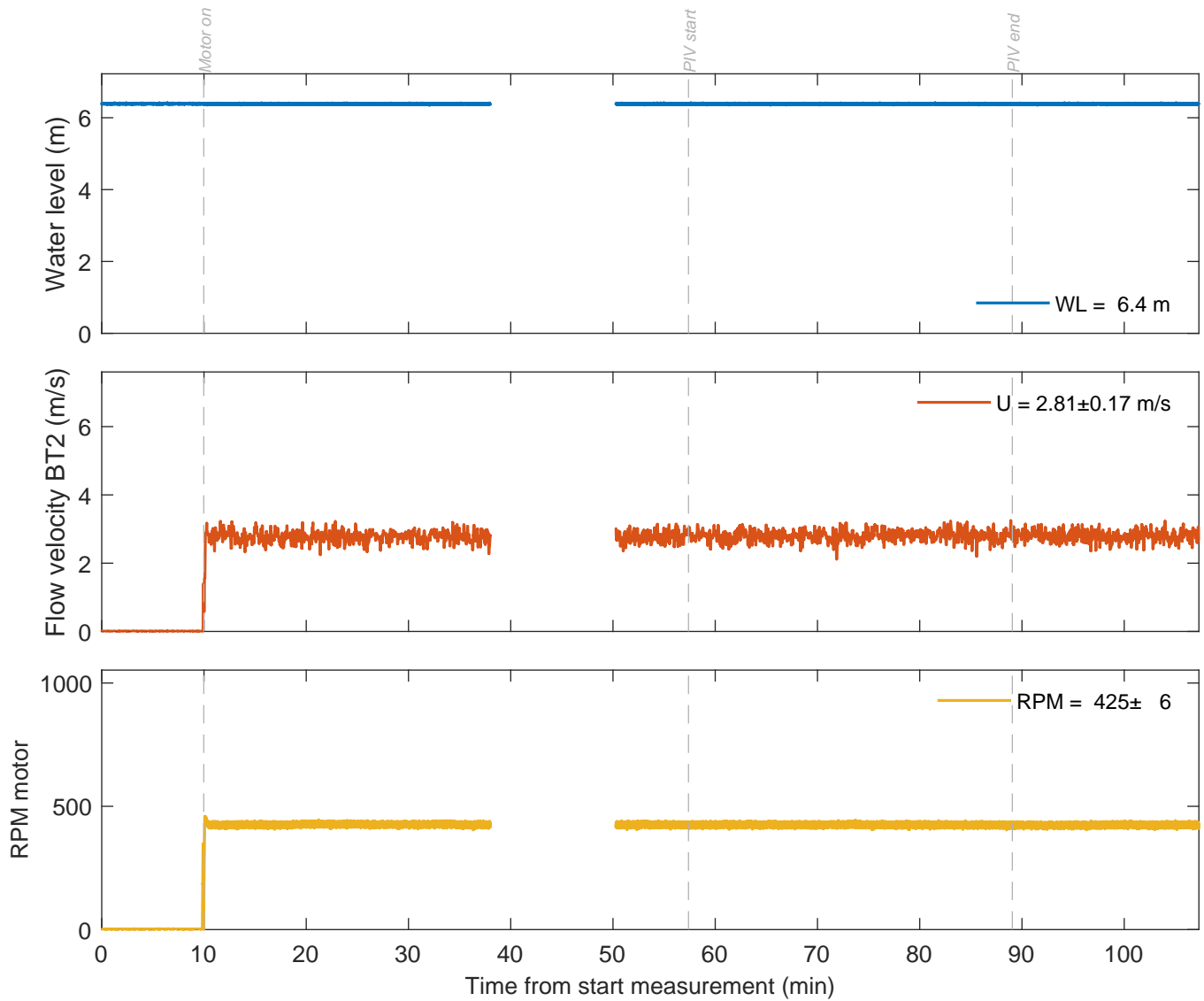
TKI-SOP

PIVSOP107

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 5.0$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 2.8$ m/s

Measurement
signals

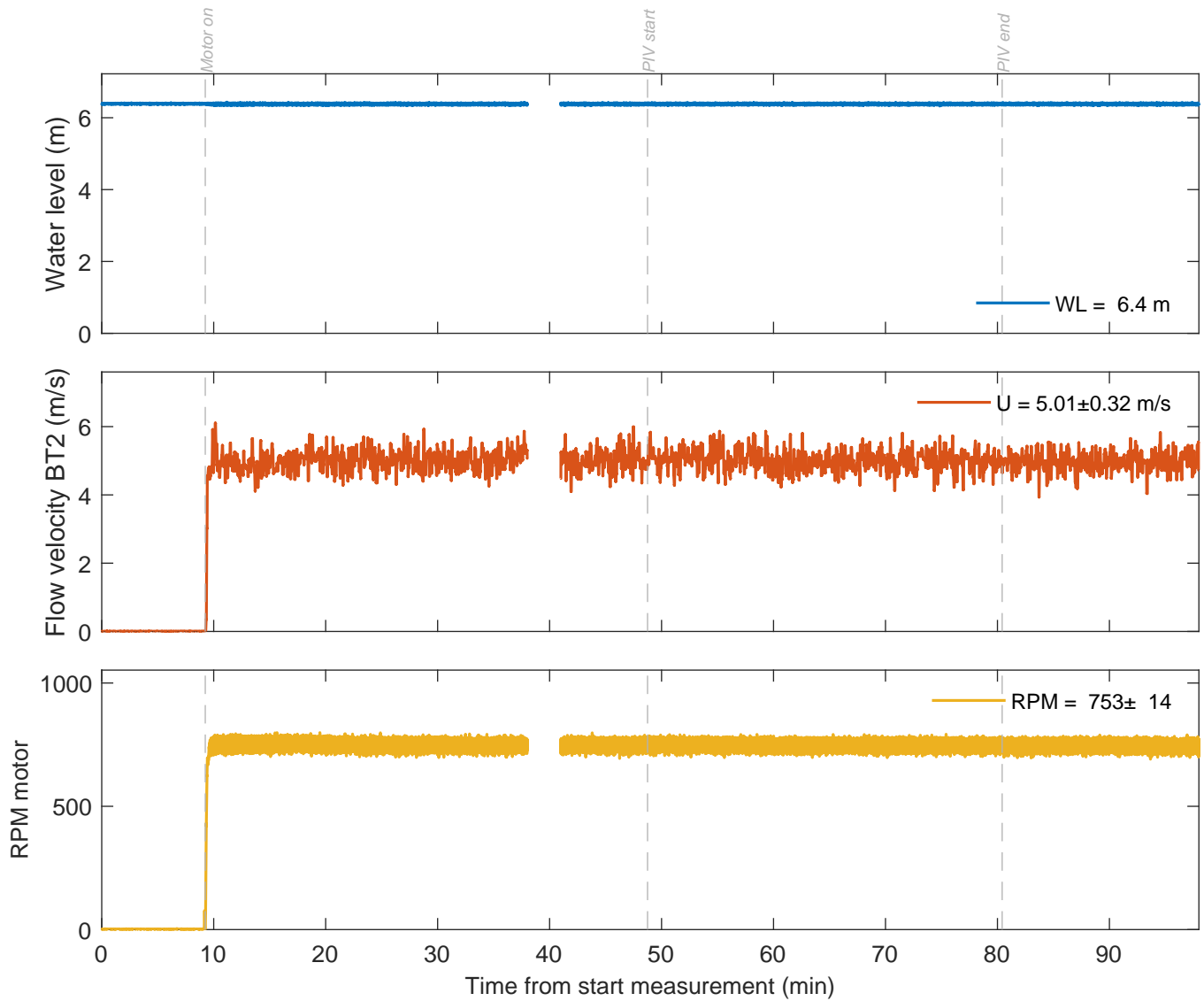
TKI-SOP

PIVSOP110

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 5.0$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 5.0$ m/s

Measurement
signals

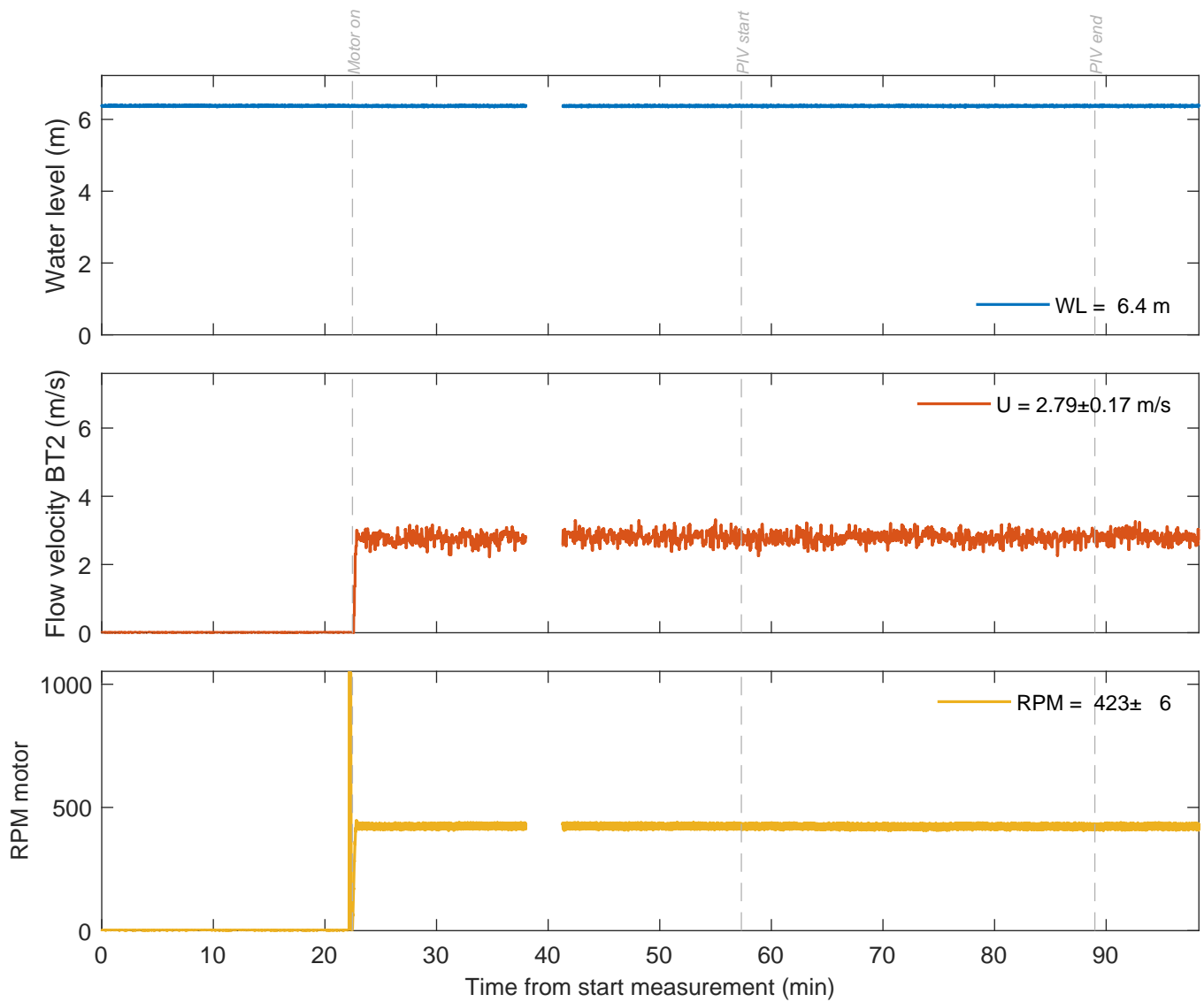
TKI-SOP

PIVSOP112

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 5.0$ m, $\Delta y = -2.0$ m, UKC = 2.4 m, $U_{BT2} = 2.8$ m/s

Measurement
signals

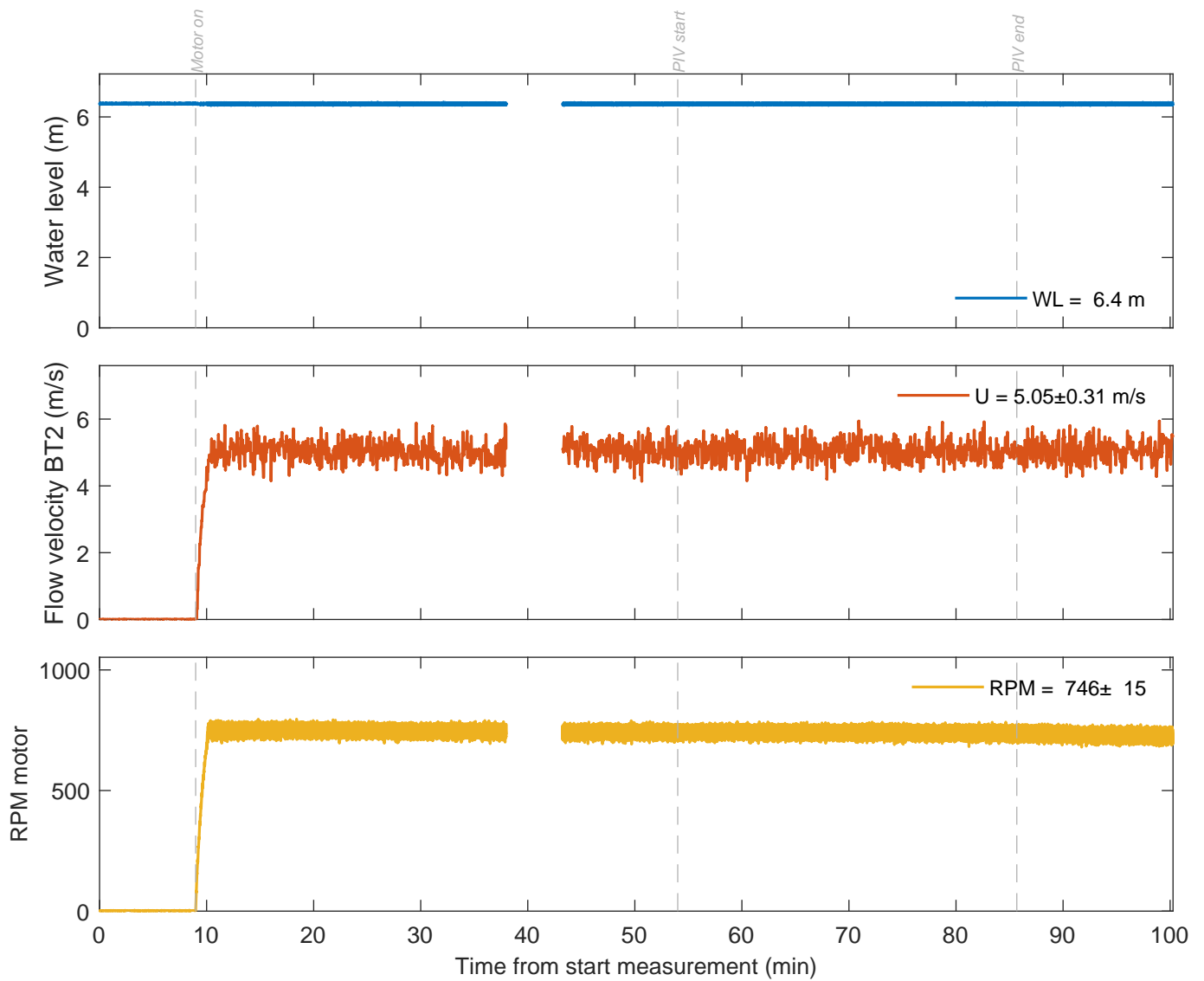
TKI-SOP

PIVSOP115

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 5.0 \text{ m}$, $\Delta y = -2.0 \text{ m}$, $UKC = 2.4 \text{ m}$, $U_{BT2} = 5.1 \text{ m/s}$

Measurement
signals

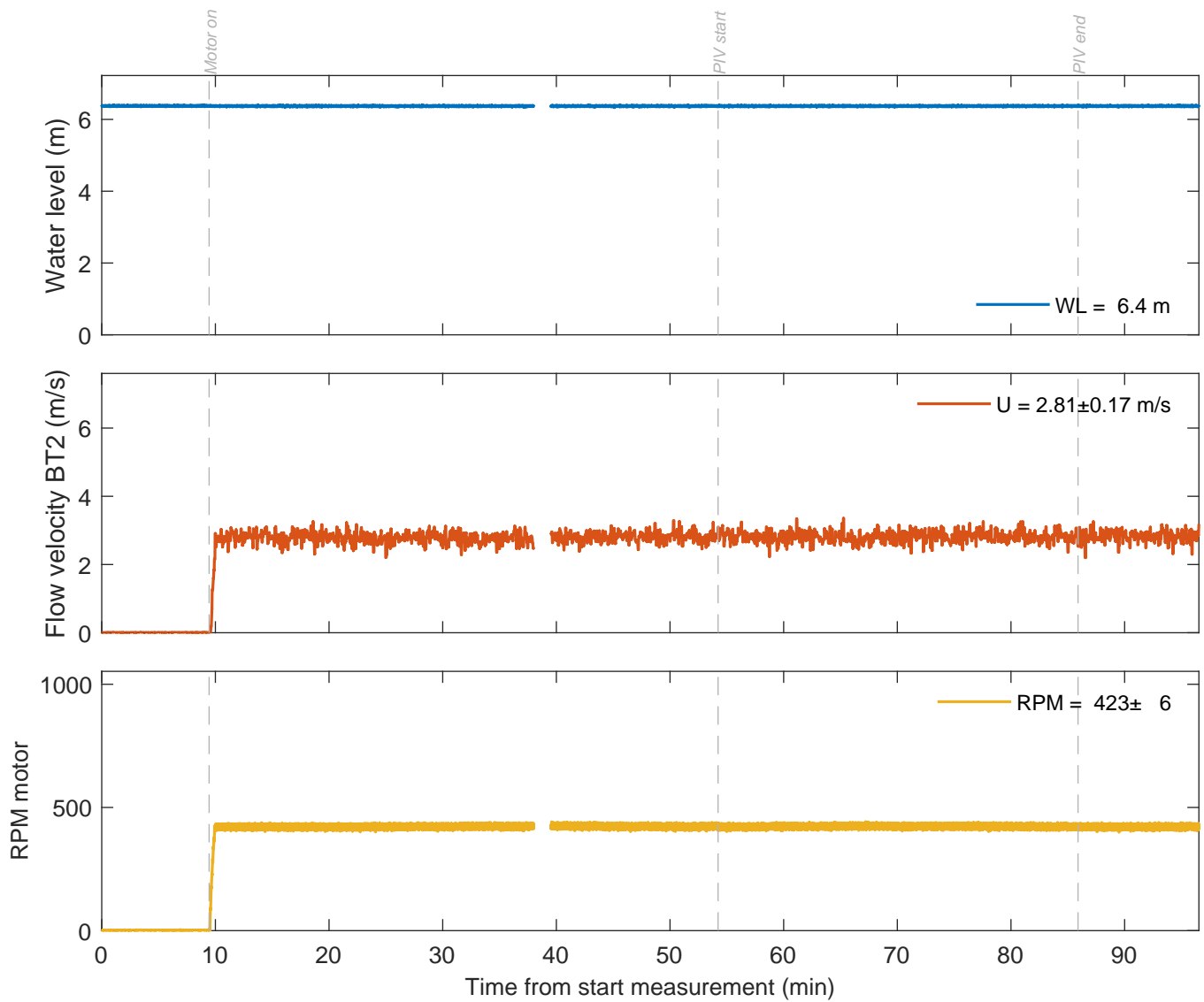
TKI-SOP

PIVSOP117

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 5.0$ m, $\Delta y = 2.0$ m, UKC = 2.4 m, $U_{BT2} = 2.8$ m/s

Measurement
signals

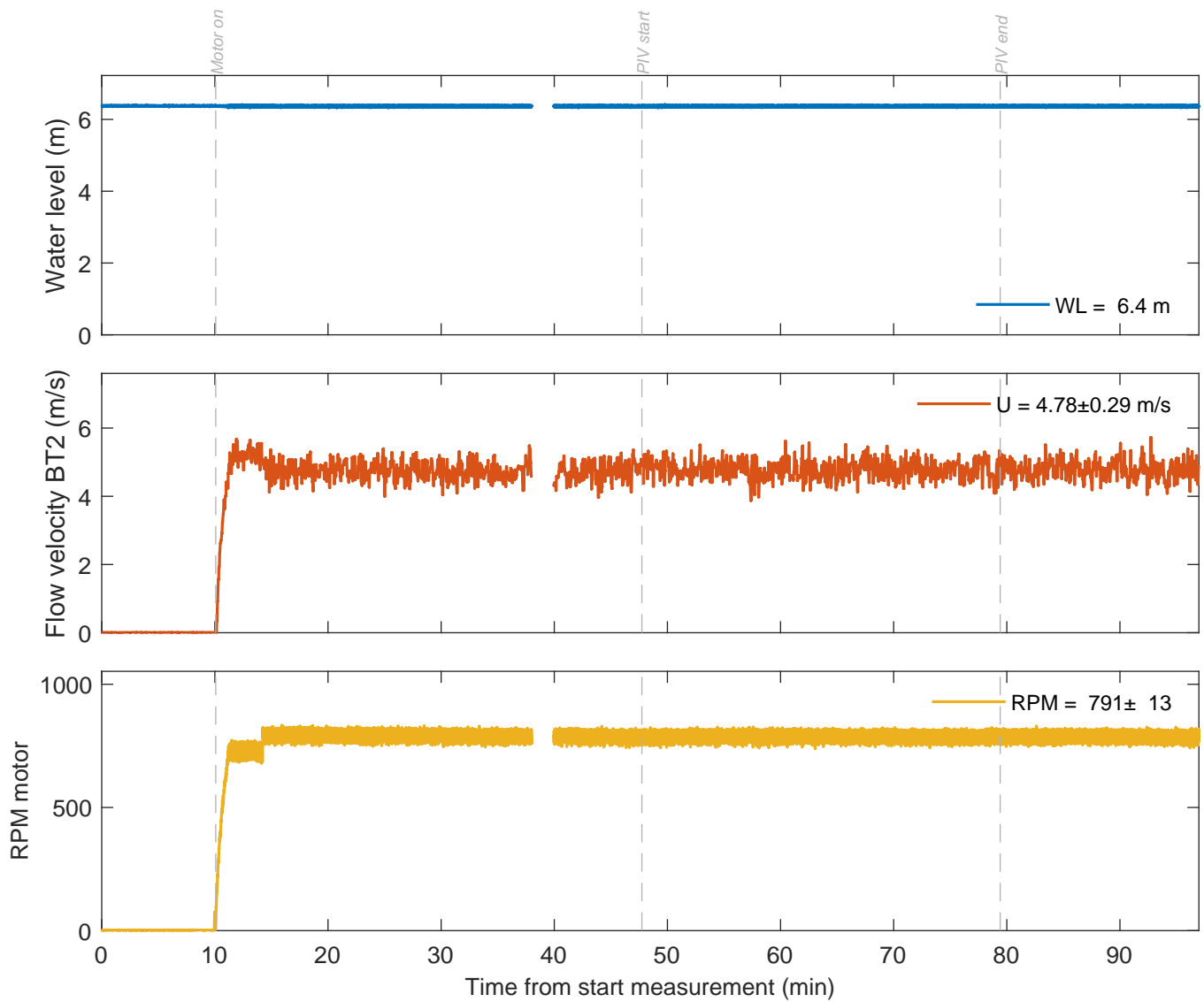
TKI-SOP

PIVSOP119

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 5.0$ m, $\Delta y = 2.0$ m, UKC = 2.4 m, $U_{BT2} = 4.8$ m/s

Measurement
signals

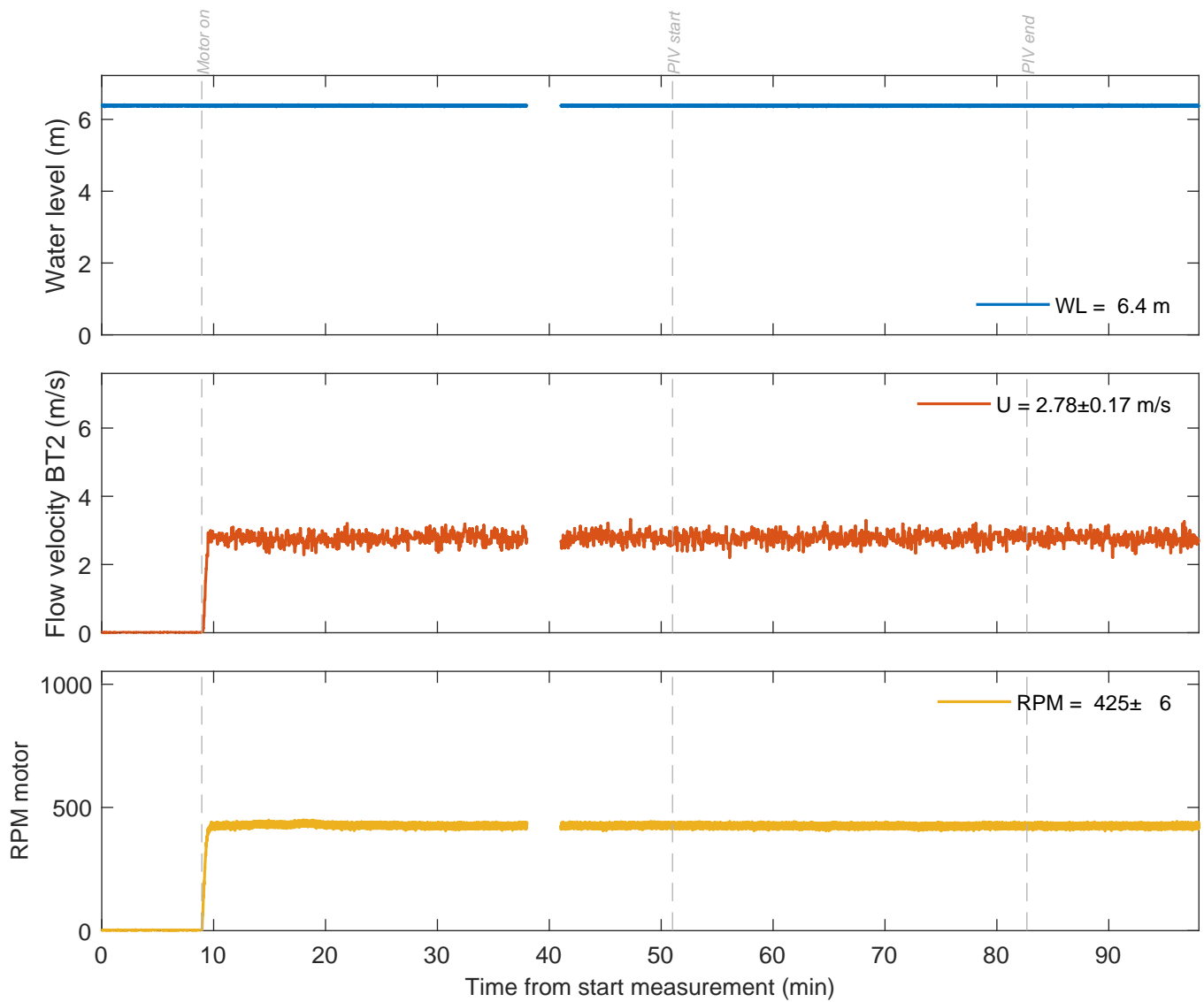
TKI-SOP

PIVSOP121

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 3.0$ m, $\Delta y = 2.0$ m, UKC = 2.4 m, $U_{BT2} = 2.8$ m/s

Measurement
signals

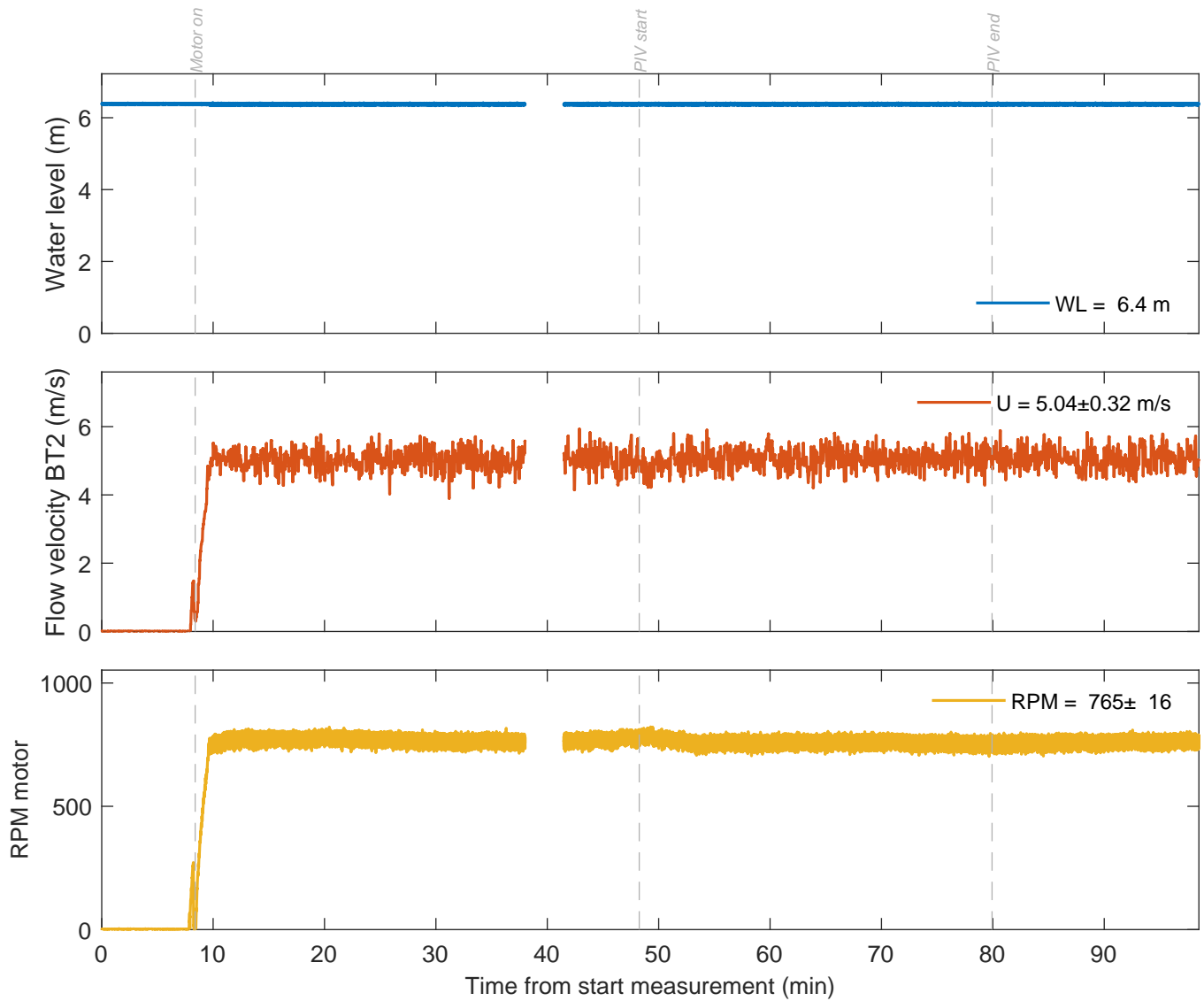
TKI-SOP

PIVSOP124

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 3.0 \text{ m}$, $\Delta y = 2.0 \text{ m}$, UKC = 2.4 m, $U_{BT2} = 5.0 \text{ m/s}$

Measurement
signals

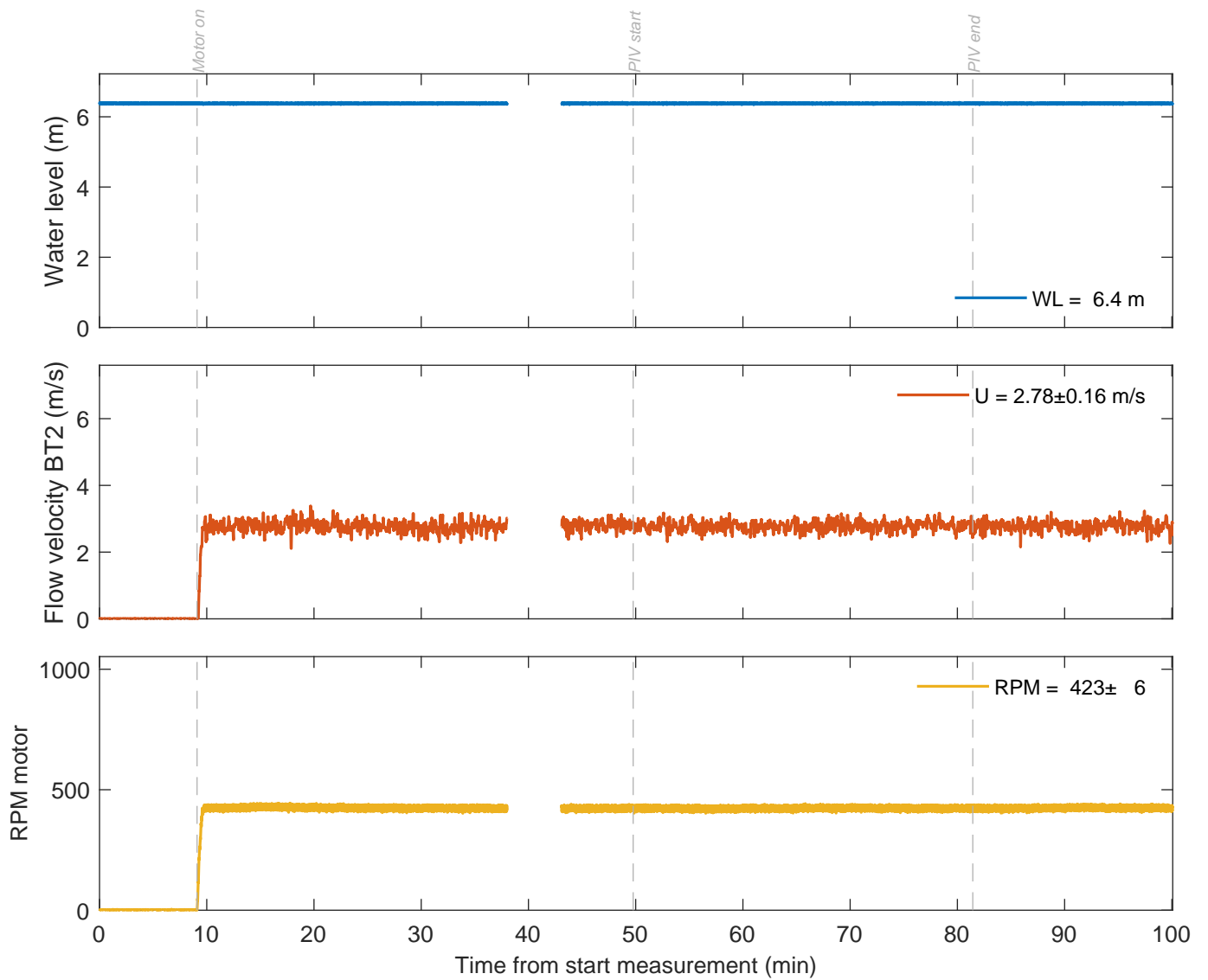
TKI-SOP

PIVSOP126

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 3.0 \text{ m}$, $\Delta y = 0.0 \text{ m}$, $UKC = 2.4 \text{ m}$, $U_{BT2} = 2.8 \text{ m/s}$

Measurement
signals

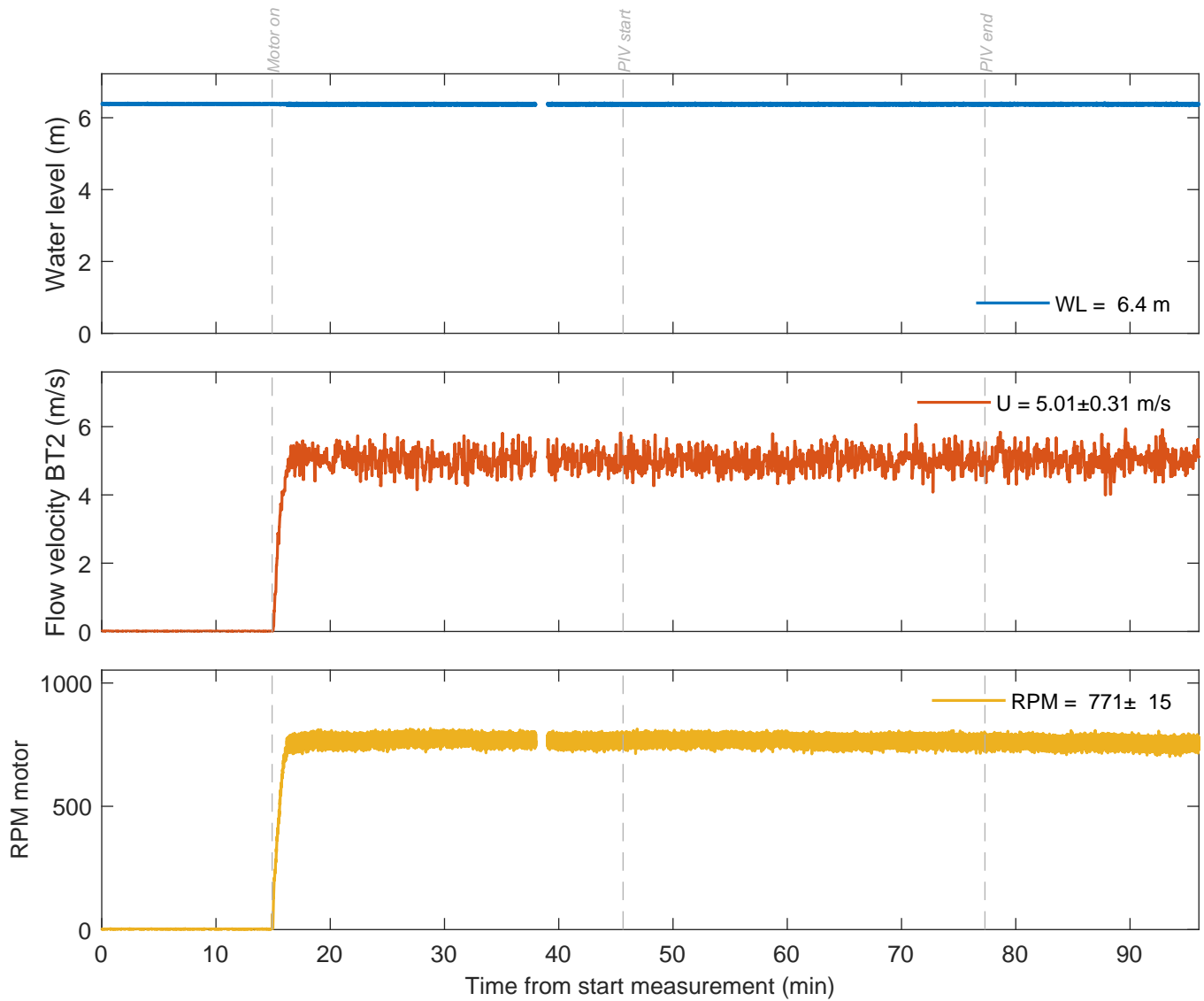
TKI-SOP

PIVSOP131

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 3.0$ m, $\Delta y = 0.0$ m, UKC = 2.4 m, $U_{BT2} = 5.0$ m/s

Measurement
signals

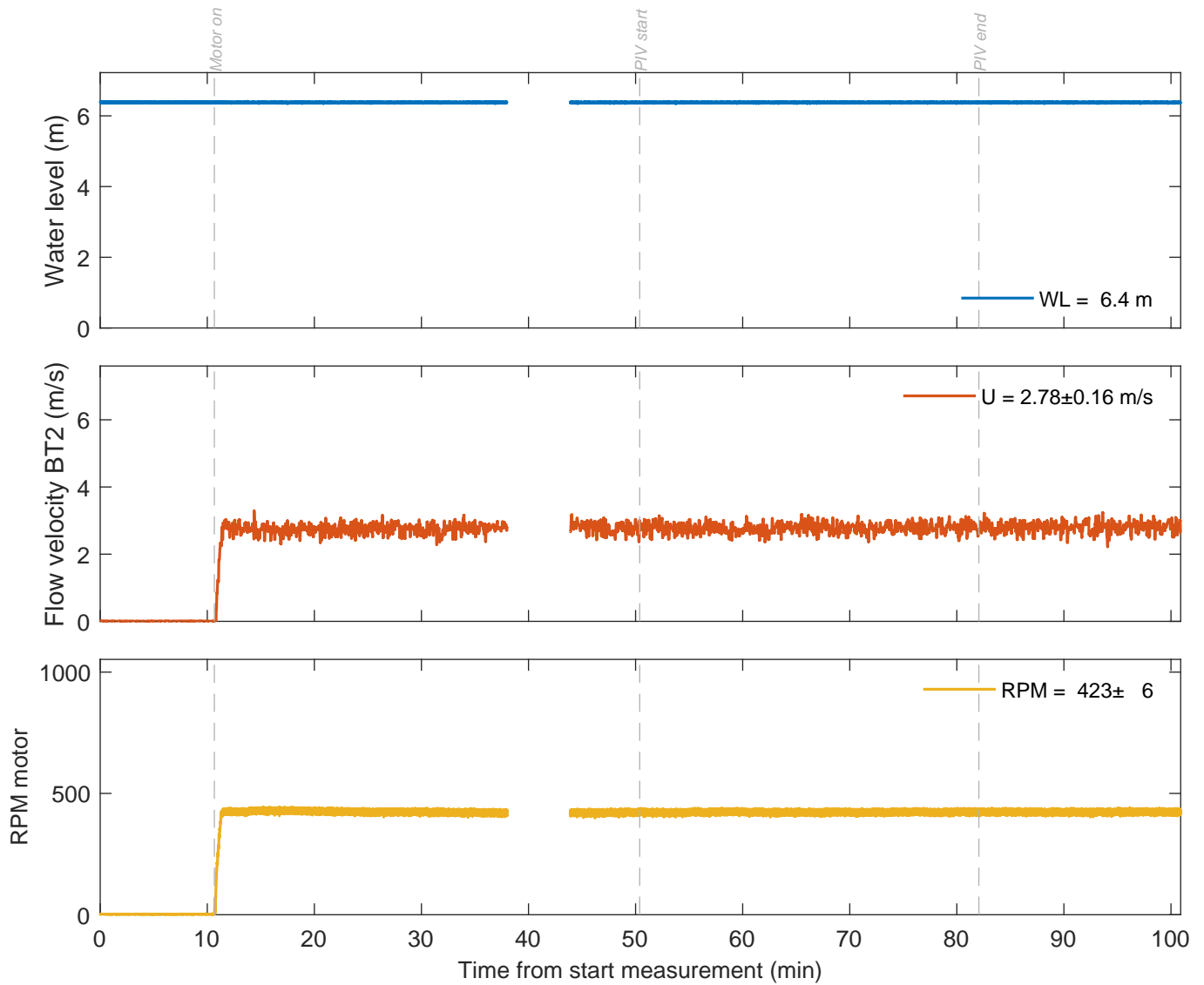
TKI-SOP

PIVSOP133

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 3.0$ m, $\Delta y = -2.0$ m, UKC = 2.5 m, $U_{BT2} = 2.8$ m/s

Measurement
signals

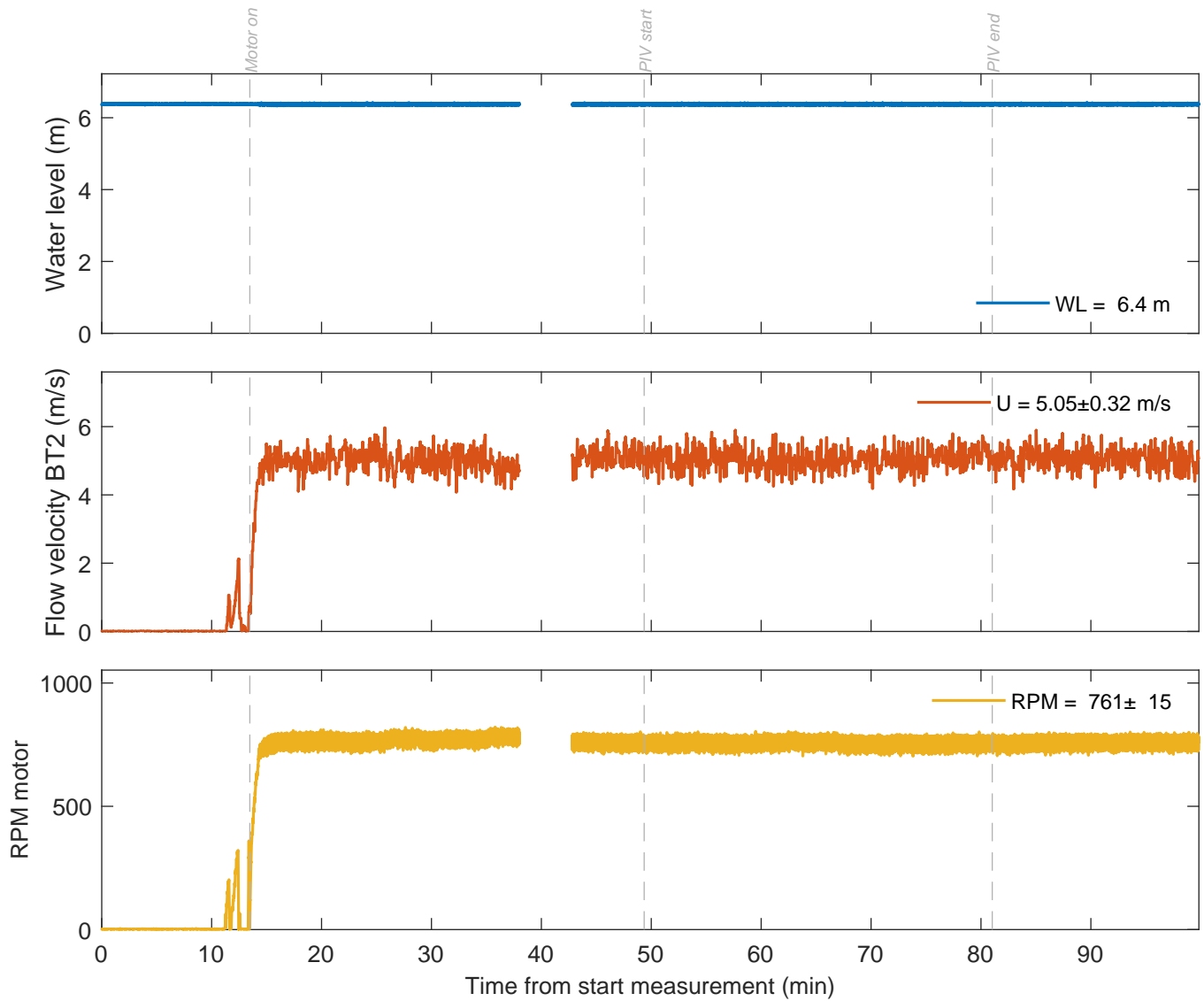
TKI-SOP

PIVSOP135

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 3.0$ m, $\Delta y = -2.0$ m, UKC = 2.5 m, $U_{BT2} = 5.0$ m/s

Measurement
signals

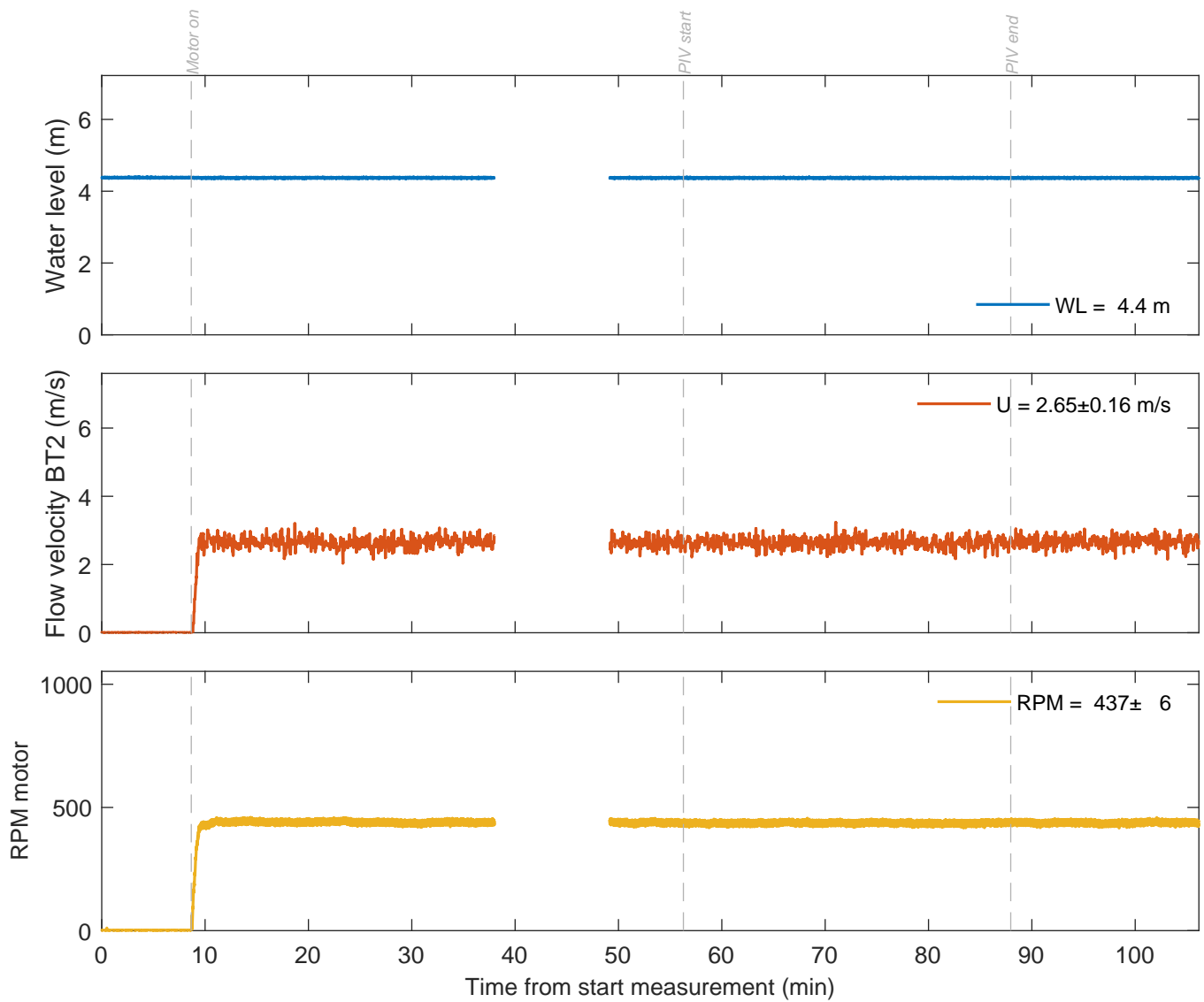
TKI-SOP

PIVSOP137

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 3.0 \text{ m}$, $\Delta y = 0.0 \text{ m}$, UKC = 0.4 m, $U_{BT2} = 2.6 \text{ m/s}$

Measurement
signals

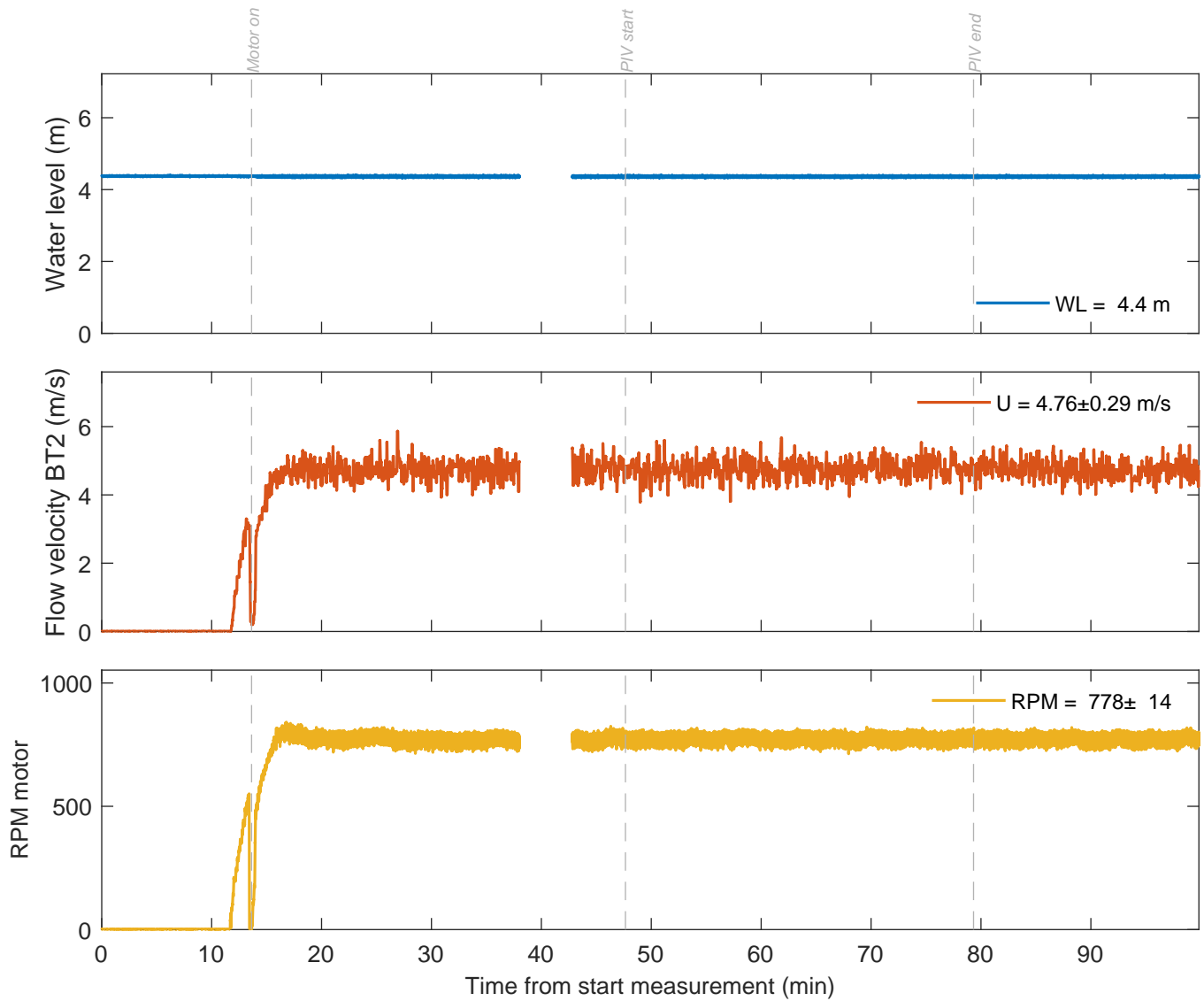
TKI-SOP

PIVSOP140

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 3.0$ m, $\Delta y = 0.0$ m, UKC = 0.4 m, $U_{BT2} = 4.8$ m/s

Measurement
signals

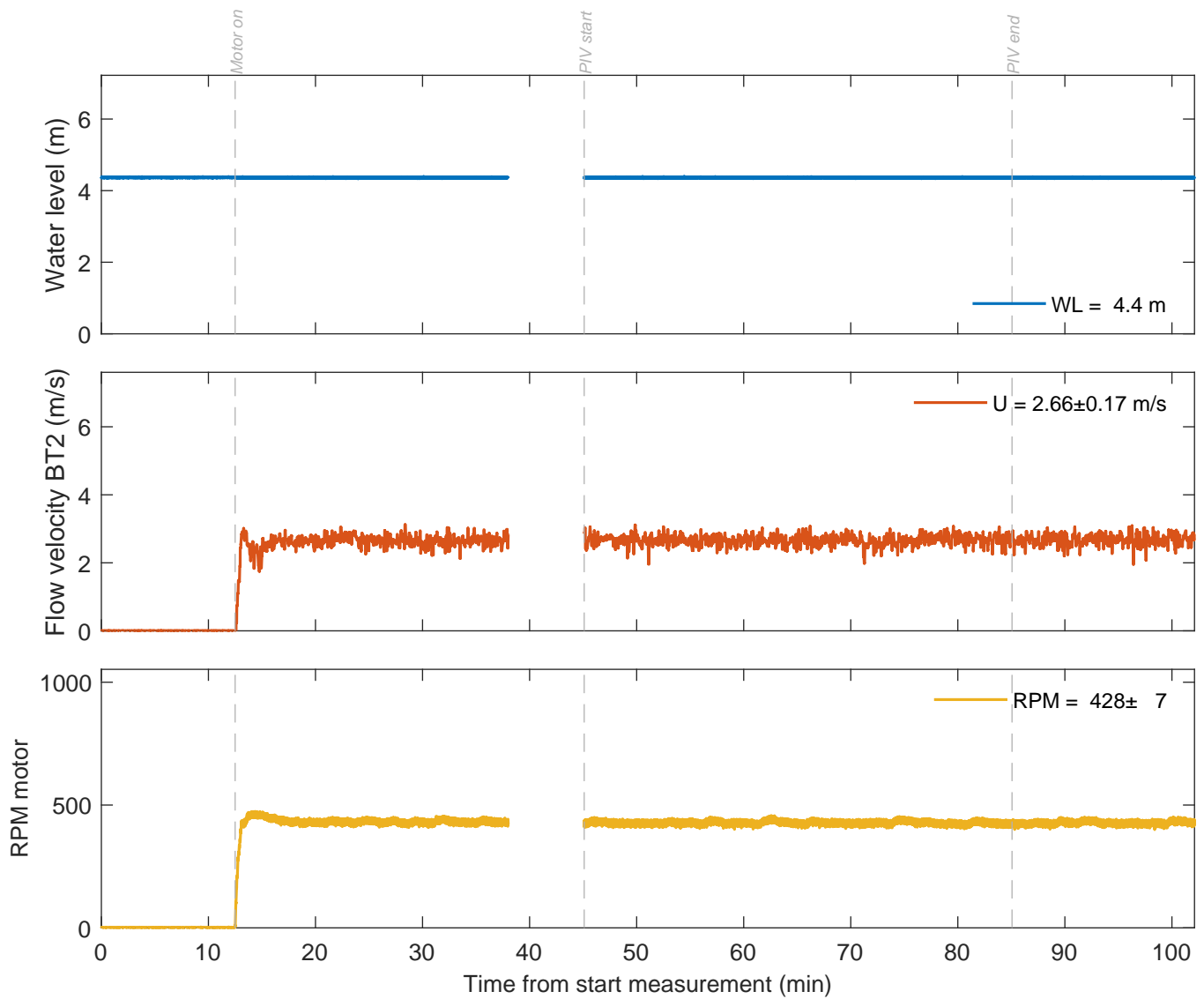
TKI-SOP

PIVSOP142

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 0.4 m, $U_{BT2} = 2.7$ m/s

Measurement
signals

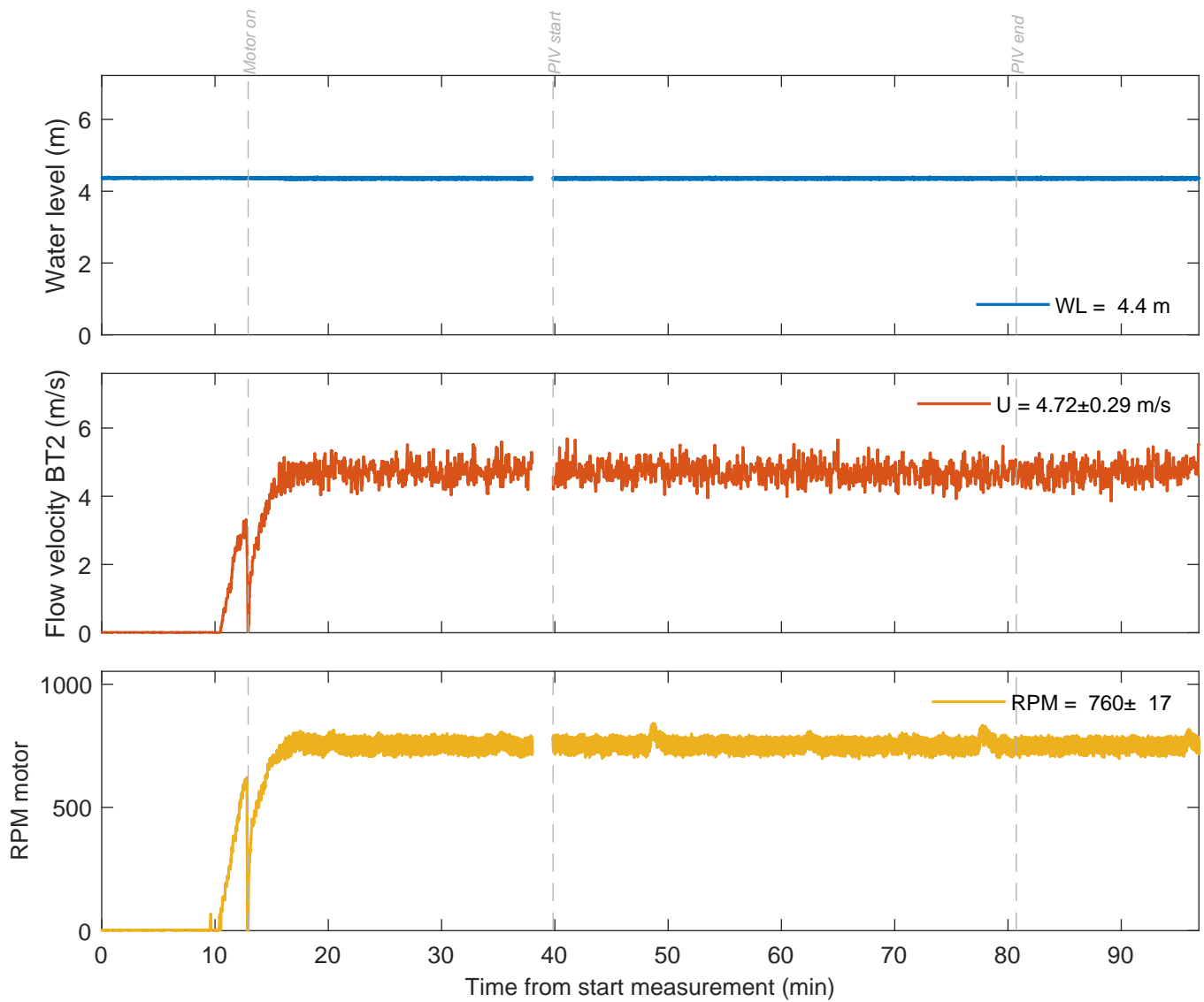
TKI-SOP

PIVSOP144

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 0.4 m, $U_{BT2} = 4.7$ m/s

Measurement
signals

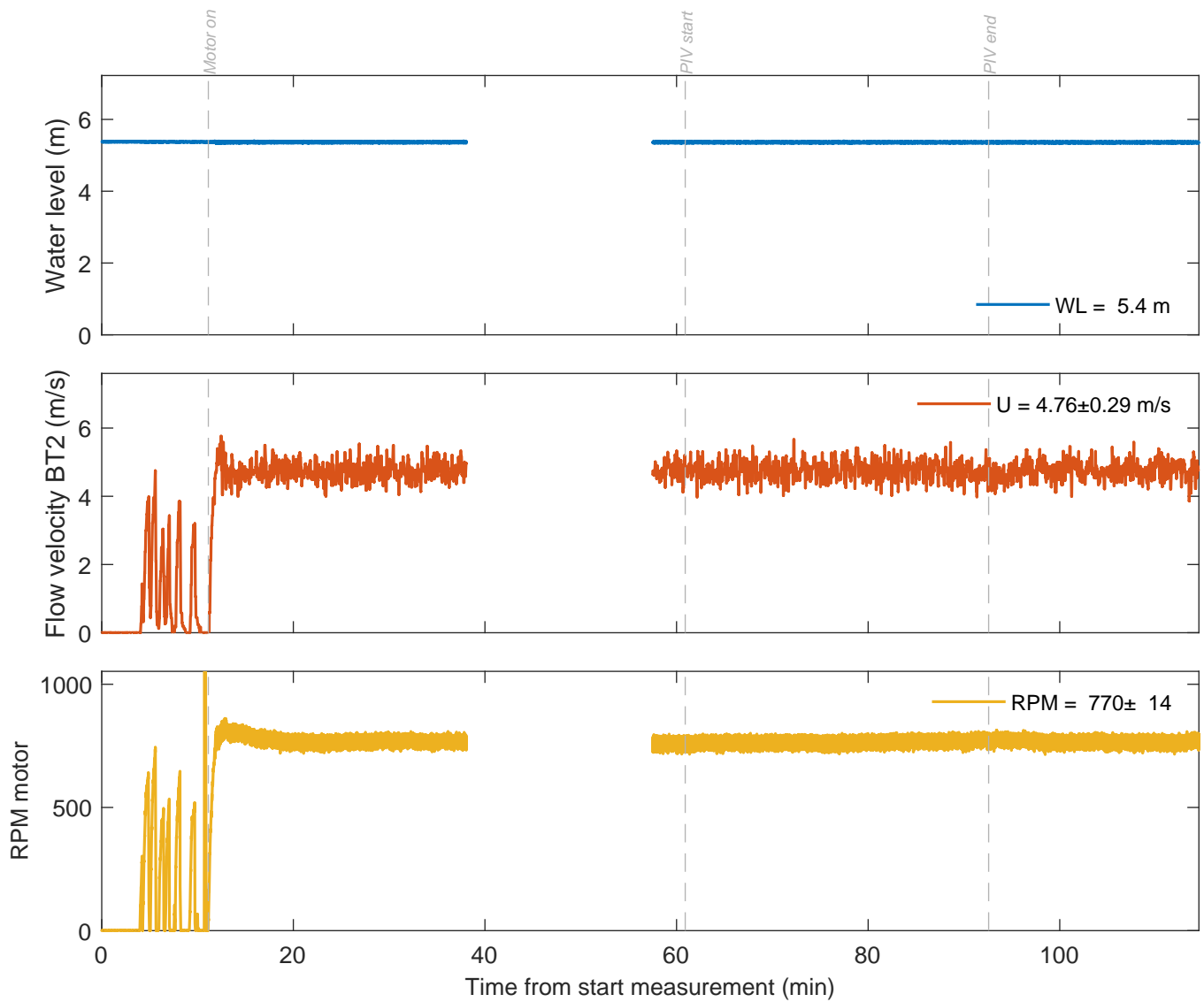
TKI-SOP

PIVSOP146

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 1.4 m, $U_{BT2} = 4.8$ m/s

Measurement
signals

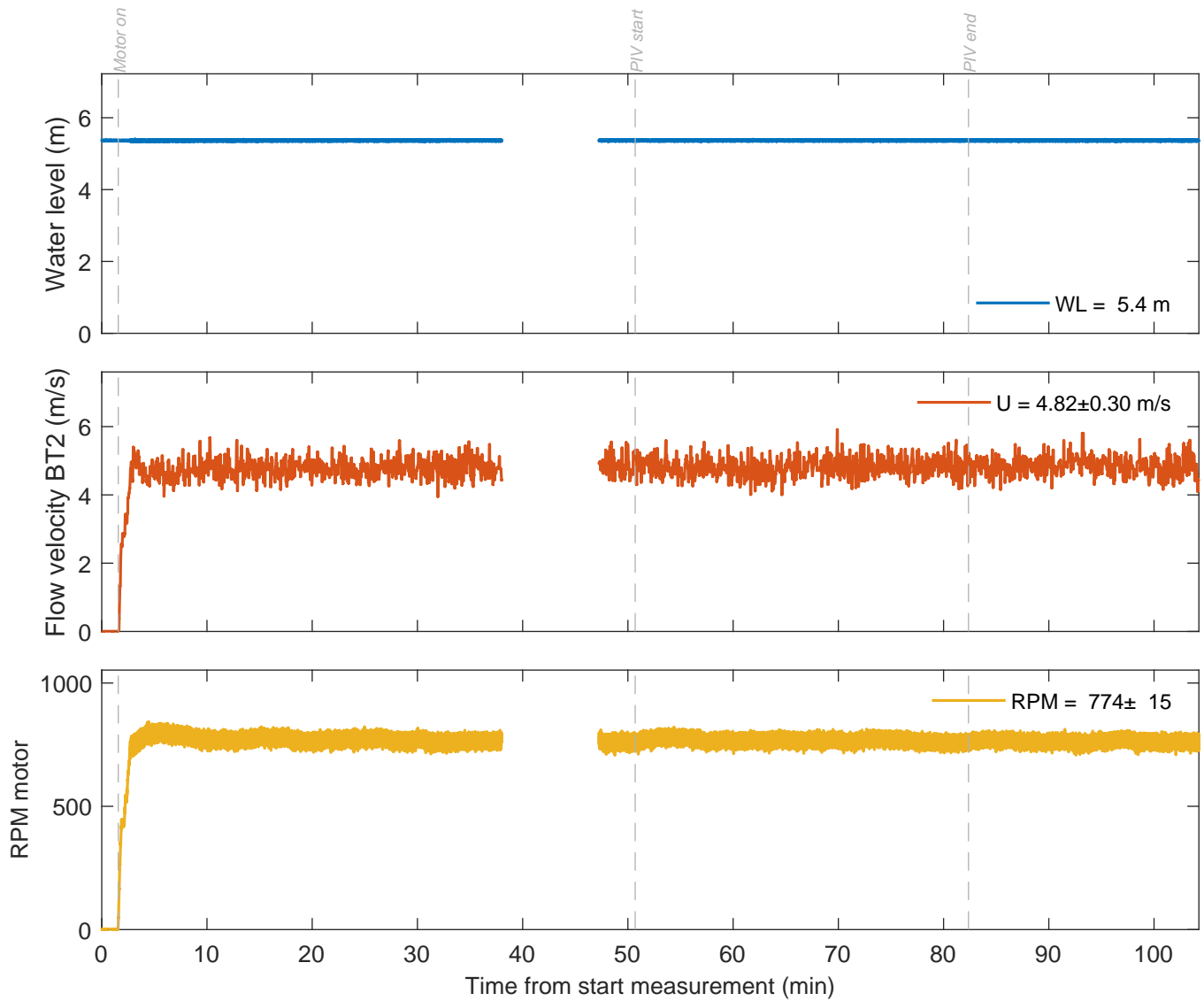
TKI-SOP

PIVSOP150

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 3.0 \text{ m}$, $\Delta y = 0.0 \text{ m}$, UKC = 1.4 m, $U_{BT2} = 4.8 \text{ m/s}$

Measurement
signals

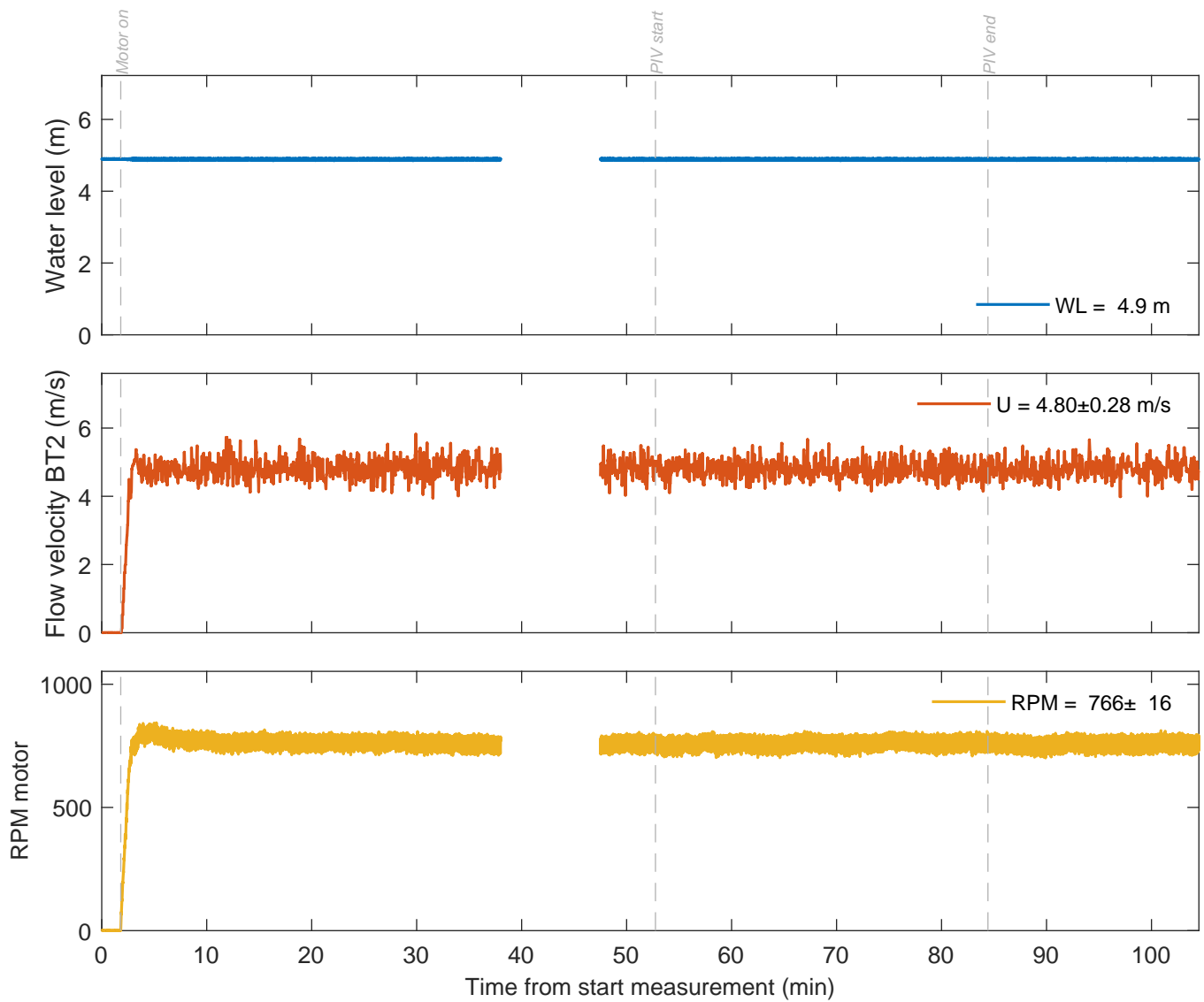
TKI-SOP

PIVSOP154

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 3.0 \text{ m}$, $\Delta y = 0.0 \text{ m}$, UKC = 0.9 m, $U_{\text{BT2}} = 4.8 \text{ m/s}$

Measurement
signals

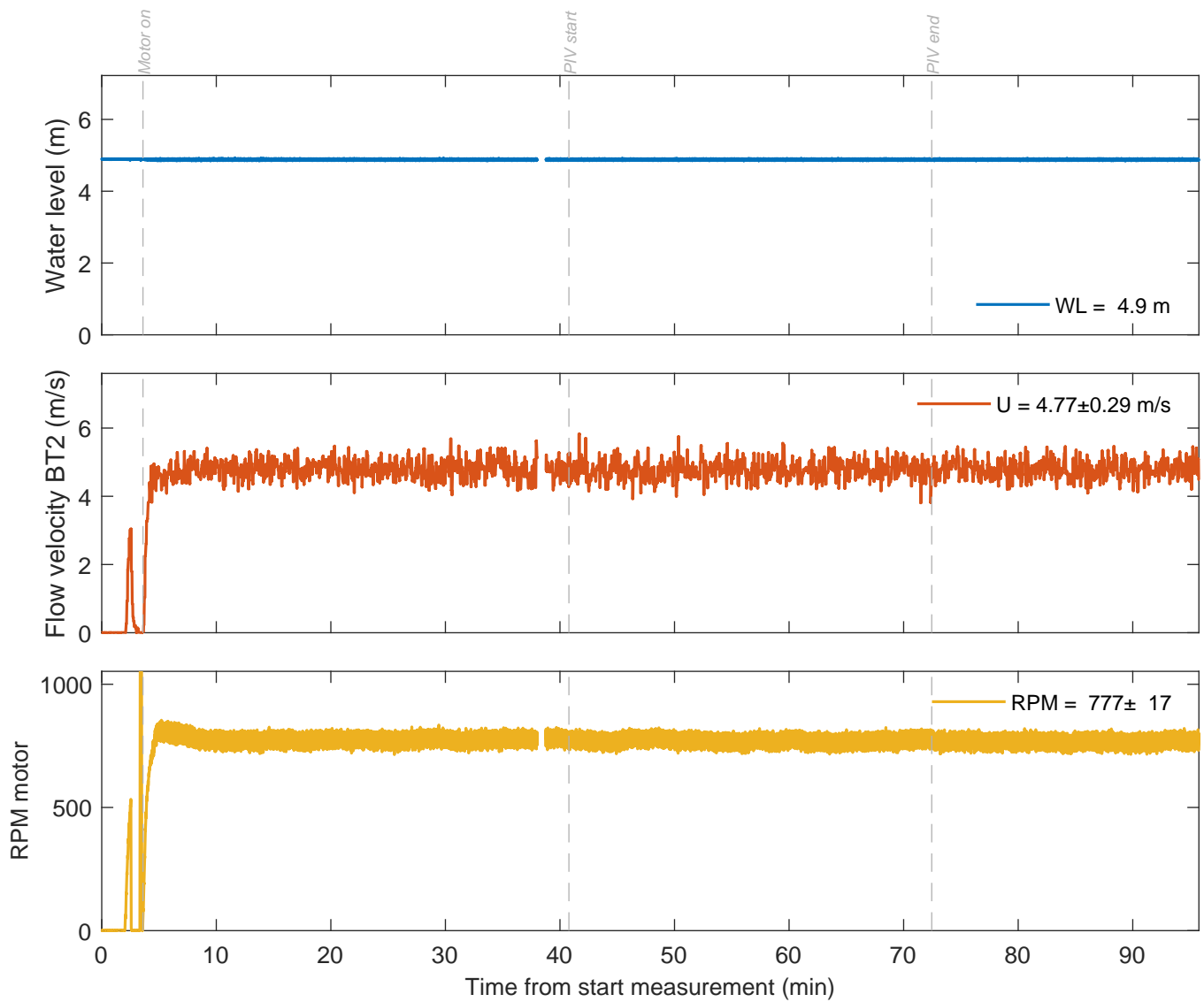
TKI-SOP

PIVSOP158

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 1.0 m, $U_{BT2} = 4.8$ m/s

Measurement
signals

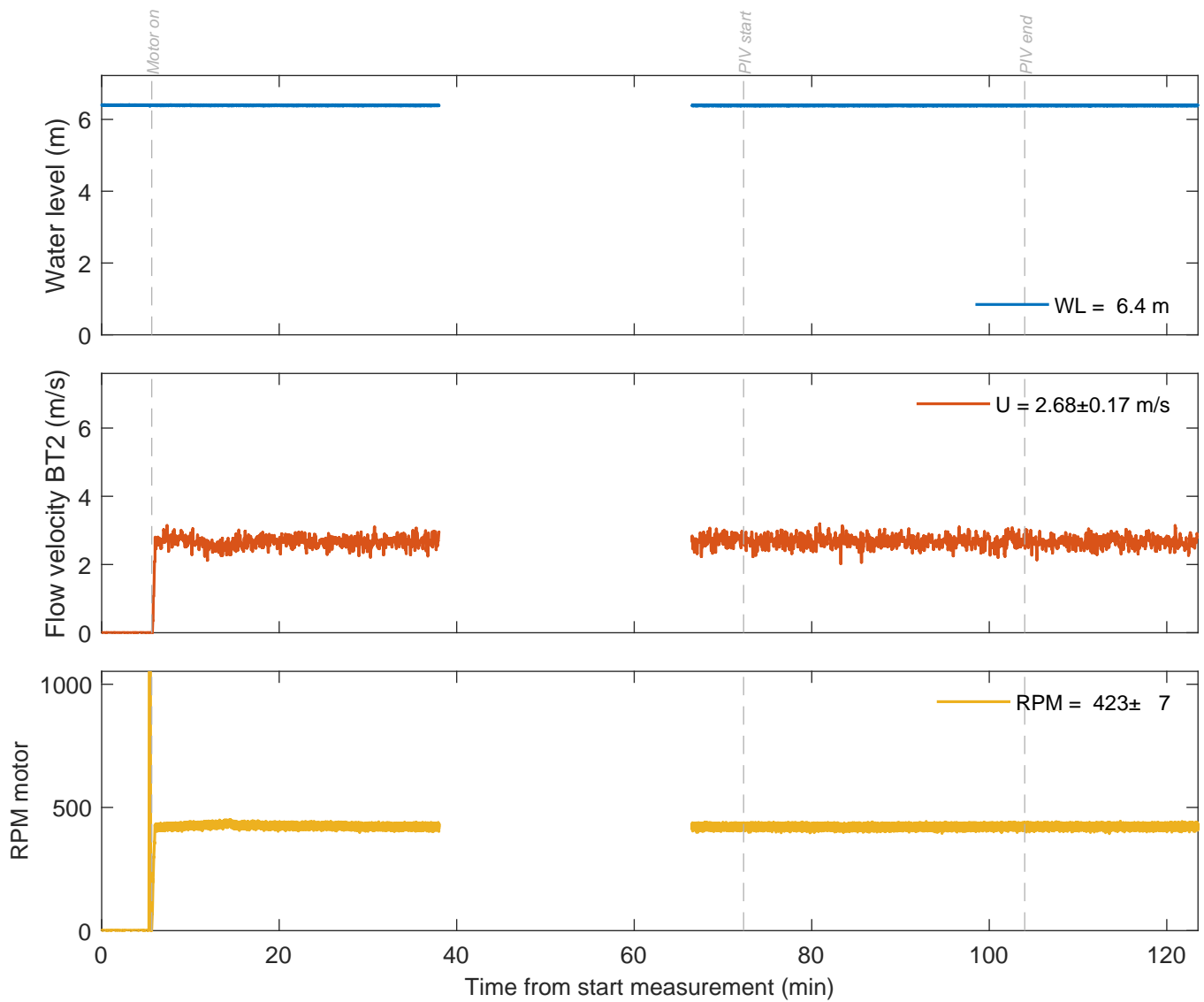
TKI-SOP

PIVSOP162

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.5 m, $U_{BT2} = 2.7$ m/s

Measurement
signals

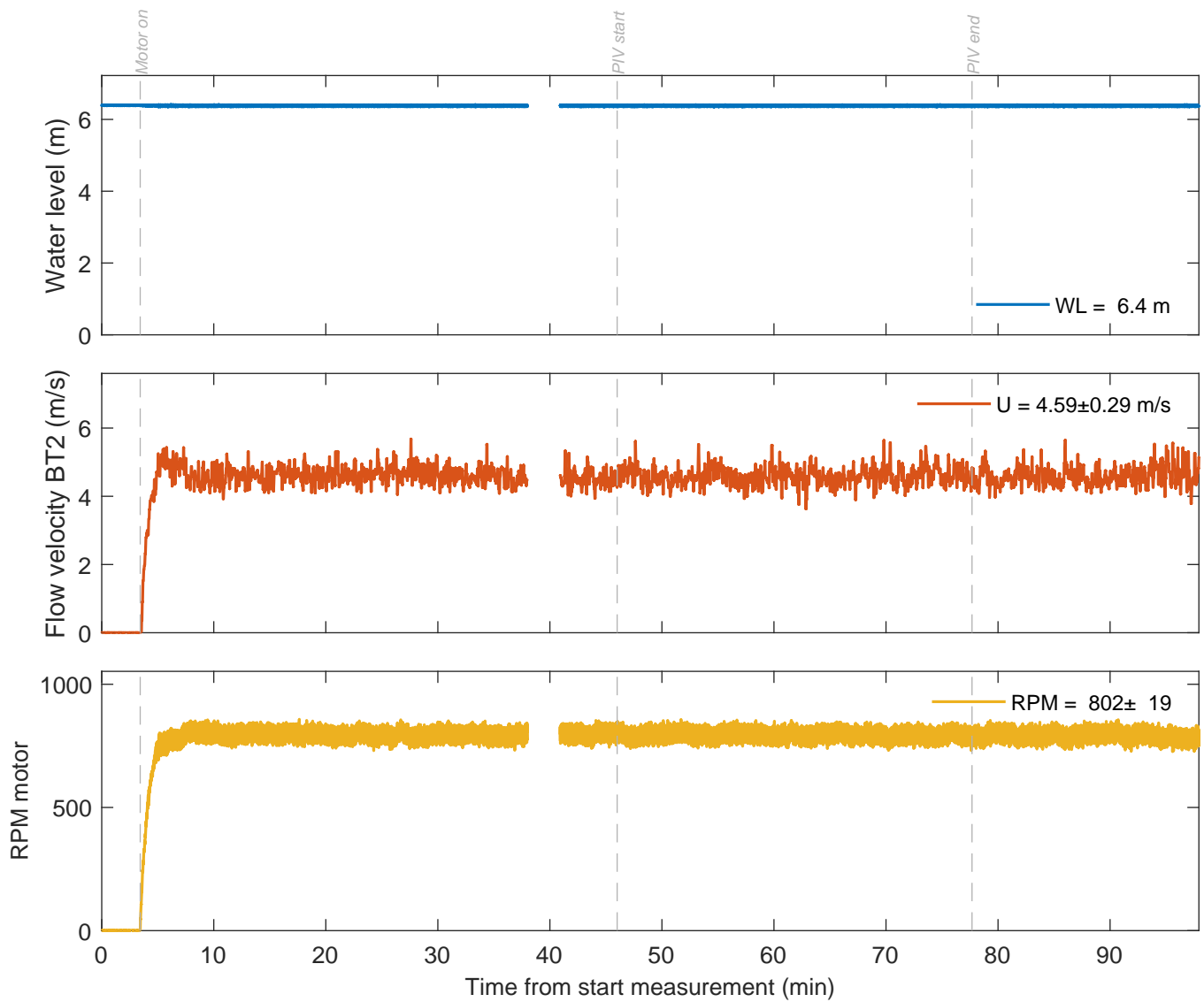
TKI-SOP

PIVSOP166

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.5 m, $U_{BT2} = 4.6$ m/s

Measurement
signals

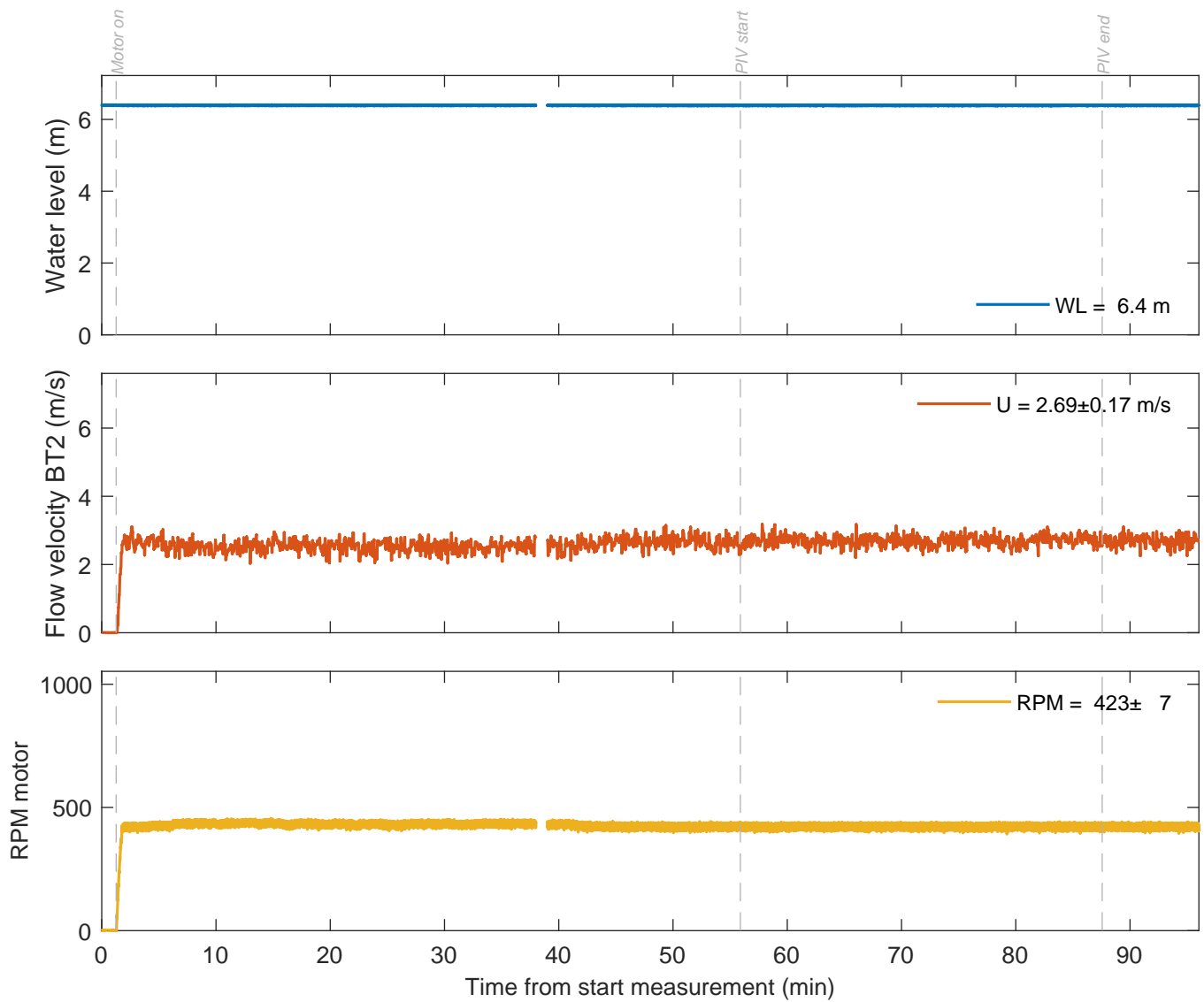
TKI-SOP

PIVSOP168

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8 \text{ m}$, $\Delta y = -2.0 \text{ m}$, $UKC = 2.5 \text{ m}$, $U_{BT2} = 2.7 \text{ m/s}$

Measurement
signals

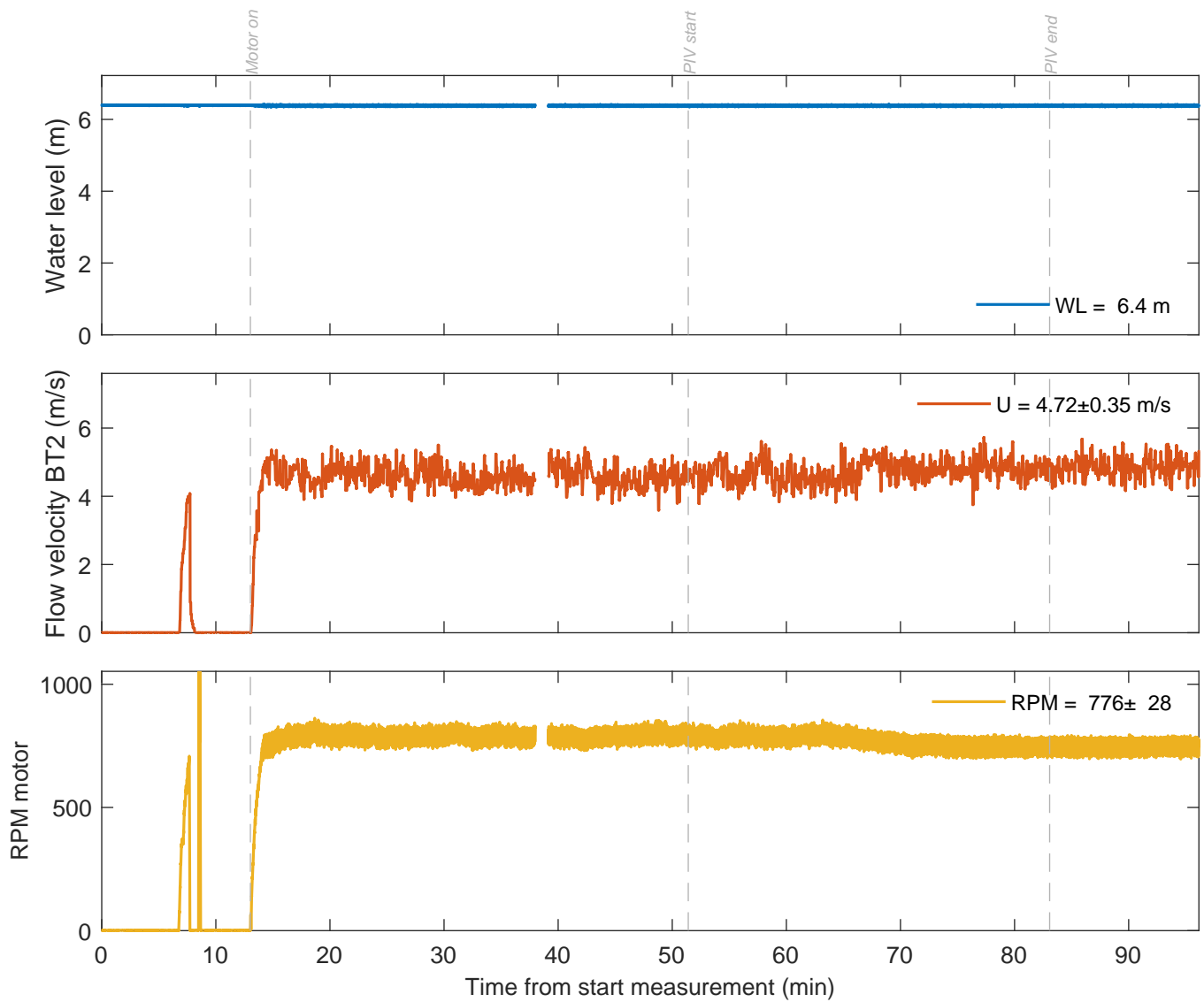
TKI-SOP

PIVSOP172

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = -2.0$ m, UKC = 2.5 m, $U_{BT2} = 4.7$ m/s

Measurement
signals

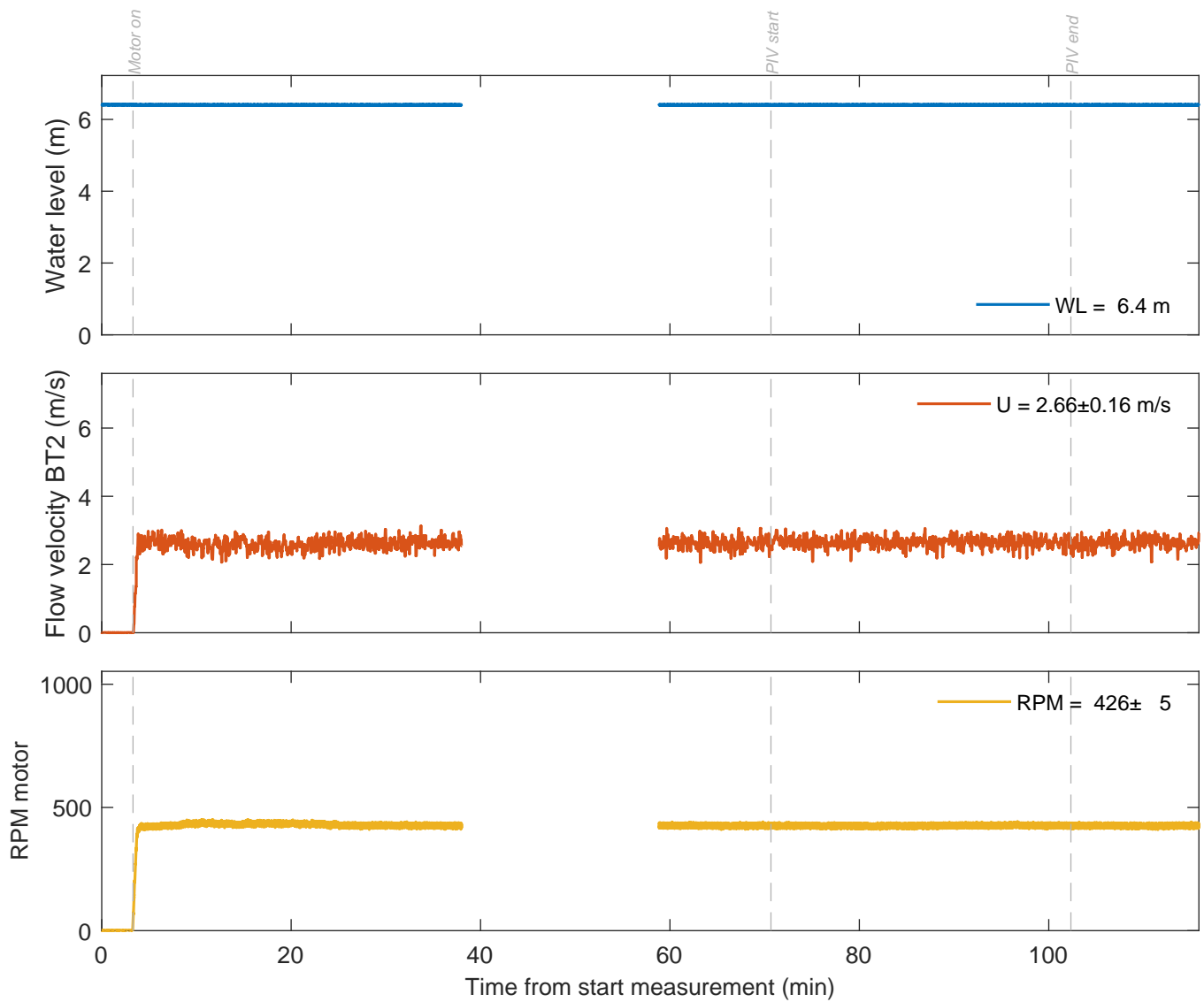
TKI-SOP

PIVSOP174

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.5 m, $U_{BT2} = 2.7$ m/s

Measurement
signals

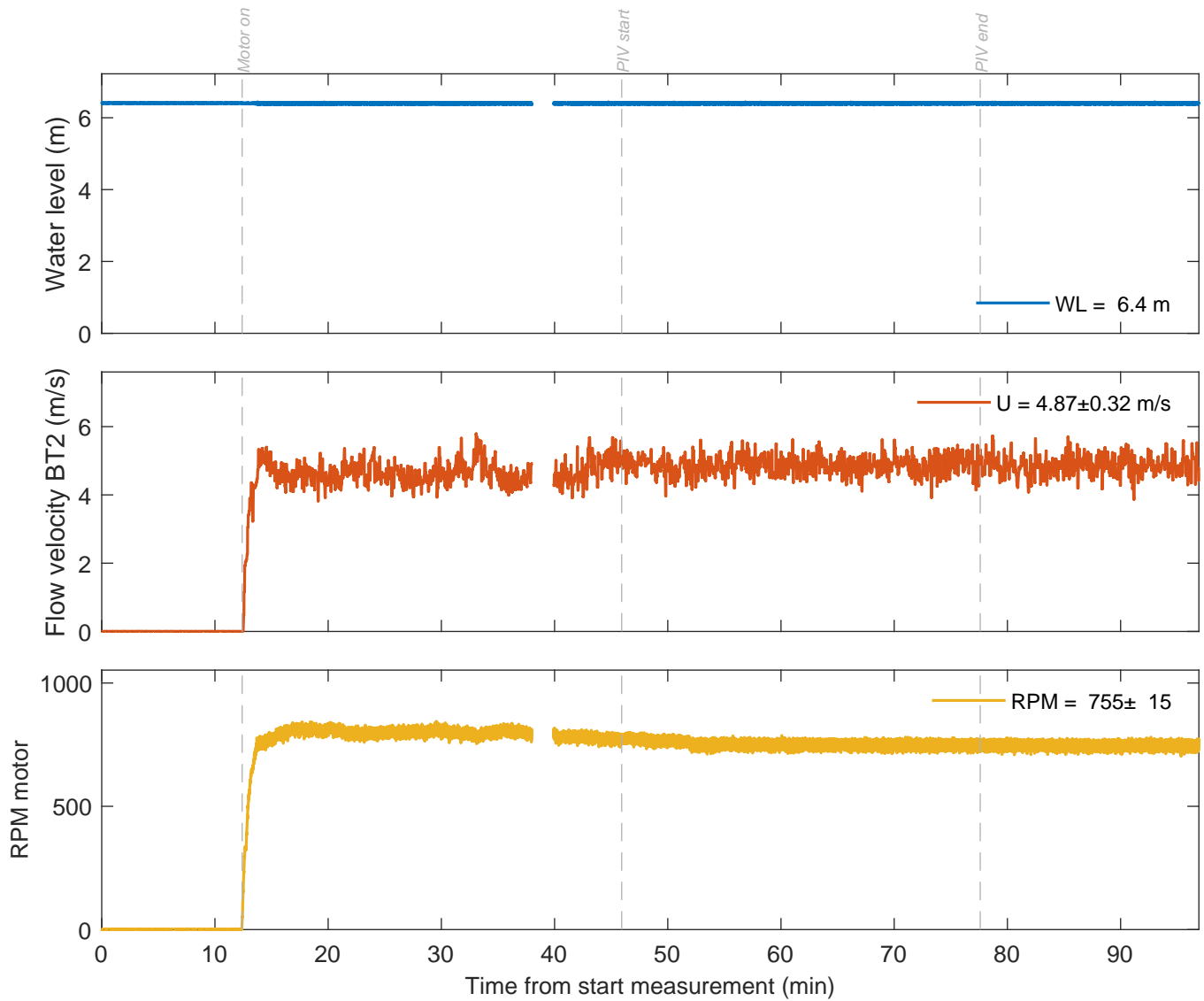
TKI-SOP

PIVSOP178

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.5 m, $U_{BT2} = 4.9$ m/s

Measurement
signals

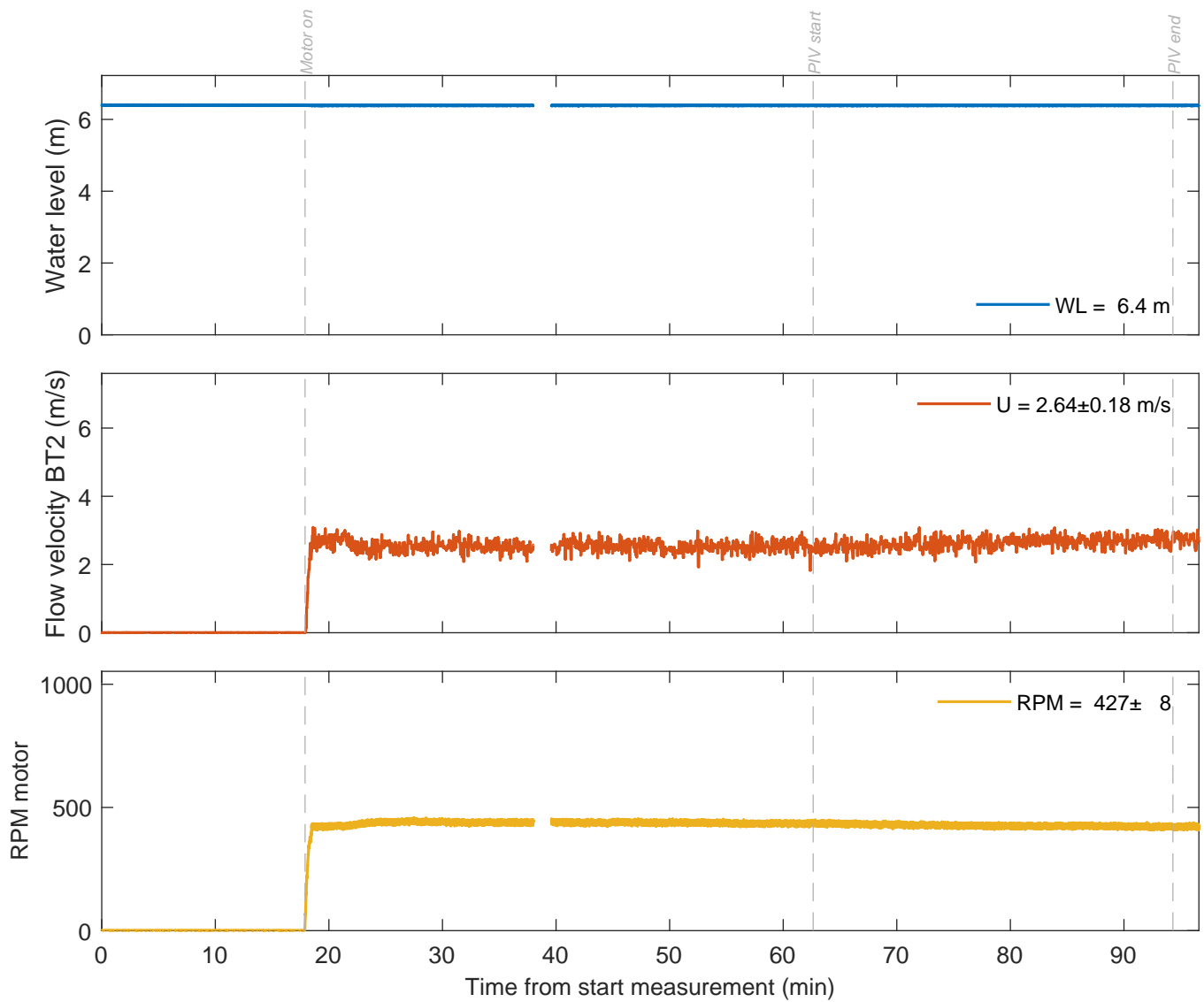
TKI-SOP

PIVSOP180

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.5 m, $U_{BT2} = 2.6$ m/s

Measurement
signals

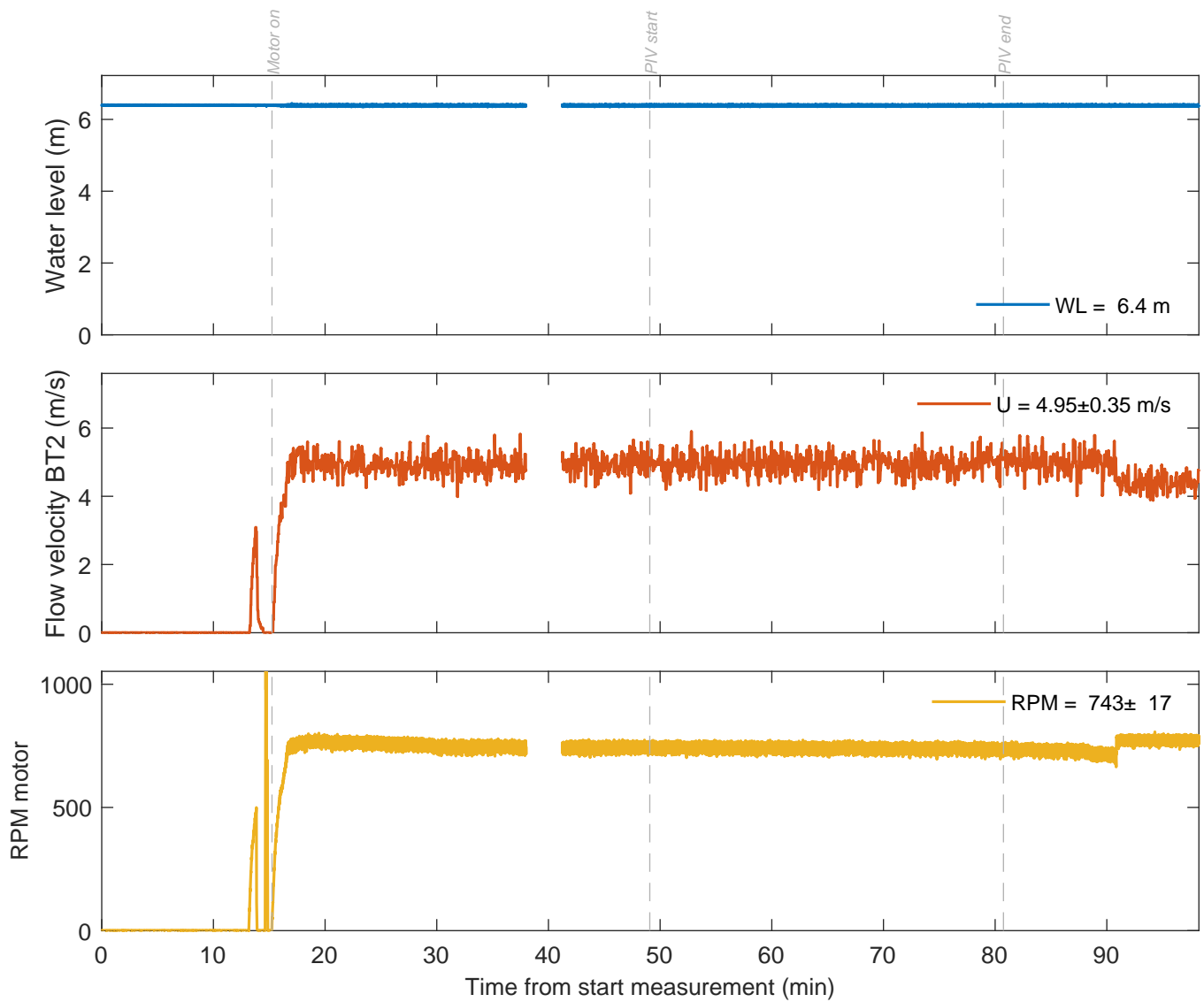
TKI-SOP

PIVSOP183

Deltares

11206641

Fig. D



Water level, flow velocity BT2, RPM motor
 $\Delta x = 0.8$ m, $\Delta y = 0.0$ m, UKC = 2.5 m, $U_{BT2} = 4.9$ m/s

Measurement
signals

TKI-SOP

PIVSOP186

Deltares

11206641

Fig. D