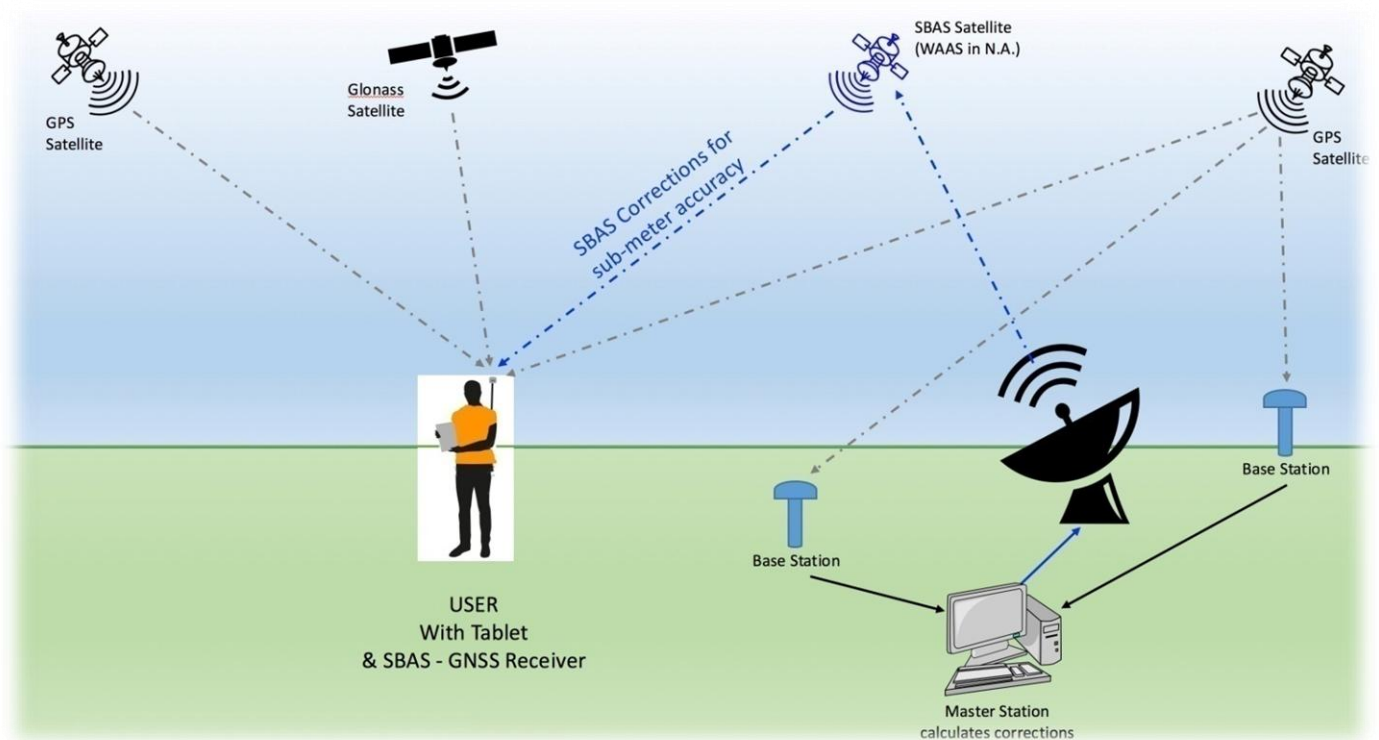


D.G.P.S. SURVEY REPORT OF
POWER LINE ERRECTION
FOREST DIVISION EAST BHANUPRATAPUR
DISTRICT KANKER
CHHATTISGARH



Name of the Applicant:

M/S SHRI BAJRANG POWER & ISPAT LTD,
Vill - Borjhara, Guma-Urla Road , Urla Industrial Area,
Raipur, Chhattisgarh.

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MAPS ON A3 SIZE PRINTOUT

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1	LOCATION MAP
2	GEO REFERENCE SURVEY SITE ON SOI TOPOSHEET
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DATA ENCLOSED IN SOFT COPY

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1	SURVEY REPORT
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1. ABOUT US

Computer Plus an **ISO 9001:2008 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.

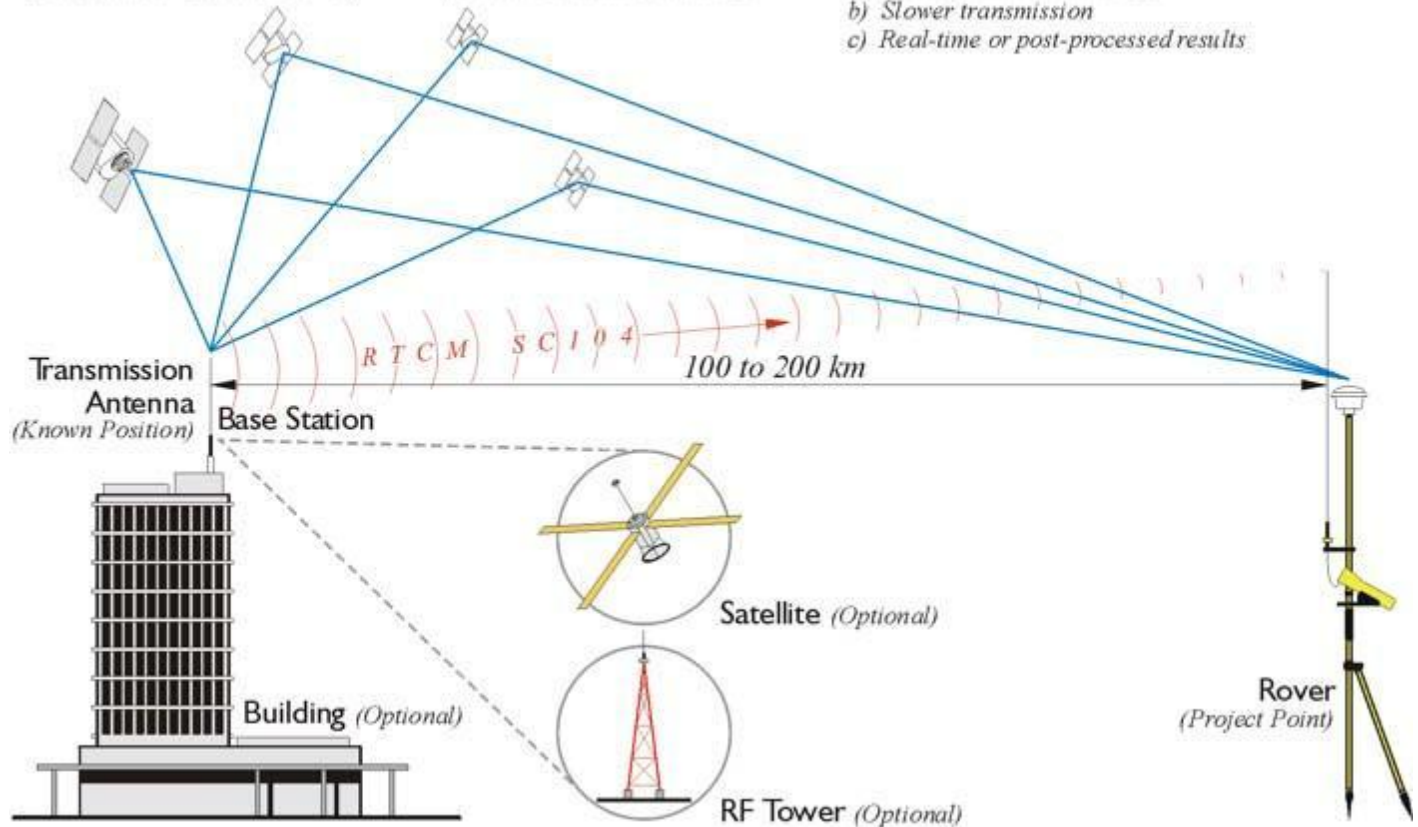
We create new teams for each project, ensuring the best possible combination of skills and experience to meet the client's needs and deliver high quality solutions.

2. INTRODUCTION TO DGPS

Differential GPS/DGPS

Positional Accuracy +/- 1 meter or so

- Same Satellite Constellation
(Base Station - Rover/or Rovers)
- Code Phase/Pseudorange
(Track 4 Satellites Minimum)
- Radio Link
 - a) Less information than RTK
 - b) Slower transmission
 - c) Real-time or post-processed results



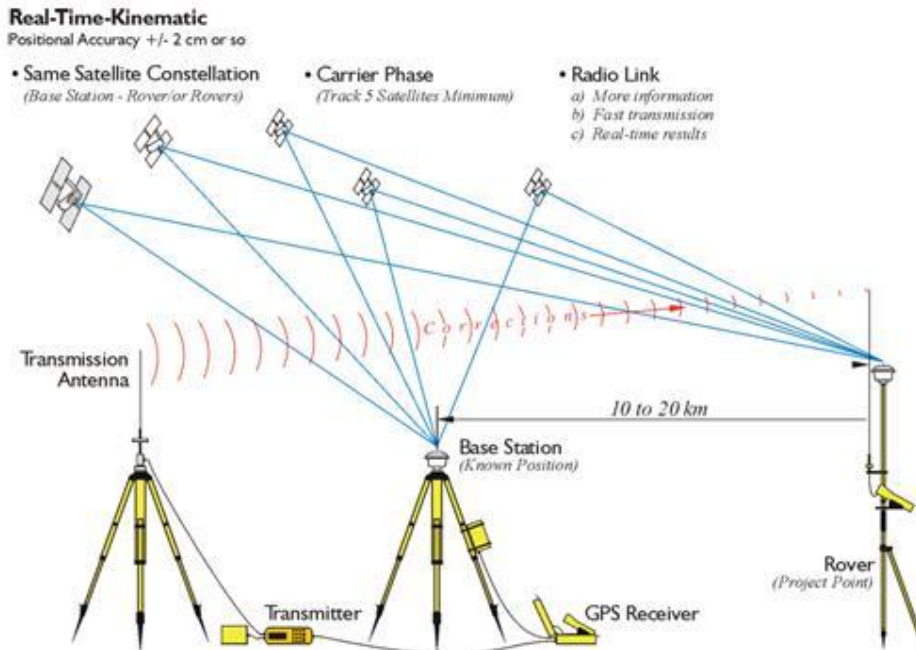
The term DGPS is sometimes used to refer to differential GPS that is based on pseudo ranges, aka code phase. Even though the accuracy of code phase applications was given a boost with the elimination of Selective Availability (SA) in May 2000 consistent accuracy better than the 2-5 meter range still 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 versions 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)
- 2 STATIC METHOD

1 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.

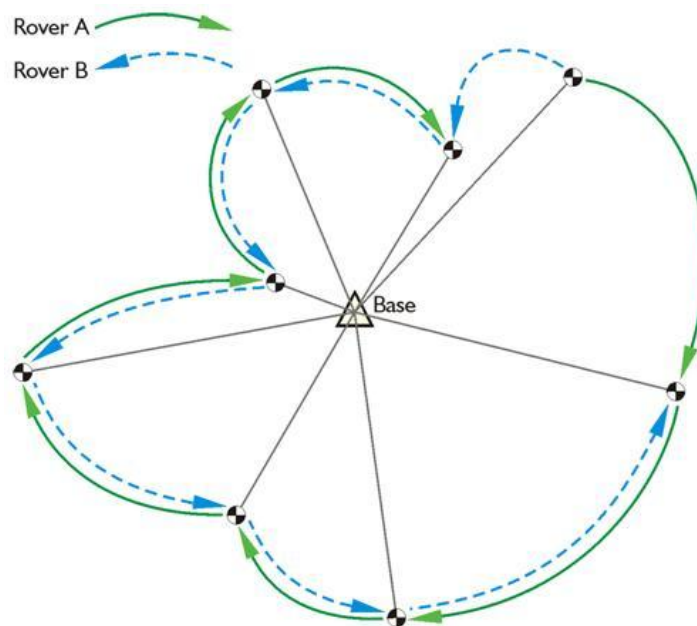
Errors in satellite clocks, imperfect orbits, the trip through the layers of the atmosphere, and many other sources contribute inaccuracies to GPS signals by the time they reach a receiver.

These errors are variable, so the best 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 sent 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 a 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.

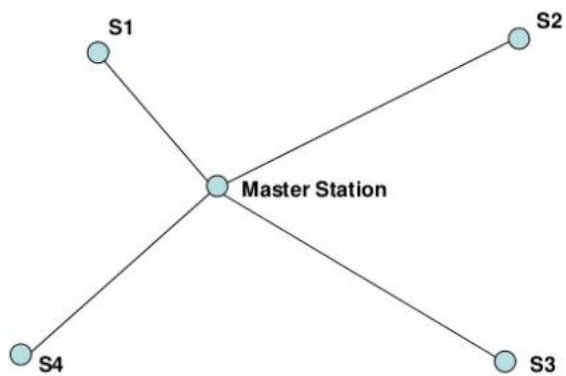
These are a few possibilities to consider when you are doing a real-time survey.

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.



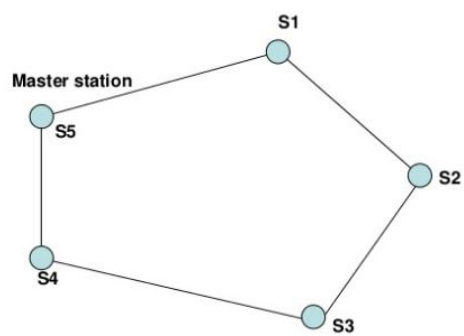
2. STATIC METHOD

I. Rapid Static Method



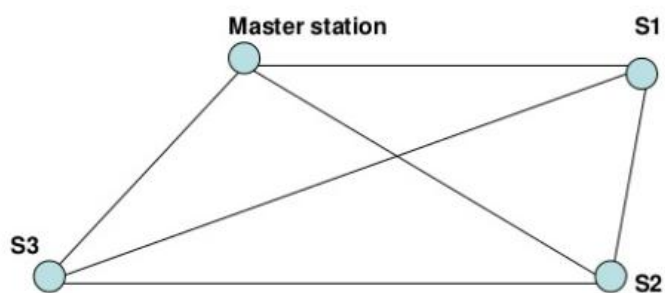
Schematic diagram of Rapid Static Method

II. Traverse Method



Schematic diagram of Traverse method

III. Trilateration Method



Trilateration method



3. INTRODUCTION TO SURVEY SITE

The surveyed area is located on **Village Hahaladdi**, which comes under **Block Durgukondal, District Kanker, Chhattisgarh**. East Bhanupratapur Bus Stand longitude latitude is **81°4'7.18"E 20°18'35.34"N**. Survey site is located **20.6** Km from **East Bhanupratapur**. Survey site comes under **Forest Division East Bhanupratapur, Forest Range Durgukondal & Forest Circle Kanker**.

AREA DETAILS & LAND CLASSIFICATION

S.No.	Division Name	District Name	Range Name	Village Name	Compartment No.	Area In Hectare
1	East Bhanupratapur	Kanker	Durgukondal	Hahaladdi	642	0.746
2					640	0.087
3					FDC P876	0.787
TOTAL						1.620

LAND CLASSIFICATION SUMMARY

S.No	LAND TYPE	Area In Hectare
1	RESERVE FOREST	0.833
2	PROTECTED FOREST	0.787
TOTAL		1.620

4. METHODOLOGY USED

SURVEY METHODOLOGY UNDER FOREST

UNDER FOREST AREA MAKE PERMANENT BENCH MARK (PBM POINTS) ALREADY AVAILABLE ON THAT PBM POINT STATIC OBSERVATION HAVE BEEN TAKEN FOR 12HOURS OF OBSERVATION POINTS HAVE TO BE GENERATED WHICH WILL BE USED AS CORRECTION POINTS.

USING THIS PBM AS CORRECTION POINT ALL OTHER BOUNDARY PILLARS HAVE TO SURVEYED

ALL COLLECTED PILLAR POINTS HAVE TO BE CONNECTED TO MAKE POLYGON BOUNDARY

COLLECTED DATA HAVE TO BE SUPERIMPOSE ON TOPOSHEET MAP WHICH HAVE BEEN COLLECTED FROM SURVEY OF INDIA

COLLECTED DATA HAVE TO BE SUPERIMPOSE ON SATELLITE IMAGE WHICH HAVE BEEN COLLECTED FROM NRSC HYDERABAD

REPORT PREPARATION & MAP PREPARED AS PER REQUIRED SCALE

5. CONTROL POINT

PRIMARY CONTROL POINT (FIXING OF BASE STATION POINTS)

S.No.	P.C.P (VILLAGE NAME)	LONGITUDE	LATTITUDE
GROUND CONTROL POINT 1	Hahaladdi	80° 56' 28.829" E	20° 13' 5.764" N

SURVEYED GROUND CONTROL POINTS

S.No.	PILLAR ID	LONGITUDE	LATTITUDE
1	L1	80° 53' 51.238" E	20° 12' 32.157" N
2	L2	80° 53' 53.798" E	20° 12' 30.420" N
3	L3	80° 53' 56.602" E	20° 12' 28.681" N
4	L4	80° 53' 59.103" E	20° 12' 26.990" N
5	L5	80° 54' 1.362" E	20° 12' 25.224" N
6	L6	80° 54' 3.597" E	20° 12' 23.468" N
7	L7	80° 54' 5.826" E	20° 12' 22.150" N
8	L8	80° 54' 8.259" E	20° 12' 20.716" N
9	L9	80° 54' 10.840" E	20° 12' 19.163" N
10	L10	80° 54' 13.357" E	20° 12' 17.688" N
11	L11	80° 54' 15.940" E	20° 12' 16.541" N
12	L12	80° 54' 18.795" E	20° 12' 15.409" N
13	L13	80° 54' 20.690" E	20° 12' 14.783" N
14	L14	80° 54' 21.736" E	20° 12' 14.486" N
15	L15	80° 54' 24.954" E	20° 12' 14.034" N
16	L16	80° 54' 27.850" E	20° 12' 13.690" N
17	L17	80° 54' 30.874" E	20° 12' 13.335" N
18	L18	80° 54' 31.806" E	20° 12' 11.864" N
19	L19	80° 54' 32.826" E	20° 12' 10.253" N
20	L20	80° 54' 34.149" E	20° 12' 7.977" N
21	L21	80° 54' 35.586" E	20° 12' 5.534" N
22	L22	80° 54' 37.068" E	20° 12' 3.130" N
23	L23	80° 54' 38.563" E	20° 12' 0.729" N
24	L24	80° 54' 39.945" E	20° 11' 58.037" N
25	L25	80° 54' 38.473" E	20° 11' 55.647" N
26	L26	80° 54' 37.533" E	20° 11' 53.836" N
27	L27	80° 54' 36.539" E	20° 11' 52.315" N
28	L28	80° 54' 35.440" E	20° 11' 50.595" N
29	L29	80° 54' 34.509" E	20° 11' 49.183" N
30	L30	80° 54' 32.687" E	20° 11' 47.973" N
31	L31	80° 54' 30.752" E	20° 11' 46.592" N
32	L32	80° 54' 29.453" E	20° 11' 44.875" N
33	L33	80° 54' 28.315" E	20° 11' 43.309" N
34	L34	80° 54' 26.723" E	20° 11' 41.865" N

S.No.	PILLAR ID	LONGITUDE	LATTITUDE
35	L35	80° 54' 24.966" E	20° 11' 40.414" N
36	L36	80° 54' 23.960" E	20° 11' 39.522" N
37	L37	80° 54' 23.476" E	20° 11' 38.773" N
38	L38	80° 54' 23.121" E	20° 11' 38.382" N
39	L39	80° 54' 22.363" E	20° 11' 37.599" N
40	L40	80° 54' 21.800" E	20° 11' 37.075" N
41	R1	80° 53' 51.367" E	20° 12' 32.309" N
42	R2	80° 53' 53.917" E	20° 12' 30.580" N
43	R3	80° 53' 56.717" E	20° 12' 28.843" N
44	R4	80° 53' 59.226" E	20° 12' 27.147" N
45	R5	80° 54' 1.495" E	20° 12' 25.374" N
46	R6	80° 54' 3.724" E	20° 12' 23.622" N
47	R7	80° 54' 5.936" E	20° 12' 22.315" N
48	R8	80° 54' 8.369" E	20° 12' 20.881" N
49	R9	80° 54' 10.950" E	20° 12' 19.329" N
50	R10	80° 54' 13.458" E	20° 12' 17.858" N
51	R11	80° 54' 16.026" E	20° 12' 16.719" N
52	R12	80° 54' 18.872" E	20° 12' 15.590" N
53	R13	80° 54' 20.756" E	20° 12' 14.968" N
54	R14	80° 54' 21.777" E	20° 12' 14.678" N
55	R15	80° 54' 24.983" E	20° 12' 14.227" N
56	R16	80° 54' 27.875" E	20° 12' 13.883" N
57	R17	80° 54' 30.993" E	20° 12' 13.508" N
58	R18	80° 54' 31.990" E	20° 12' 11.954" N
59	R19	80° 54' 33.005" E	20° 12' 10.351" N
60	R20	80° 54' 34.330" E	20° 12' 8.071" N
61	R21	80° 54' 35.766" E	20° 12' 5.629" N
62	R22	80° 54' 37.246" E	20° 12' 3.229" N
63	R23	80° 54' 38.744" E	20° 12' 0.824" N
64	R24	80° 54' 40.165" E	20° 11' 58.029" N
65	R25	80° 54' 38.654" E	20° 11' 55.552" N
66	R26	80° 54' 37.717" E	20° 11' 53.745" N
67	R27	80° 54' 36.716" E	20° 11' 52.213" N
68	R28	80° 54' 35.617" E	20° 11' 50.493" N
69	R29	80° 54' 34.665" E	20° 11' 49.053" N
70	R30	80° 54' 32.808" E	20° 11' 47.814" N
71	R31	80° 54' 30.901" E	20° 11' 46.455" N
72	R32	80° 54' 29.623" E	20° 11' 44.763" N
73	R33	80° 54' 28.474" E	20° 11' 43.183" N
74	R34	80° 54' 26.864" E	20° 11' 41.723" N
75	R35	80° 54' 25.107" E	20° 11' 40.270" N
76	R36	80° 54' 24.120" E	20° 11' 39.398" N
77	R37	80° 54' 23.648" E	20° 11' 38.665" N
78	R38	80° 54' 23.275" E	20° 11' 38.251" N
79	R39	80° 54' 22.514" E	20° 11' 37.465" N
80	R40	80° 54' 21.945" E	20° 11' 36.936" N

6. SURVEY DATE

Survey Date	Survey Time	Village Name
23/04/2018	11.00 AM To 05.00 PM	Hahaladdi

Weather was nice with clear sun light. Survey pillar marking has been done before itself so it was easy to get the location point. Survey has been done by the survey team members Mr. Ketan Rao & Mr. Kishor Sahu. The team was lead by **Mr. Kishor Sahu.**

Base Station Photographs



Survey Photographs With Staff



Thank You!

DGPS SURVEY & REPORT PREPARED BY:



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