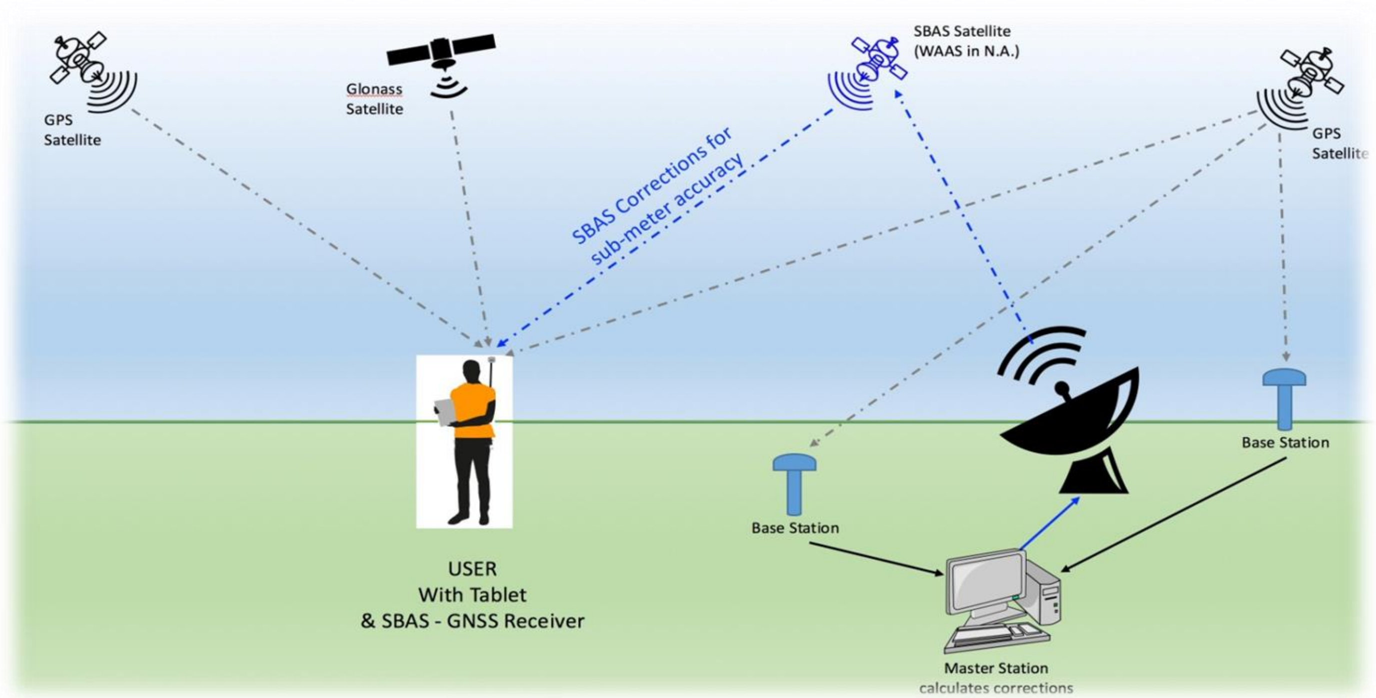
D.G.P.S. SURVEY REPORT FOR

COMPENSATORY AFFORESTATION PLANTATION LAND AGAINST DIVERSION OF 3rd LINE IN BETWEEN PANIAJOB-BORTALAO IN LIEU OF 3rd LINE PROJECT BETWEEN RAJNANDGAON-NAGPUR (KALUMNA)

FOREST DIVISION KHAIRAGARH
DISTRICT RAJNANDGAON
CHHATTISGARH



Applicant

Executive Engineer,
Construction/Rajnandgaon (XEN/CON/RJN),
Chhattisgarh.

Surveyed By

COMPUTER PLUS
Software Development &Consultancy
Devendra Nagar (Raipur),
Chhattisgarh.

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MAPS ON A4, A3 & A0 PAPER SIZE PRINTOUT____________________________

DATA ENCLOSED IN SOFT COPY____

1. ABOUT US

Computer Plus an **ISO 9001:2015 certified** organization working in the field of I.T. Consulting & Software Services. We are registered organization under **Directorate of Geology and Mining, Chhattisgarh**. We are serving since 1998 & head office in Raipur, (C.G.), with core competence in the areas of Integrated Business Solutions with Implementation and Support.

Our Team:

We're justifiably proud of the team we've assembled. Initially numbering just two programmers, **Computer Plus** has grown steadily and now has over 250 staff members. The **Computer Plus** team is made up of highly-qualified, talented and innovative IT and GIS professionals each with their own area of expertise. Their experience spans the full range of custom software development, from small entrepreneurial projects to complex systems for major corporations.

Our Mission:

Computer Plus's mission is to solve challenging technical problems in partnership with our clients.
How we achieve it:

- We understand the business needs of our clients, and how technology can be a tool to make modern businesses more profitable for both private and government sector.
- **Computer Plus** combines technical excellence with great customer service and value for money.
- We value creativity and collaboration; ideas are shared and everybody contributes on an individual basis toward the common goal.

We create new teams for each project, ensuring the best possible combination of skills and experience to meet the client's needs and deliver high quality solutions.

2. LOCATION OF SURVEY SITE

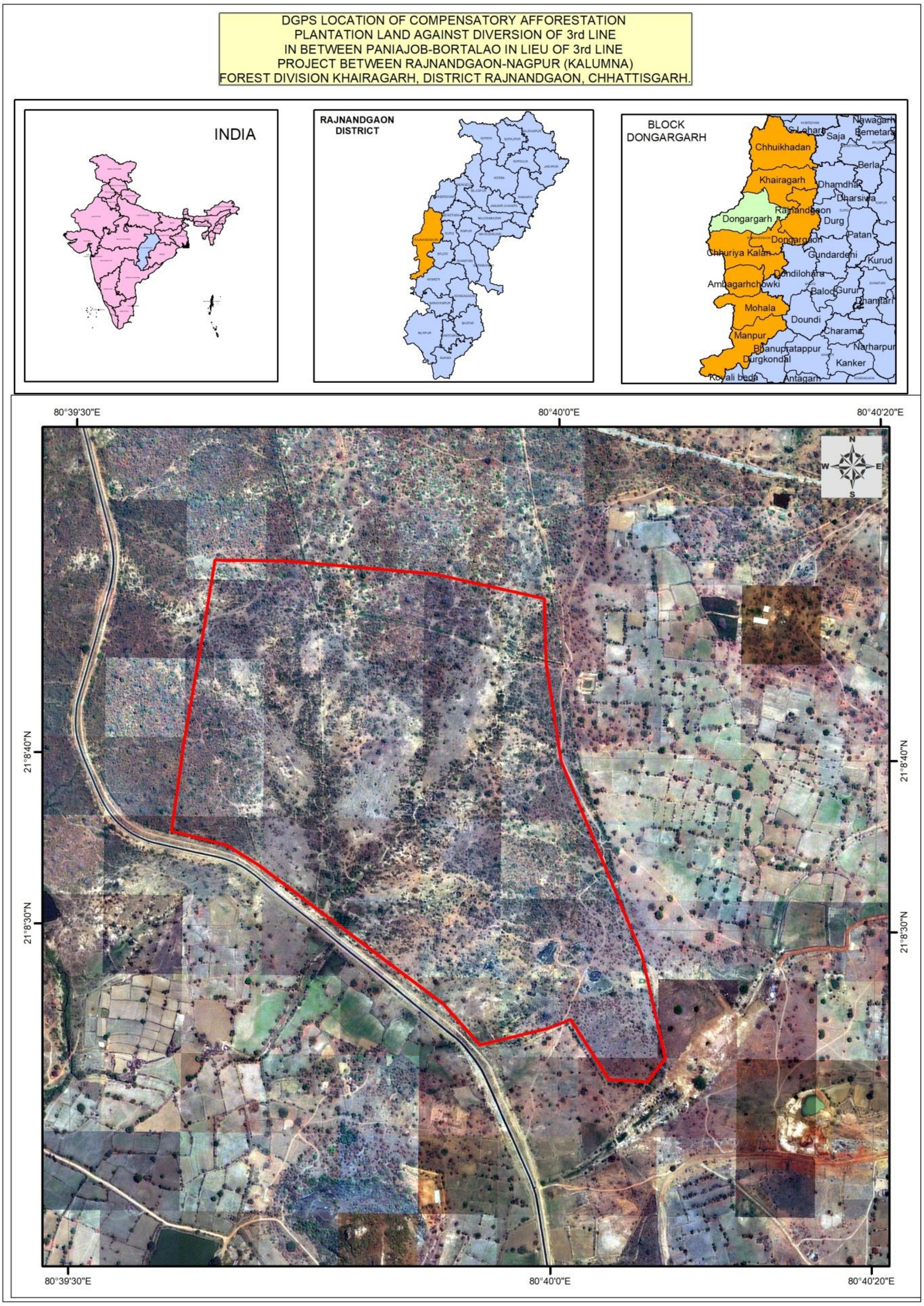
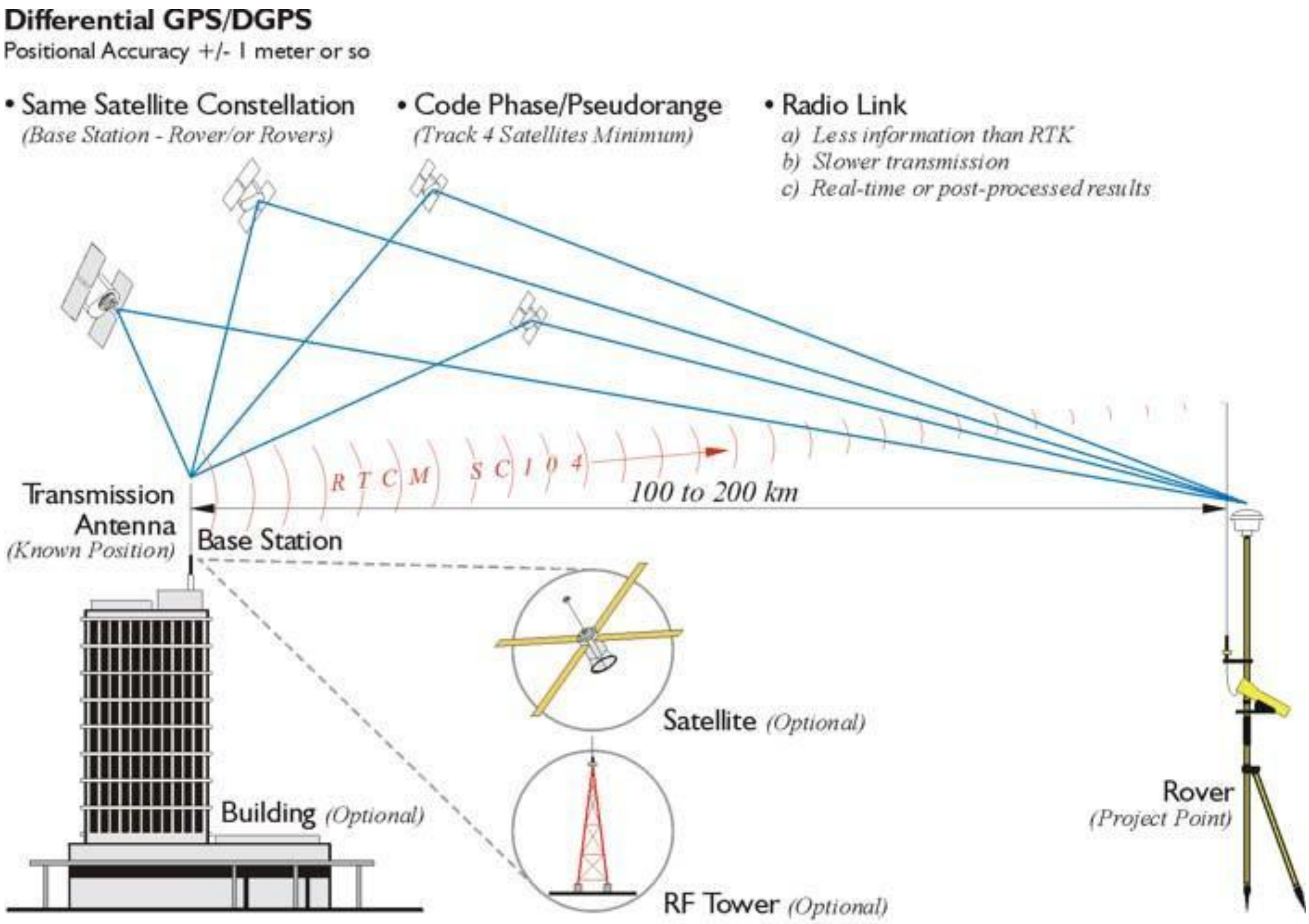


Fig: 1. Location Map of the area

3. INTRODUCTION TO DGPS



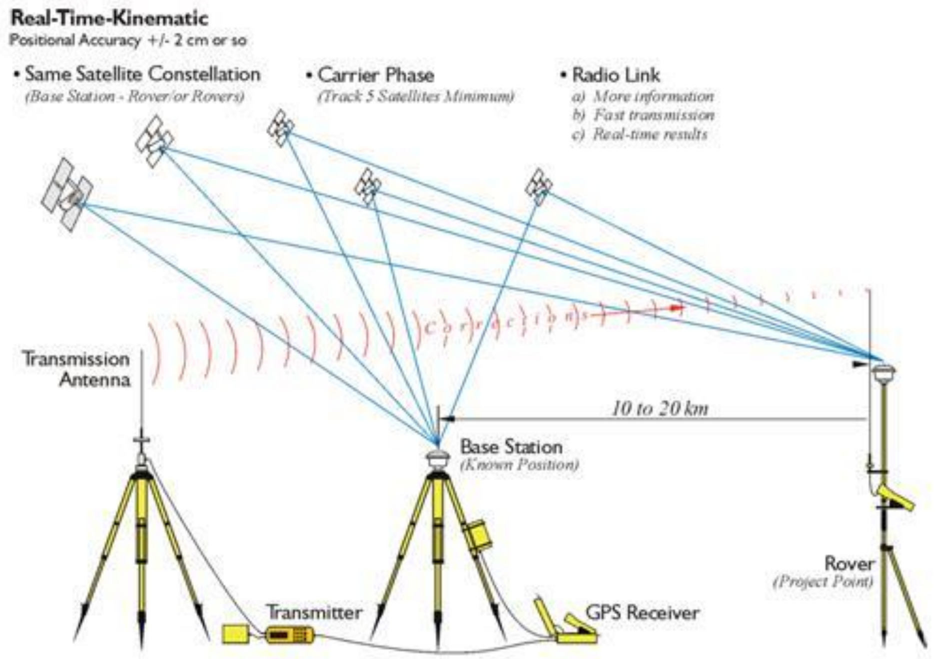
The term DGPS is sometimes used to refer to differential GPS that is based on pseudo ranges, aka code phase. Even though the accuracy of code phase applications was given a boost with the elimination of Selective Availability (SA) in May 2000 consistent accuracy better than the 2-5-meter range still requires reduction of the effect of correlated ephemeris and atmospheric errors by differential corrections. Though the corrections could be applied in post-processing services that supply these corrections, most often operate in real-time. In such an operation pseudo range-based version can offer meter- or even sub meter results.

Usually, pseudo range corrections are broadcast from the base to the rover or rovers for each satellite in the visible constellation. Rovers with an appropriate input/output (I/O) port can receive the correction signal and calculate coordinates. The real-time signal comes to the receiver over a data link. It can originate at a project specific base station or it can come to the user through a service of which there are various categories. Some are open to all users and some are by subscription only. Coverage depends on the spacing of the beacons, aka transmitting base stations, their power, interference, and so forth. Some systems require two-way, some one-way, communication with the base stations. Radio systems, geostationary satellites, low-earth-orbiting.

SURVEY METHOD

1) RTK (Real Time Kinematic)

A. Real-time Kinematic



Most, not all, GPS surveying relies on the idea of differential positioning. The mode of a base or reference receiver at a known location logging data at the same time as a receiver at an unknown location together provide the fundamental information for the determination of accurate coordinates. While this basic approach remains today, the majority of GPS surveying is not done in the static post-processed mode. Post-processing is most often applied to control work. Now, the most commonly used methods utilize receivers on reference stations that provide correction signals to the end user via a data link sometimes over the Internet, radio signal, or cell phone and often in real-time.

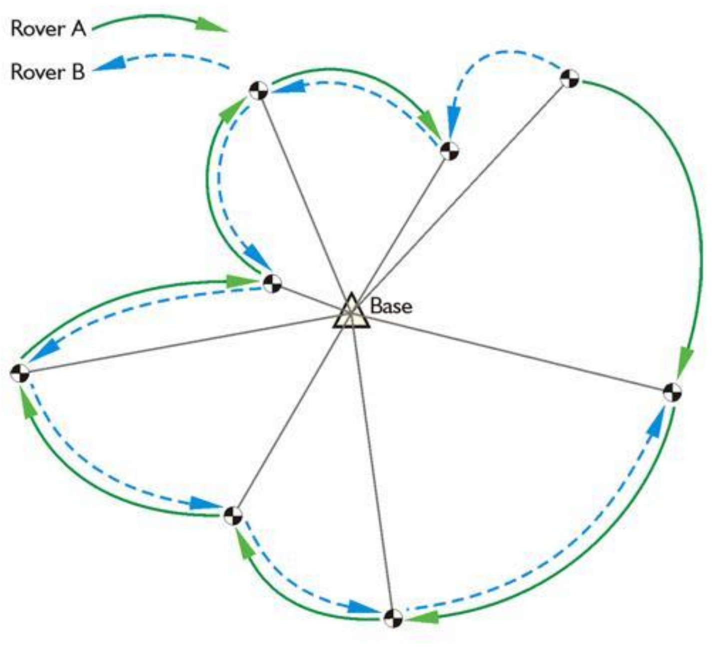
In this category of GPS surveying work there is sometimes a distinction made between code- based and carrier-based solutions. In fact, most systems use a combination of code and carrier measurements so the distinction is more a matter of emphasis rather than an absolute difference. Well that's a bit of discussion about static surveying, but as you know, a good deal of GPS these days is done not static. Much work is now done with DGPS or real-time kinematic, RTK.

Errors in satellite clocks, imperfect orbits, the trip through the layers of the atmosphere, and many other sources contribute inaccuracies to GPS signals by the time they reach a receiver.

These errors are variable, so the best to way to correct them is to monitor them as they happen. A good way to do this is to set up a GPS receiver on a station whose position is known exactly, a base station. This base station receiver's computer can calculate its position from satellite data, compare that position with its actual known position, and find the difference. The resulting error corrections can be communicated from the base to the rover. It works well, but the errors are constantly changing so a base station has to monitor them all the time, at least all the time the rover receiver or receivers are working. While this is happening, the rovers move from place to place collecting the points whose positions you want to know relative to the base station, which is the real objective after all. Then all you have to do is get those base station corrections and the rover's data together somehow. That combination can be done over a data link in real-time, or applied later in post processing.

Real-time positioning is built on the foundation of the idea that, with the important exceptions of multipath and receiver noise, GPS error sources are correlated. In other words, the closer the rover is to the base the more the errors at the ends of the baseline match. The shorter the baseline, the more the errors are correlated. The longer the baseline, the less the errors are correlated.

The base station is at a known point, whether it was on a building permanently or it's a tripod mounted base station. The fact that it is in a known position allows the base station to produce corrections. The constellation is telling the base station that it is in a slightly different place, so corrections can be created to send to the rover at the unknown point. The corrections are applied in real time.



RADIAL GPS

Such real-time surveying is essentially radial. There are advantages to the approach. The advantage is a large number of positions can be established in a short amount of time with little or no planning. The disadvantage is that there is little or no redundancy in positions derived, each of the baselines originates from the same control station. Redundancy can be incorporated, but it requires repetition of the observations so each baseline is determined with more than one GPS constellation. One way to do it is to occupy the project points, the unknown positions, successively with more than one rover. It is best if these successive occupations are separated by at least 4 hours and not more than 8 hours so the satellite constellation can reach a significantly different configuration.

RTK and DGPS are radial. You have a known point in the middle, the base, and then the unknown points around it. This provides little geometric solidity. If there's an error in one of these radial base lines, it would be tough to catch it because there's no real redundancy. The illustration shows a way around this difficulty. There are two receivers, A and B, and it's possible by double occupation, one receiver going one way and the other going the other, by double occupying the unknown points to get some redundancy and some checks against the positions from a base. Another way to do it is to use one receiver. That receiver would occupy each point twice with four to eight hours between the first occupation and the second occupation on the point. Another way is to move the base to another known point. Then if you have vectors from another base into these points, you have a check. This approach allows a solution to be available from two separate control stations. Obviously, this can be done with re-occupation of the project points after one base station has been moved to a new control point, or two base stations can be up and running from the very outset and throughout of the work as would be the case using two CORS stations. It is best if there are both two occupations on each point and each of the two utilize different base stations.

A more convenient but less desirable approach is to do a second occupation almost immediately after the first. The roving receiver’s antenna is blocked or tilted until the lock on the satellites is interrupted. It is then re-oriented on the unknown position a second time for the repeat solution. This does offer a second solution, but from virtually the same constellation.

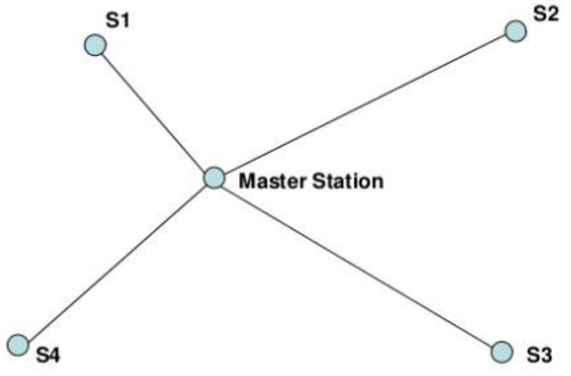
More efficiency can be achieved by adding additional roving receivers. However, as the number of receivers rises, the logistics become more complicated, and a survey plan becomes necessary. Also, project points that are simultaneously near one another but far from the control station should be directly connected with a baseline to maintain the integrity of the survey. Finally, if the base receiver loses lock and it goes unnoticed, it will completely defeat the radial survey for the time it is down.

These are a few possibilities to consider when you are doing a real-time survey.

An advantage to continuously operating reference station network is that since those bases are operating simultaneously and all the time, it's possible to download the positions from more than one base and process your new position based on these continuously operating reference stations and have some redundancy.

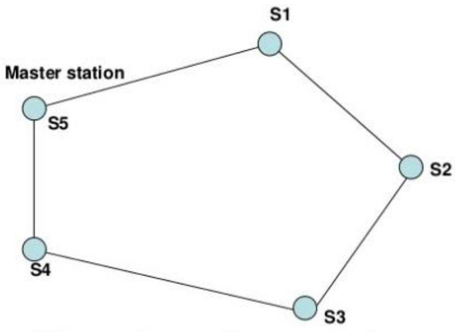
2) STATIC METHOD

I. Rapid Static Method



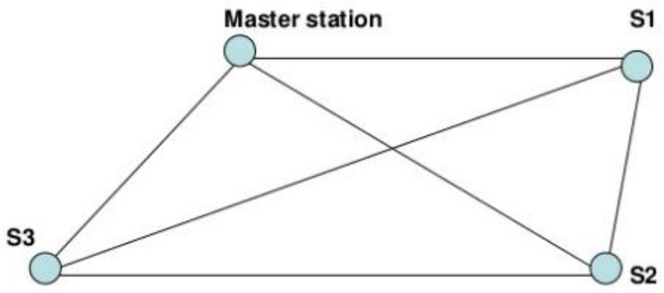
Schematic diagram of Rapid Static Method

II.Traverse Method



Schematic diagram of Traverse method

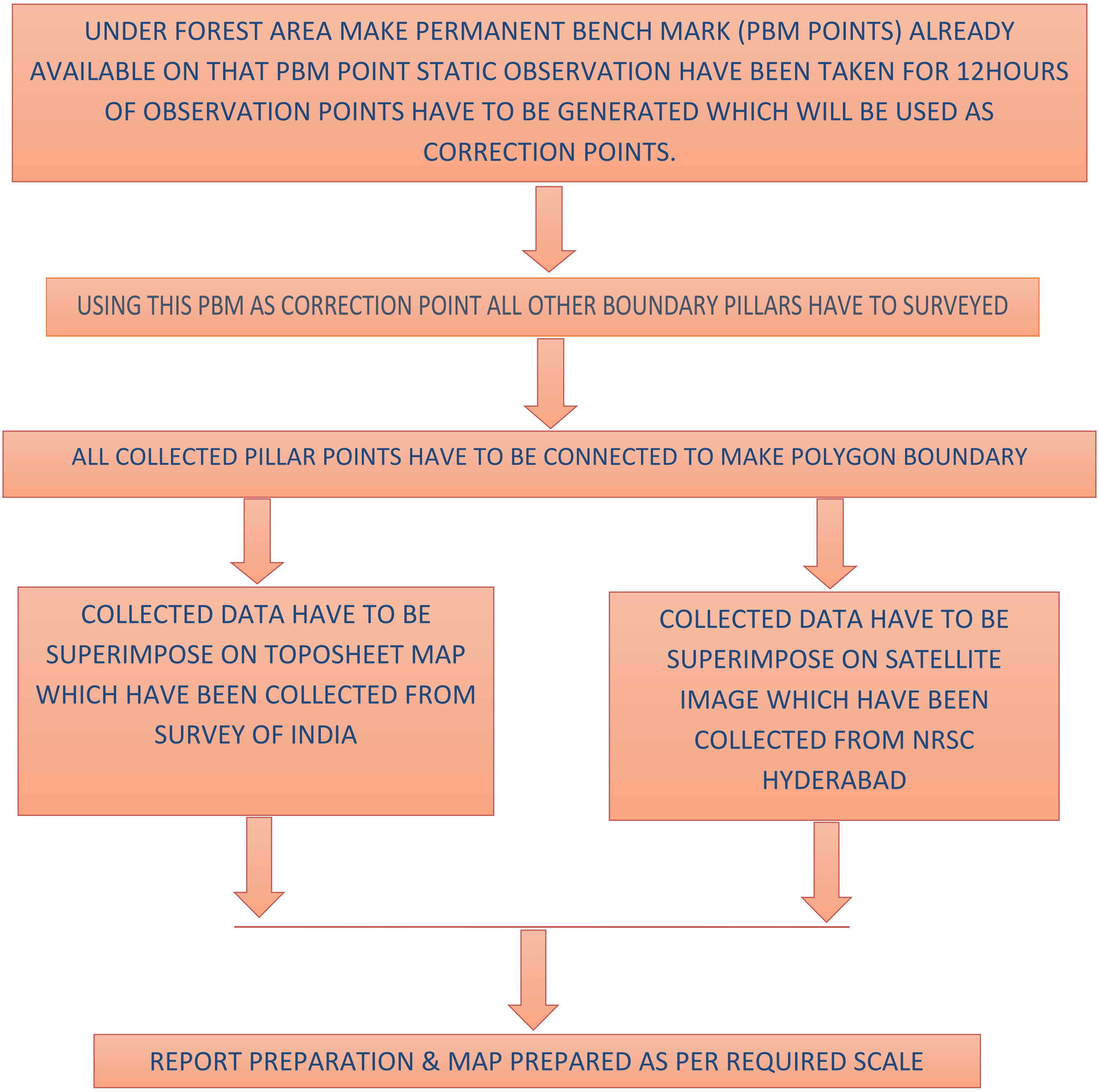
III. Trilateration Method



Trilateration method

4. METHODOLOGY USED

Following Methodology have been adopted for DGPS Survey of the proposed site.



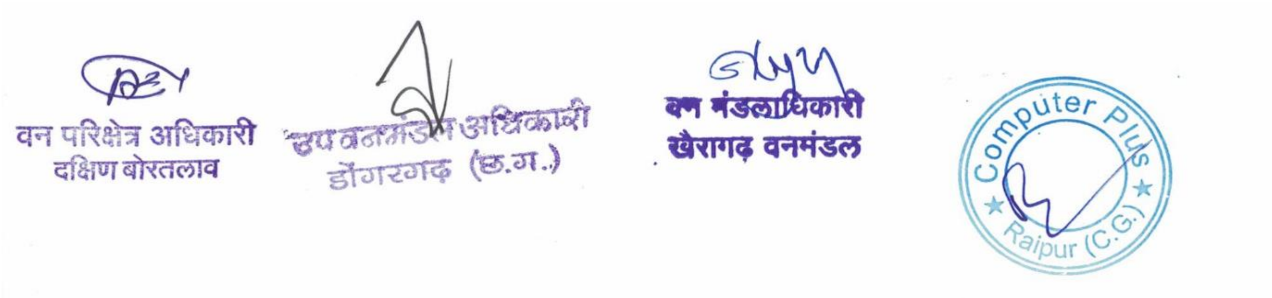
5. DETAILS OF SURVEYED SITE

The surveyed area for **Compensatory Afforestation Plantation Land Against Diversion of 3rd Line in Between Paniajob-Bortalab In Lieu of 3rd Line Project Between Rajnandgaon-Nagpur (kalumna)** which comes under **Block Dongargarh, District Rajnandgaon, and Chhattisgarh**. Dongargarh New Bus Stand longitude latitude is **80°44'55.09"E 21°11'25.67"N.** Survey site is located **15.8** Km from **Dongargarh New Bus Stand**. Survey site comes under **Forest Division Khairagarh**, **Forest Range South Bortalab and Forest** Circle **Durg.**

It is covered in Survey of India Toposheet No. 64C12.

Details of area surveyed and land details are given below:

S.NO.	District Name	Forest Division Name	Range Name	Forest Type	Compartment No.	Area (In Hectare)
1	Rajnandgaon	Khairagarh	South Bortalab	Protected Forest	P 465	50.000
TOTAL						**50.000**



6. CONTROL POINT

Primary Control Point (Fixing of Base Station Point)

Details of primary control points used for fixing of Base Station Point are given below.

Primary Control Point (Fixing of Base Station Point)

Sr.No.	Geographical Coordinates		UTM Coordinates		Height
	Longitude "E"	Latitude "N"	Easting (m)	Northing (m)	
1	80°39' 57.445" E	21°8' 27.080" N	465315.825000	2337773.098000	306.083
2	80°39' 54.937" E	21°8' 53.621" N	465245.204000	2338589.215000	356.275

Surveyed Ground Control Points

Sr.No.	Compartment No.	Geographical Co-ordinates		UTM Co-ordinates	
		Longitude	Latitude	Easting	Northing
1	P465	80° 40' 0.348" E	21° 8' 39.796" N	465400.37338	2338163.84891
2		80° 39' 59.340" E	21° 8' 45.526" N	465371.67926	2338340.08822
3		80° 39' 59.181" E	21° 8' 49.293" N	465367.34094	2338455.89071
3A		80° 39' 55.842" E	21° 8' 49.958" N	465271.07165	2338476.53949
4		80° 39' 52.340" E	21° 8' 50.655" N	465170.13336	2338498.18973
4A		80° 39' 47.866" E	21° 8' 50.982" N	465041.10029	2338508.50434
5		80° 39' 43.049" E	21° 8' 51.333" N	464902.19024	2338519.60849
6		80° 39' 38.656" E	21° 8' 51.338" N	464775.50956	2338520.01121
7		80° 39' 38.046" E	21° 8' 47.514" N	464757.65790	2338402.48778
7A		80° 39' 37.498" E	21° 8' 44.389" N	464741.64400	2338306.46753
8		80° 39' 36.828" E	21° 8' 40.574" N	464722.08909	2338189.21522
8A		80° 39' 36.128" E	21° 8' 35.493" N	464701.54276	2338033.06308
9		80° 39' 39.533" E	21° 8' 34.719" N	464799.71421	2338009.03758
10		80° 39' 41.522" E	21° 8' 33.593" N	464857.00200	2337974.31300
11		80° 39' 47.464" E	21° 8' 29.487" N	465028.12200	2337847.72000
12		80° 39' 53.171" E	21° 8' 25.562" N	465192.44700	2337726.68600
13		80° 39' 55.461" E	21° 8' 23.194" N	465258.34600	2337653.74100
14		80° 39' 59.637" E	21° 8' 24.191" N	465378.86400	2337684.15500
15		80° 40' 1.095" E	21° 8' 24.724" N	465420.95600	2337700.46600
16		80° 40' 3.519" E	21° 8' 21.258" N	465490.65200	2337593.76100
17		80° 40' 5.919" E	21° 8' 21.138" N	465559.87100	2337589.91600
18		80° 40' 7.018" E	21° 8' 22.529" N	465591.65000	2337632.60400
19		80° 40' 6.329" E	21° 8' 25.248" N	465571.95132	2337716.24631
20		80° 40' 5.493" E	21° 8' 28.546" N	465548.06000	2337817.69100
21		80° 40' 3.755" E	21° 8' 32.346" N	465498.17034	2337934.62575
22		80° 40' 1.996" E	21° 8' 36.193" N	465447.67549	2338052.97902

वन परिक्षेत्र अधिकारी

उपवनमंडल अधिकारी

वन मंडलाधिकारी खैरागढ़ वनमंडल

Computer Plus Raipur (C.G.)

➢ Survey Photographs with Staff

Pillar Survey Photographs


465
7
N - 21° 08' 47.514"
E - 80° 39' 38.046"


465
7A
N - 21° 08' 44.389"


465
8
N - 21° 08' 40.574"
E - 80° 39' 36.828"


465
8A
N - 21° 08' 35.493"
E - 80° 39' 36.128"


Thank You!

DGPS SURVEY & REPORT PREPARED BY:

COMPUTER PLUS

Software Development & Consultancy

Plot No. 4 Sector-1, Devendra Nagar
Raipur (C.G.) 492001
Phone No: 0771 4031077 M: 7587113793
E-mail: info@cplus.in Website: www.cplus.in

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