An image of the borehole wall is produced by moving the sonde along the borehole axis while it is scanning radially. By the same logic as shown above, it can be seen that any horizontal point will be imaged by more than one sweep of the acoustic beam so long as the axial movement of the sonde during one complete sweep is no greater than the beam diameter. An upper limit is therefore imposed upon the logging speed which will be a function of the rotational speed of the transducer, the radial sampling interval and borehole diameter.

Objective

The objective of this procedure is to provide a pseudo “core” of the borehole, and map the orientation and angles of cracks and voids in rock boreholes.

Instrumentation

This procedure is written specifically for the Robertson Geologging High-Resolution Acoustic Televiewer (HiRAT). The required equipment includes:

1. The Robertson High-Resolution Acoustic Televiewer (HiRAT) sonde with centralizers
2. A 4-conductor wire-line winch with cable at least 30m (100ft) longer than the depth of the borehole (RG Smart Winch or equivalent. GEOVision has adapted all our 4-conductor winches)
3. A sheave with depth encoder with minimum 500 pulse/revolution
4. A Robertson Geologging Micrologger II
5. A laptop with Winlogger installed and the following minimum system requirements:
    - Windows 98SE or above
    - 64M System memory
    - 800x600x24 SVGA Display with DirectX 8.0
    - 500Mhz CPU
    - USB 2.0 connection
6. Battery power supply with cables

Environmental Conditions

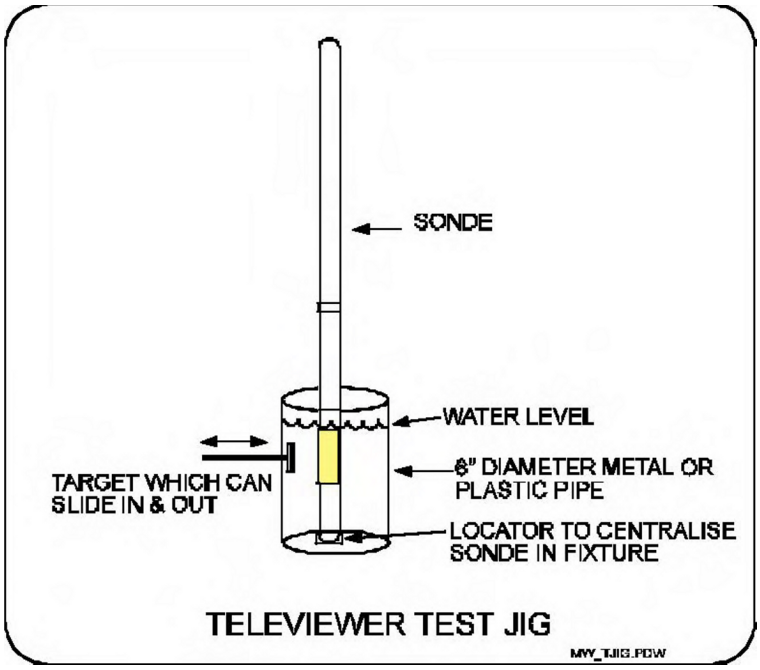
This tool is designed for fluid-filled boreholes between 67 and 150mm (3-6in) in rock. Since fine cracks are usually not visible in the walls of soil borings, the televiewers add very little information from a soil boring than a simple video. Now if the boring has soil AND rock, televiewer visuals in the soil may still be useful.

Calibration

The acoustic televiewer uses the variability in reflectance and the travel time to make an image of the borehole wall, mostly resulting from relative differences of materials and the physical characteristics of the wall. Since these are relative measurements, no field calibration of the sonde is required. However, it is important that the same location in the borehole be checked at the start and finish of the logging to make sure that the response or functionality haven't changed during the measurement.

A test fixture may be used to check function of the acoustic televiewer prior to use. This test fixture should comprise a plastic pipe, with a known internal diameter between 3 and 6 inches. This should be filled with water and the sonde stood upright in the fixture. A target made of metal or metal foil is glued on the inside of the container, or optionally on a seal and shaft so that it can be moved in and out on a line radial to the center-line of the pipe. A representation of this is shown in the figure below.

The purpose of this test fixture is to check the ability of the sonde to differentiate between materials of different acoustic reflectances, and different travel times, and to check the calibration of the caliper function of the sensor using the measured diameter of the pipe. However, if calibrated caliper measurements are required, it is recommended that a mechanical 3-arm caliper tool be used for this purpose because it can be calibrated in the field prior to use. The HiRAT will give very accurate results but this procedure does not cover calibration.

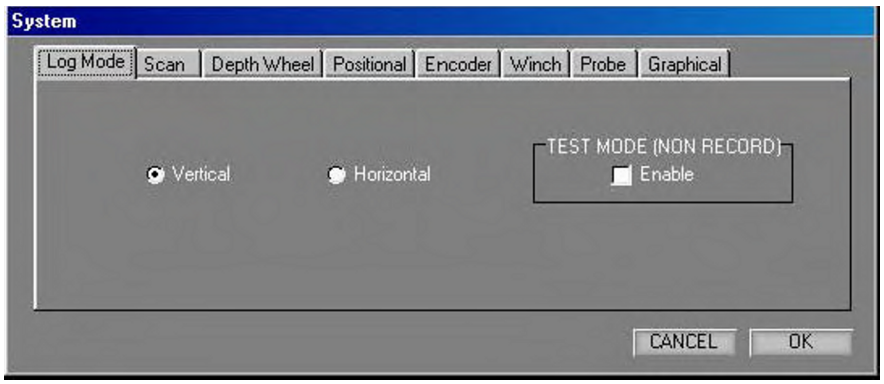


Hi-RAT Field Procedure

Because the logging software is a standalone module, there are a number of settings which must be initialized independently of the WinLogger software. These include the depth measurement subsystem and sonde operating modes. Click on 'System' on the menu bar to show the following dialog boxes:

1.0 Log Mode

The sonde can operate in three distinct modes:



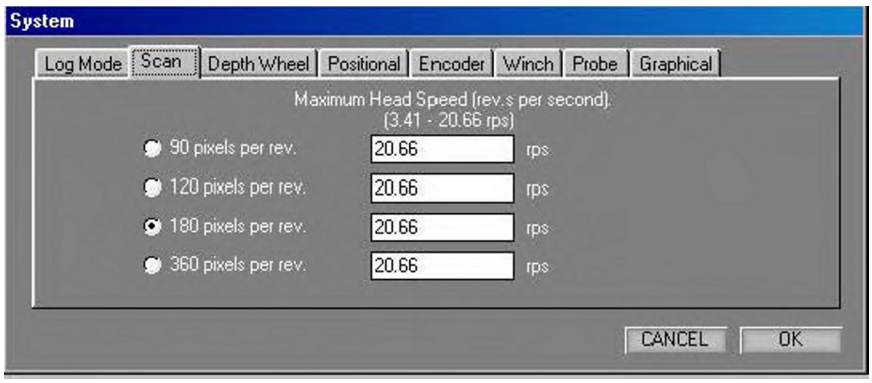
- Vertical mode is used for boreholes which are drilled from the surface and are deviated at less than 70 degrees from the vertical. Most exploration boreholes will fall into this class. In this mode the image is orientated according to compass directions (magnetic co-ordinates).

- Horizontal mode is used for boreholes which are sub-horizontal so their inclination will probably exceed 70 degrees from the vertical. Boreholes in this class would normally be drilled as part of ground investigations for tunneling and mining, drilling ahead of a drive to determine the nature and extent of fracturing. In this mode the image is orientated according to gravitational coordinates (up/down) since there is no unique point of the image circle which can be orientated to North with any precision.

- Test mode is used to exercise all sonde functions without creating a log. The image will scroll on the screen in the normal fashion, and orientation readouts will be refreshed continuously.

2.0 Scan Parameters

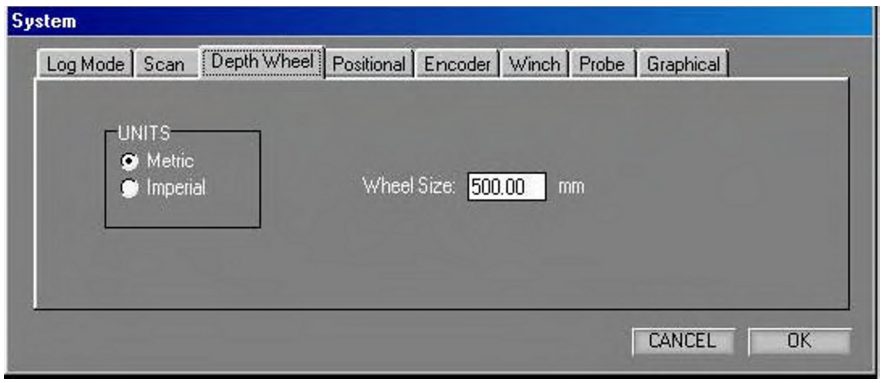
The scan parameters control the radial sampling of the borehole. The values will be retained between logging sessions, so the sonde will be initialized correctly at power-on. There are three parameters in the dialog:



- The radial sampling rate can be set to one of 90, 120, 180, 360 samples per revolution. There is a relationship between the logging speed and the radial sampling rate, since the time taken to send the dataset to the surface depends upon its length. The size of the log file is also determined by the radial sampling rate. The probe will always try to use the maximum head speed entered. If limited by a low Baud rate or a large 'window' setting then the probe will reduce its head speed automatically to compensate - see sonde operation section.

3.0 Depth Wheel Configuration

The depth measurement system is dependent upon the combination of depth measurement wheel with its calibrated groove, and the shaft encoder which translates rotation into pulses which are counted by the logging system controller. Two parameters are therefore required: depth wheel circumference and encoder pulse rate. The encoder parameters are covered in a subsequent topic.

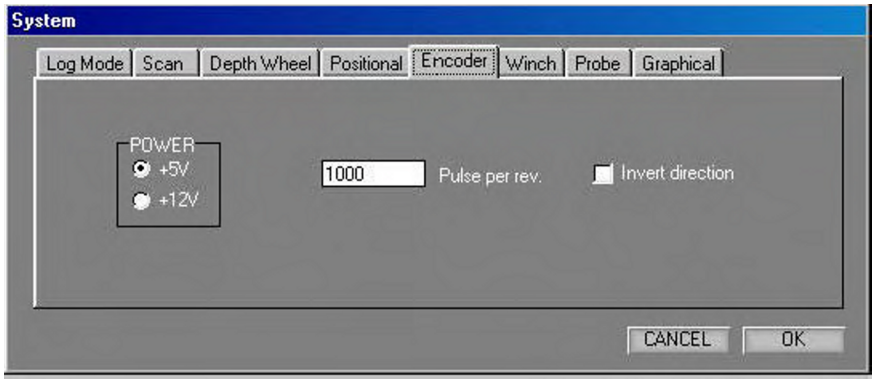


- Select Metric or Imperial depth measurement units from the left-hand pane.

- Type the circumference of the depth measurement wheel into the 'wheel size' box. The standard sizes of GEOVision wheels are 1000mm. If you are measuring in Imperial units (or changing back to metric units), the standard wheel size can be converted automatically by clicking the left mouse button and choosing the appropriate conversion. The size is always specified in units of 1/1000 of the depth unit i.e. millimetres (mm) or millifeet (mft).

4.0 Encoder Configuration

The depth measurement system is dependent upon the combination of depth measurement wheel with its calibrated groove, and the shaft encoder which translates rotation into pulses which are counted by the logging system controller. The depth wheel circumference is covered in a previous topic. In order to accommodate a variety of encoders, their operational characteristics can be configured in the software.



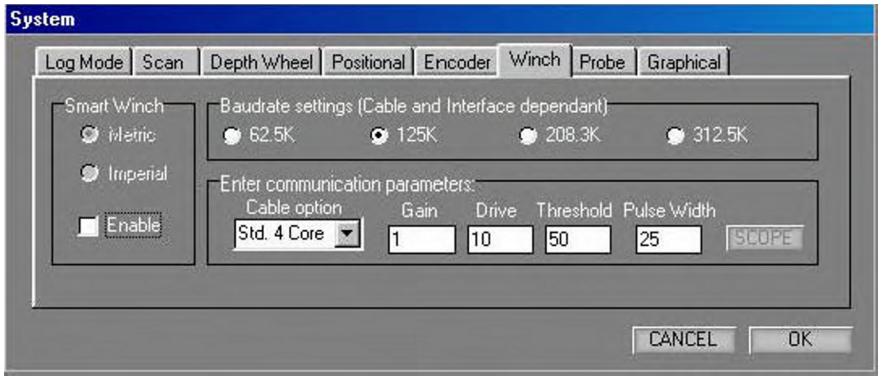
- Select supply voltage from the radio buttons in the left-hand pane. The options are 5 Volt and 12 Volt. GEOVision encoders are always specified for 5 Volt operation.

- Type the number of pulses emitted per revolution into the central box. The standard values for all GEOVision winches are 500 pulses/rev.

- The logical direction of movement can be reversed if required to accommodate the directional characteristics (phase lead or lag) of the different encoder types.

5.0 Winch and Cable Configuration

Support for remote control of the RG Smart Winch is provided, and can be enabled by checking the ***Enable*** control in the left-hand Smart Winch pane. If the Smart Winch control is enabled, it is also necessary to select the measure units in force - select ***Metric*** or ***Imperial*** from the radio buttons on offer.



The Baud settings can be chosen to match the *quality* of the communication channel. The channel will be effected by cable type and length. Typically a Baudrate of 312.5K is used. The remaining controls in the dialog relate to the communications parameters. The operation is entirely compatible with the WinLogger software operation and the values would be expected to be the same as those in force for logging six-channel type sondes with that software. (Certain probe types may be fitted with a digital interface that does not require set-up and in this case the parameter edit boxes will not appear.)

- ***Cable Option*** is used to select the logging cable type which is available on the winch. The options are *Not Connected*, *Std. 4 Core*, *Differential* and *Monocable*. The only cable types used in GEOVision systems is Std. 4 Core. Select the appropriate type from the drop-down menu box. Note this value can only be changed when the probe power is turned off.

- ***Gain*** is related to cable length and uphole signal attenuation. Gain values range from 0-3 and control the amplification applied to the incoming signal. Use the *Scope* dialog to visualize the incoming signals. Gain should be set so that the signal reaches between 70% and 100% of the height of the display, generally obtained with a setting of 0 for GEOVision winches. If the peak height exceeds this level, clipping will result in artifacts which will be detected erroneously. Click *Apply* to set the parameters before proceeding to the *Scope* dialog.

- ***Threshold*** is the level at which the incoming signals are detected. Gain and Threshold are related, and can be visualized using the *Scope* dialog. Set the gain so that the signal reaches between 70% and 100% of the height of the display. Then adjust the threshold so that it is between 50% and 70% of the height of the pulses displayed and clear of any region of 'overshoot' of the positive and negative pulses. This will ensure that peaks are detected and noise is ignored. Generally a setting of 25 is used for GEOVision winches. When the scope dialog is displayed, the position of the mouse is reported as a threshold value to make it simpler to infer the correct setting. The scope option is greyed out when the probe power is turned off.

- ***Drive*** sets the strength of the downhole signal. It is not possible to visualize the downhole signal, but the effect of insufficient drive is to disable downhole communication, which will result in the commands being ignored by the sonde. Values range from 0 -127, and for GEOVision winches will be around 10. Increase the drive for longer cables.

- ***Pulse Width*** This is the width of the transmitted communication pulses in 100nS steps. The default is 25 equivalent to 2.5uS. The range is from 8 to 64. The pulse width can be reduced to prevent signal overshoot on short cables. The default value is used in most cases. Note any changes only come into effect during a log. (Note setting too large a pulse width when using the highest Baud rates will automatically be prevented within the probe and the pulse width reduced.)

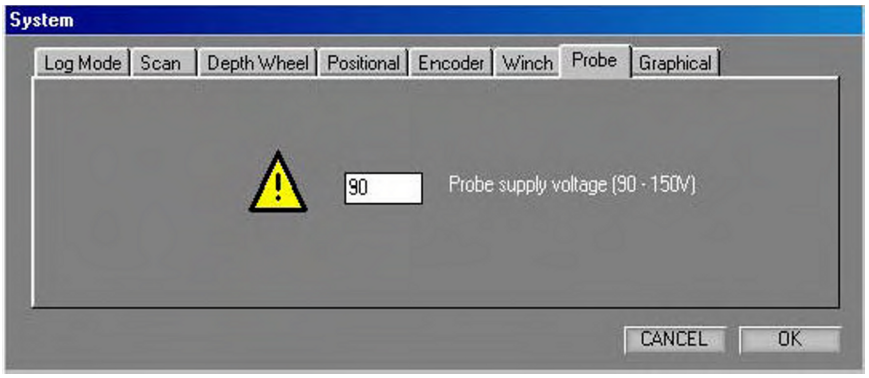
IMPORTANT Please note the effects of changing 'Baud' will not appear until the first new log is made. The setting for 'threshold' may be effected by an increase in the 'Baud' rate please recheck 'threshold' if 'Baud' is altered using the 'Scope' function after making a short test log.

The parameters which are entered will be applied automatically if you close the dialog with ***OK***. The above parameters once set correctly will be remembered by the system and should never need to be altered.

6.0 Probe Configuration

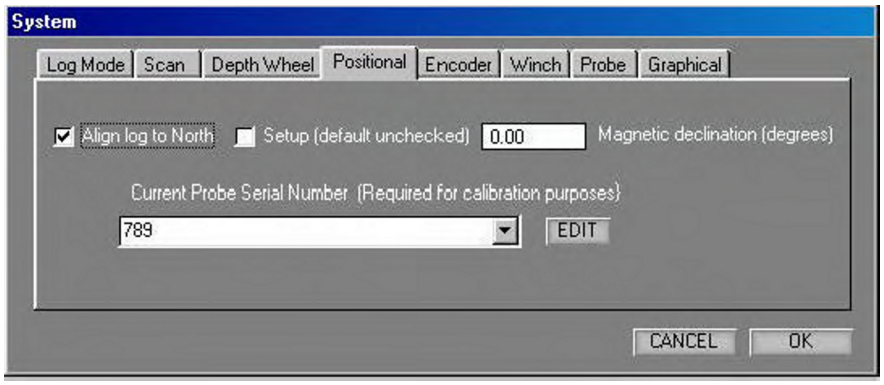
The probe is normally energized at 90 Volts from the surface. However, it may be necessary to compensate for voltage drop on longer cables due to the higher power draw of this sonde. The voltage at

the surface may be increased in order to deliver 90 Volts at the sonde. Simply type the value into the text box provided. The voltage should be set at 90V for all GEOVision winches. Values outside the indicated range will be rejected.



7.0 Positional Configuration

The probe includes a 3-axis orientation package, and is capable of producing a borehole image aligned to geographic North. This is achieved by determining and applying two image rotation parameters:



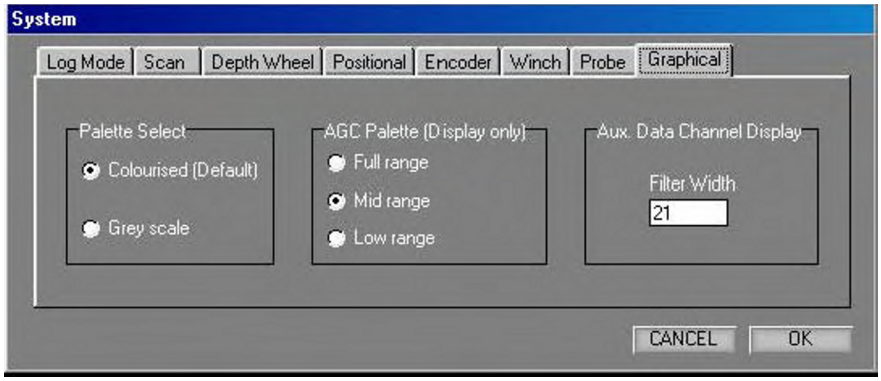
- ***Magnetic Declination*** is used to correct for the difference between Magnetic North and True North. The value varies from place to place, so the local value must be inserted here if you wish to perform this correction during data collection. This correction may also be made during processing. If the value is zero, the log will be referred to Magnetic North.
- ***Align to North*** is a check-box used to select image rotation to start at Magnetic North. If in addition a value is set for Magnetic Declination (see above) the image will be rotated to start at True North. If the box is not checked, the image will not be oriented to geographic co-ordinates, but will use the local co-ordinate frame of the sonde (X, Y, Z axis of the orientation module). This mode may be used to inspect the inside of magnetic casing, where an orientated image would be subjected to random effects caused by the metalwork.
- Set-up mode is selected by checking the ***Setup*** box, and is used to determine the required image rotation offset to correct for the angle between the axis of the orientation package and the index mark of the rotating transducer section. In set-up mode the normal sonde azimuth display is modified, and will instead show the 'relative bearing' which is measured between the high side of the borehole and the orientation sensor index. Check ***Setup***, then OK to close the dialog. The icon adjacent to the sonde azimuth readout at the top of the screen is modified with the legend CAL when the system is in set-up mode. The sonde must now be placed in a stand or jig so that it

is inclined at about 20 degrees to the vertical, and adjacent to a target fixed to the jig so that it is directly above the transducer in the vertical plane. Lower the sonde with its attachment into a large bucket of water so that the transducer and target are fully immersed. Start the radial amplitude display, when it will be possible to see the strong signal returning from the target. Rotate the sonde so that the image of the target moves to the top of the display. When the two are coincident, the 'relative bearing' reads out the image rotation offset. This value is fixed for the sonde unless it is disassembled and rebuilt, at which point the procedure MUST be repeated. Please see the additional topic on the Radial Amplitude Display for further details.

- The ***Serial Number*** list box is used to select the sonde which is in use. When the appropriate sonde is selected, the image rotation offset determined by the above procedure is selected. To edit the image offset click the '***Edit***' and enter the new offset. Several serial numbers and associated offsets can be stored and selected as required.

8.0 Graphical

The palette can be changed between a colored and grey scale setting. The changes affect the log screen palette display and are also applied when replaying a log. Selecting Full range in the 'AGC Palette' will cause the software to spread the palette over the full 16bit signal. 'Mid range' will spread the palette over the first quarter of the 16bit range and 'Low range' will spread the palette over the first eighth of the 16 bit range. In most cases the 'Low range' selection is used. Note these settings do not affect the stored log data in any way. The 'Filter Width' is applied to the Natural Gamma trace data and is a simply running average filter. The range of the filter width is from 1 to 50 (x 10 millidepth units ie. mm or mft).



9.0 Sonde Operation

When the operations specified above have been reviewed and the correct settings have been selected, the system is ready for use. The main screen area is divided into 3 horizontal elements. At the top is the depth and orientation readout, together with the scale headings for the scrolling display of unwrapped borehole image.

On the left side of the depth track is the travel time display, with text boxes for sonde inclination, azimuth and head temperature.

On the right side is the display of amplitude and indication of current operating mode. Located in the center above the depth track are the text boxes for depth and cable speed (computed at the surface). The ranges for the 'Natural Gamma' channel overlay (optional) are shown above the Amplitude.

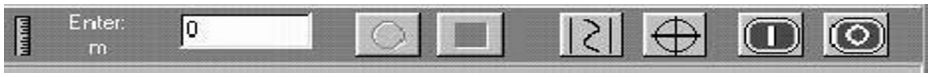
The central area is utilized for the scrolling display of unwrapped borehole data. The display is orientated with the left edge corresponding to North point of the aligned image data (if orientation is selected) according to the outputs of the sonde's orientation package.

The lower area has controls for the winch (applicable to RG Smart Winch only), depth initialization and sonde control.

The winch control area is only displayed when RG SmartWinch operation is enabled - see section 5 - and has four controls. Set Target Speed by typing the required speed into the window and pressing Enter.

Cable movement is initiated by clicking on either the UP or DOWN arrow control.

Cable movement is halted by clicking on the square STOP control.



Depth is initialized by typing the required value into the entry box and pressing Enter. The entry box is not available at times when the system is in logging mode and the depth should not be changed by user entry.

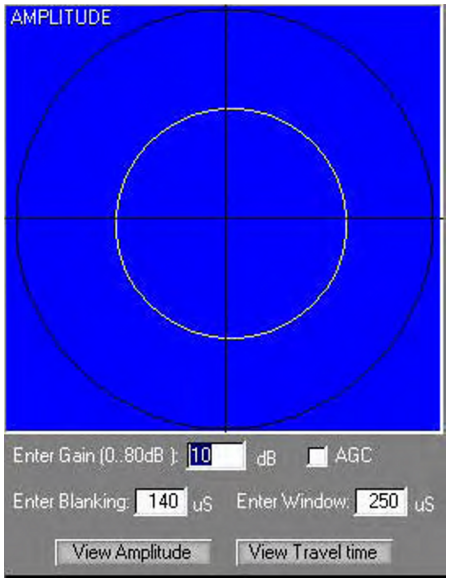
Sonde power is applied by clicking on the green-colored 1 button. Power is turned off by clicking on the red-colored 0 button. There is no indicator for the state of the power supply on the desktop, so the external indicators should be observed for this purpose.

To make a log ensure that the Test Mode is disabled - see section 1, Log Mode setting. Click File|New Log and select a filename. Old logs may be overwritten if necessary -TAKE CARE. The header editor will be started automatically. A previous set of header data may be loaded by clicking LOAD and choosing a template.

To start logging, click on the red Record (circle) control. The log data will start to scroll down the screen after a brief pause for synchronization. The messages "DSP2: Detecting data stream" and "Updating probe settings" will be observed at the bottom of the screen during this process. Note that the screen scrolling direction is not affected by the actual direction of movement of the sonde. To cease logging, click on the black STOP control (square). The data should be immediately backed up to a USB drive, CD, or other data storage prior to beginning another log.

If the data display from a probe which is properly connected appears to occupy only half of the track area,

with the remainder filled with random colors such as green which are not part of the regular palette, then it is most likely that the downhole data communication is not functioning properly. This symptom is due to the fact that the probe settings cannot be communicated properly, and it is operating in its default power-up mode. If this is the case, the Drive setting of the System|Winch dialog should be increased or decreased accordingly. See section 5 for full details.



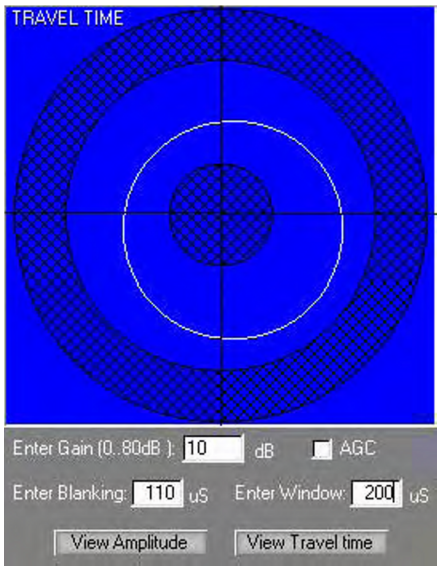
To adjust the sonde gain it is necessary to use the Radial Amplitude plot, which is enabled by clicking on the circle with cross-hairs symbol. When the dialog is active a new window will open on top of the unwrapped data display. In this display, the data is presented as a 'polar' plot. Press the 'View Amplitude' button to display the amplitude plot. This plot shows amplitude increasing towards the outside of the circle and the compass direction following the sweep of the transducer. The line indicating the data is drawn in the regular palette, so that high amplitudes are drawn in white and low amplitudes in black/brown. The picture here shows the image of the inside of a cylinder.

If the data is concentrated in a small circle at the center, the gain is too low and should be increased. If the data is obviously clipped at the outside of the circle, then the gain should be reduced. Type the new gain value into the entry box and press Enter. The ideal would be to set a gain value which allows the peak values to be displayed without clipping, with the majority of the data around the half-way level. It may also be necessary to adjust the blanking to ensure that internal reflections from the acoustic housing are not detected at the new gain value. This will be apparent in the unwrapped data display as pronounced patterning unrelated to the true target. The AGC option causes the probe to set gain automatically thus preventing signal saturation in most cases. (The gain is varied in 6dB steps

Blanking Period and window length can be set independently. Blanking is set to avoid reflections from the housing of the acoustic transducer or random reflections from a rugose borehole, and window length is set to accommodate the range of borehole radius that might be expected. An error will be indicated if the sum of the blanking period and window length would be greater than 409 microseconds, which is the maximum range of the timer. The default value for the blanking period is 145 microseconds, which is the minimum required for the two-way transit from the transceiver to the outer surface of the acoustic housing. It is not advisable to reduce this value beyond the default setting, although it may be increased for larger boreholes at the rate of 1.5mm of one-way travel per microsecond.

Window Length (sample time) defines the period during which the arrival gate remains open to detect the returned acoustic pulse. The acoustic pulse will travel in water at a speed of approximately 1.5mm per microsecond. The default window length is 150 microseconds, which is equivalent to 225 mm of (two-way) travel in the borehole fluid, or approximately 110mm of borehole diameter. If this is added to the default blanking period, which is equivalent to the outside diameter of the acoustic housing, it can be seen that the default set-up will be correct for boreholes up to 150mm. An error will be indicated if the sum of the blanking period and window length would be greater than 409 microseconds, which is the maximum range of the timer. Choose your window setting to best match the borehole diameter.

Pressing the ‘View Travel time’ button changes the display to that shown below:



The unhatched ring between the two cross hatched zones represents the sample window. The width of this ring will vary with window length value. The profile of a cylinder is represented here appearing as a circle in the sample window.

Pressing this button displays the following dialog box:

This box allows you to enable the Natural Gamma option by checking the ‘Enable Overlay’ check box. The Overlay appears as a trace upon the Amplitude plot. The trace range and color can also be set by this dialog. The level of filtering can also be altered (see section 8) (note that any displayed trace data is automatically aligned with the acoustic scan data but only when logging up. The Natural Gamma sensor occupies a higher position in the probe so sufficient data has to be prebuffered so that the acoustic data can depth aligned with gamma. The prebuffering results in a delay at the start of a log before correct gamma data appears this is normal.)

Data Analysis and Interpretation

RG-DIP, the manufacturer’s image interpretation package, offers manual and automatic feature recognition options. Feature orientations (dip/strike and azimuth) are automatically calculated. Display options include stereographic projections of zone axes, orientation frequency plots and 'synthetic cores' for comparison with real core data. The last option is invaluable for orientating core samples, particularly in the case of incomplete recovery.

Reporting

The final report will include the objective and scope of the survey, location of the boreholes, discussion of instrumentation and procedures in the field and lab. For each borehole there will be a plot showing the dip/strike and azimuth of features. The next page shows an example.

Assumptions and limitations of the results will be discussed. Supporting references will be listed as necessary

Required Field Records

Field log for each borehole showing

a) Location and description of the borehole

b) Date of test

c) Field personnel

d) Instrumentation

e) Any deviations from test plan and action taken as a result

This procedure has been reviewed and approved by the undersigned:

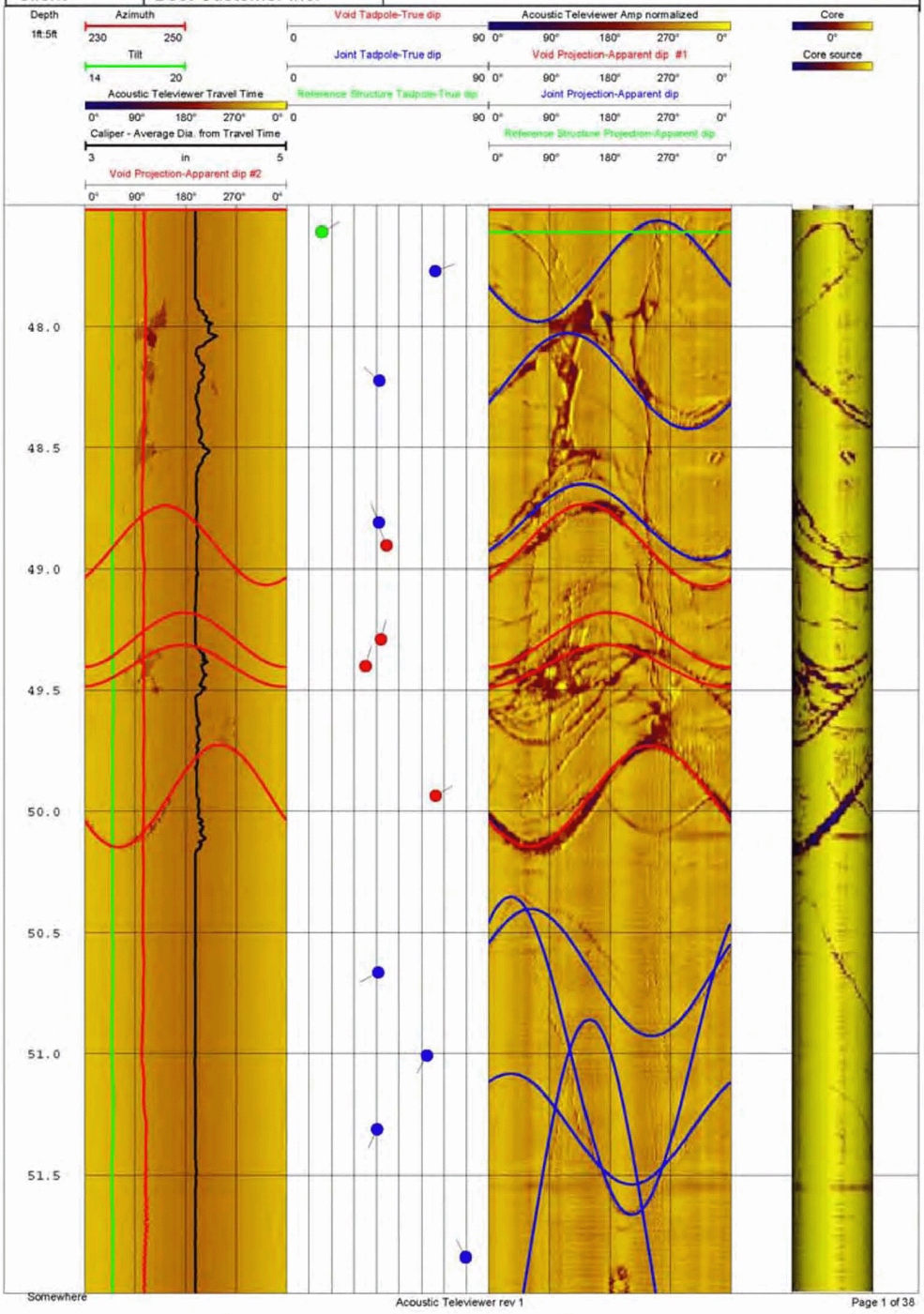
Professional Geophysicist Antony J Martin Date Feb 13. 2006

QA Review _____ Date Feb 13. 2006

B-XXX	Company	Geovision Geophysical Services
	Location	Somewhere Dam

BH	B-XXX Acoustic Televiewer		
Date	7/8/05	BH Fluid	Air/Water
Casing	4" Steel to 15 ft		
File Name	BXXXdown1		
Depth Drilled	300 feet		
Depth Logged	299.3 feet		
Logged by	Rob Steller		
Client	Best Customer Inc.		

Notes:

1) All orientations referenced to True North

2) Tadpole tails indicate dip direction with True North as up.