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ABBREVIATIONS

AAA	Anti-Aircraft Artillery
ADCP	Acoustic Doppler Current Profiler
ALARP	As Low as Reasonable Practicable
cm	Centimetre
CoG	Center of Gravity
CSAZ	Cesium Sensor Active Zone (Software)
DEMOB	Demobilisation
DGEC	Direction générale de l'énergie et du climat
DP	Dynamic Positioning
DPR	Daily production report
DTM	Digital Terrain Model
EC	Export Cable
EGN	Empirical Gain Normalization
FLO	Fisheries Liaison Officer
GEO	Geophysicist
GI	Borehole location

ABBREVIATIONS

GIS	Geographic Information System
GNSS	Global Navigation Satellite System
GPS	Global Positioning System
GRS	Geodetic Reference System
h	Hour
IGRF	International Geomagnetic Reference Field
INERIS	L'Institut national de l'environnement industriel et des risques
INS	Inertial Navigation System
JSF	EdgeTech Sonar data file format
Kg	Kilogram
KHz	kilohertz
LAT	Low Astronomical Tide
LMA	Luftmine A
LMB	Luftmine B
LSA	Land Service Ammunition
m	Meters
M	Minutes
MAG	Magnetometer
MBES	Multibeam echosounder
mm	Millimetre
MMO	Marine Mammals Observation
MOB	Mobilisation
MRU	Motion Reference Unit
nT	nanoTesla
OSS	Offshore substation
OWF	Offshore windfarm
PC	Party Chief
PEP	Project Execution Plan
POB	Personnel On Board

ABBREVIATIONS

PPP	Precise Point Positioning
PPS	Pulse Per Second
PPSU	Pulse Power Supply Unit
pUXO	Possible unexploded ordnance
QA	Quality Assurance
QC	Quality Control
QGIS	Quantum GIS (Software)
QHSE	Quality, Health, Safety and Environment
REPCO	Report Coordinator
RGB	Red, green, blue
ROTV	Remotely operated towed vehicle
ROV	Remotely Operated Vehicle
RTE	Réseau de Transport d'Electricité
RTK	Real Time Kinematics
s	Second
SHOM	Service hydrographique et océanographique de la Marine
SIT	Surrogate Item Trials
SRF	Ship's Reference Frame
SSS	Side Scan Sonar
SVP	Sound Velocity Profiler
SVS	Sound Velocity Sensor
TBC	To be confirmed
TXT	Standard text document file format
UHR	Ultra-High Resolution
USBL	Ultra-Short Base Line
UTC	Universal Time Coordinated or Coordinated Universal Time
UTM	Universal Transverse Mercator
UXO	Unexploded ordnance
VRF	Vertical Reference Frame

ABBREVIATIONS

VSAT	Very Small Aperture Terminal
WGS84	World Geodetic System 1984
WT	Work time

1. INTRODUCTION

1.1. PROJECT OVERVIEW

Tecnoambiente carried out a geophysical survey over the proposed NOR_AO8 lot, located in the English Channel (Figure 1-1 and 1-2), more precisely off the coast of Normandy, in the Bay of Seine. The site is under consideration for a windfarm and offshore substation. The survey of the UXO box was carried out over the previously acquired seismic lines in Phase I, in 2021.

The dimensions of this area of interest are 130 m x 130 m and according to the SHOM bathymetry, the site is located in water depths ranging from -41.50 to -42.00 m. The spatial surface this area represents is about 0.0169 km^2.

This is an area with a strong military history. During World War II, it is where the main Allied landings in France took place, so it is considered an area with a strong presence of potential UXO.

The objective of this report is to present the data obtained in the geophysical/UXO phase of the NOR_AO8 work area, focusing only on the Offshore Substation area (OSS). Figure 1-3 show the location of this box.

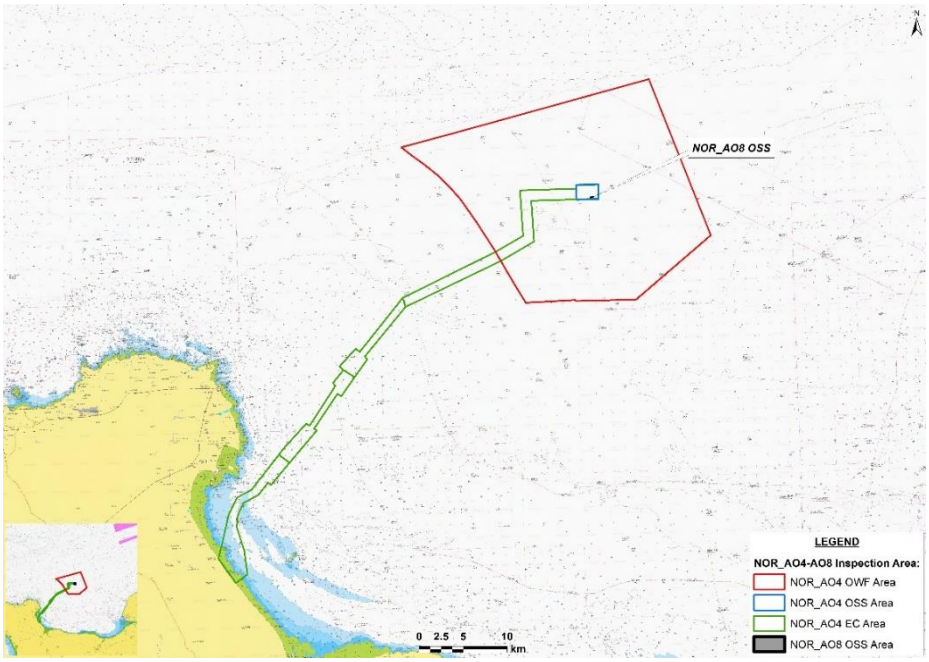


Figure 1-1: NOR_AO4-AO8 Survey area.

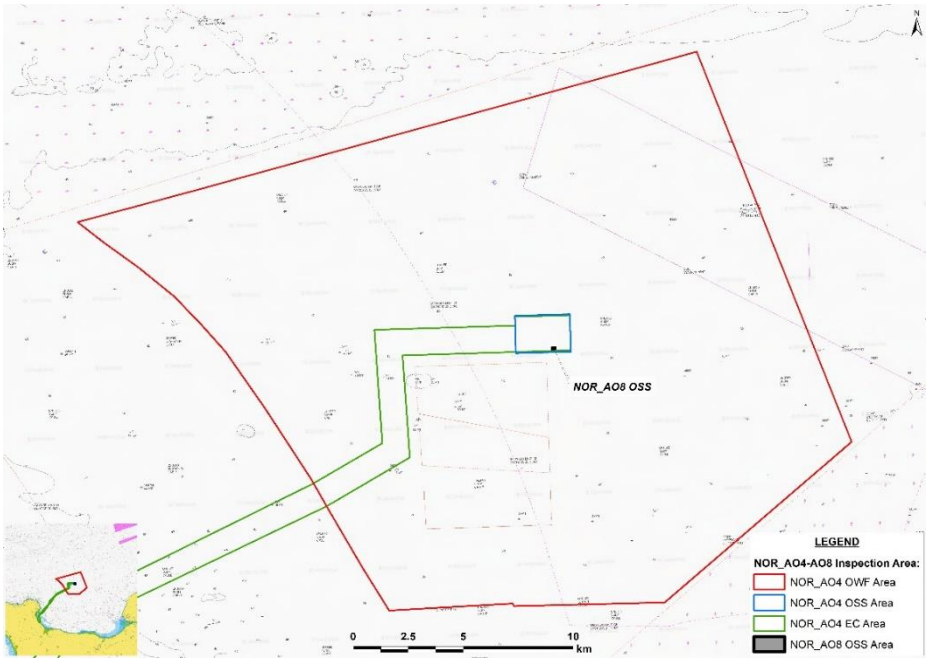


Figure 1-2: Windfarm area (OWF), Offshore Substation (OSS) and Export cable (EC) in the NOR_AO4 survey area and AO8 Offshore Substation (OSS).

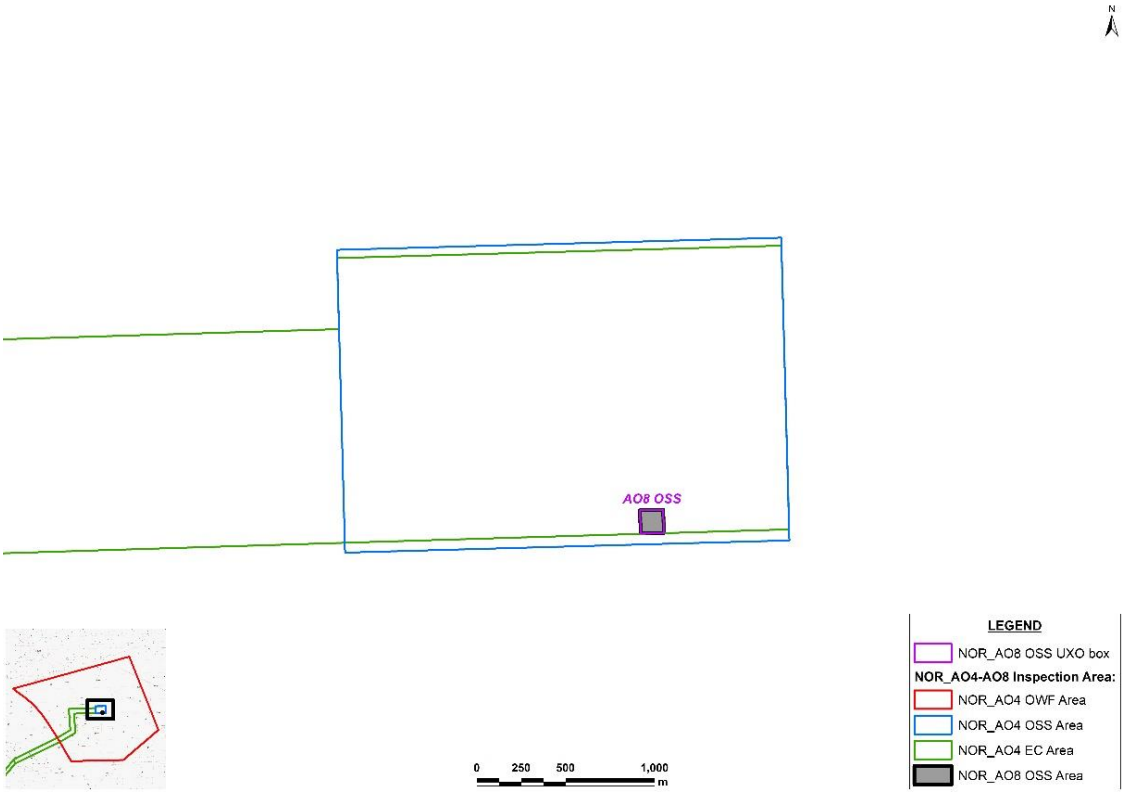


Figure 1-3: UXO box location at the NOR_AO8 Offshore substation (OSS).

The UXO box size comprises an area of 130 m x 130 m, with a run in / run out area of 1000 metres utilised to optimise the acquisition of the magnetometer data. Figure 1-4 indicates the UXO box dimensions. Figure 1-5 illustrates the survey line plan layout at 6m separation.

The NOR_AO8 OSS UXO box central point coordinates (*WGS84 Zone 30N*) are as follows:

- **UTM X**: 667995.510
- **UTM Y**: 5525038.690

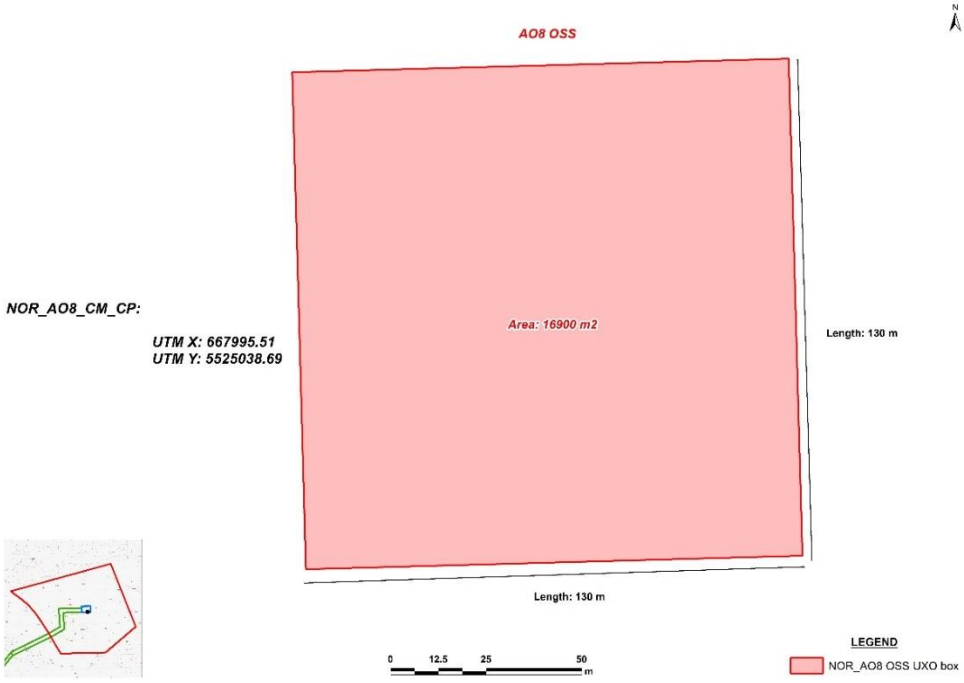


Figure 1-4: UXO box dimensions at the NOR_AO8 Offshore substation (OSS).

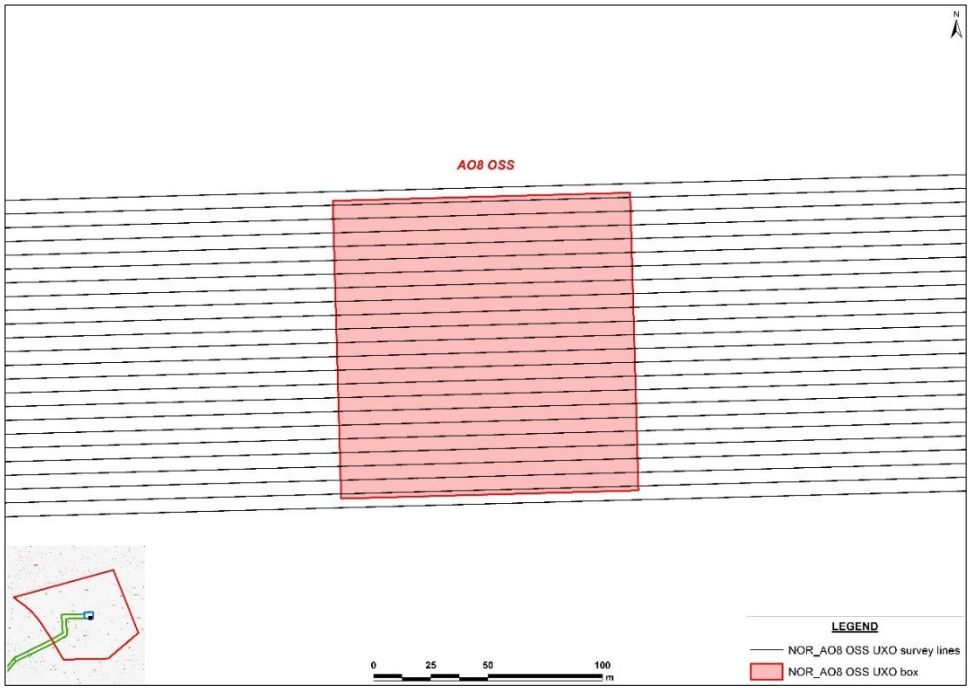


Figure 1-5: UXO box survey line plan at the NOR_AO8 Offshore substation (OSS).

1.2. SCOPE OF WORKS

The objective of the site survey was to perform a geophysical and UXO survey over the proposed 6 GI points (Borehole locations) on the OSS site, comprising MBES, SSS and MAG datasets. The purpose of this was to:

- To define the final location of the GI points on the proposed box
- To detect magnetometer anomalies, and side scan and MBES contacts
- To review proposed borehole locations for geohazards

The main purpose of the study was to provide an ALARP certificate for intrusive geotechnical sampling over the NOR_AO8 OSS area.

1.3. GEODETIC PARAMETERS

1.3.1. Survey datum

These parameters are detailed below.

Table 1: Datum parameters table

DATUM	
Survey Datum:	WGS 84
Spheroid	GRS 1980
Semi-Major Axis (a)	6,378,137.000
Semi-Minor Axis (b)	6,356,752.31424
Inverse Flattening (1/f)	1/298.257223563

Table 2: Projection parameters table.

PROJECTION	
Projection	UTM
False Easting	500000
False Northing	0
Latitude of Origin	0º00'00.000000''
Central Meridian	3º00'00.000000''
UTM Zone	30 N
Scale Factor on CM	0.9996
Units:	Meters

1.3.2. Vertical datum

Vertical datum used by the Qinsy software is LAT Bathyelli v2 geoid published by the SHOM in December 2013. The Bathyelli LAT (SHOM 2013) is a surface based on the GRS 1980 spheroid. The same geoid model was used for the AO4 survey in 2021.

1.3.3. Tidal reduction

To carry out the survey as accurately as possible, Tecnoambiente utilised MarineStar PPP corrections via satellite signal. When using an accurate GNSS system (RTK correction), the tidal corrections are carried out in real-time through Qinsy computations, as shown in Figure 1-6.

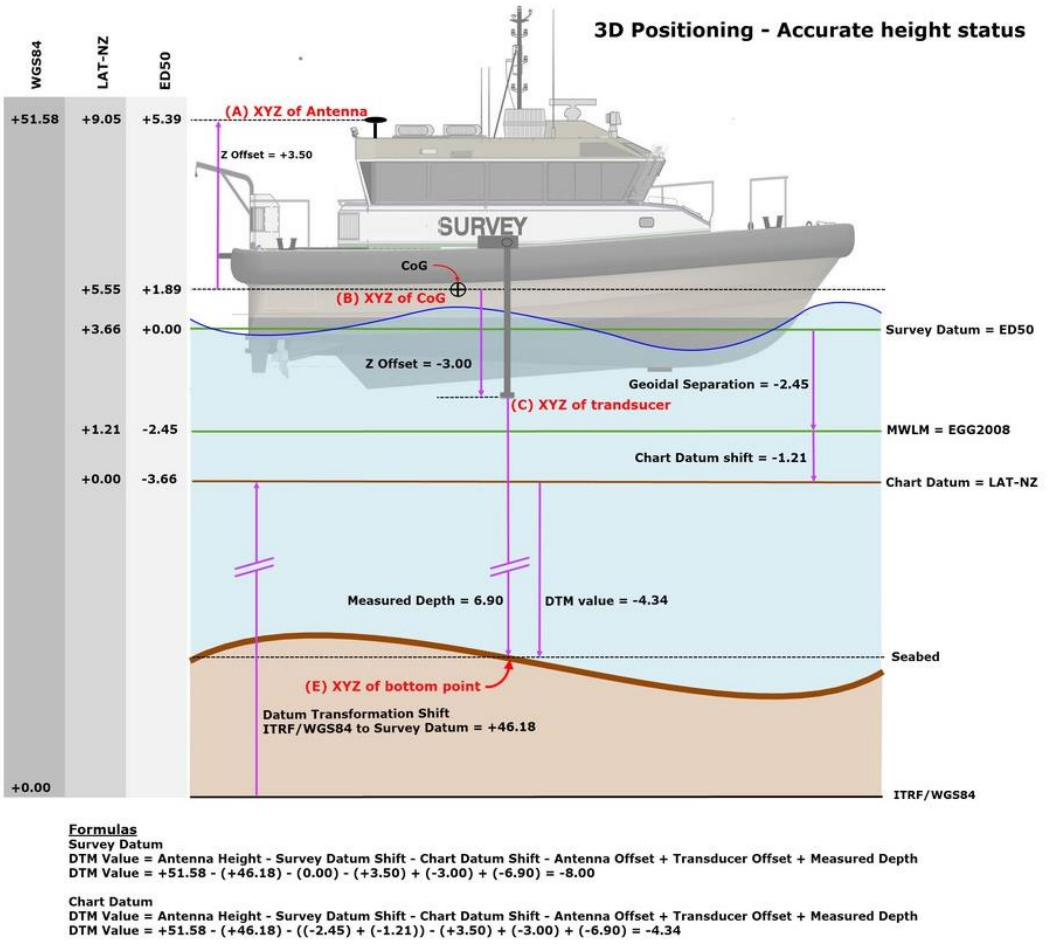


Figure 1-6: Qinsy's method for accurate height calculation.

The separation between WGS84 ellipsoid (GRS80) and the vertical datum is a model called Bathyelli v2, it is a set of surfaces, each of which defines the separation of one vertical datum from the WGS84 ellipsoid. If corrections drop out, they can be applied in post processing.

2. GEOPHYSICAL DATASET

2.1. QA/QC CHECK

The processed values obtained from the onboard processing team during the survey were checked before the ALARP certificate phase. This quality control check of the input data validates the quality of the processing method. Here is the QA/QC for the measurements made:

- QC0: check of the geophysical value
- QC1: Check of the sensor position
- QC2: Check of the altitude of sensor and dynamic coverage
- QC3: Check of the noise
- QC4: Check of the speed and sampling frequency

2.2. SIT SURVEY

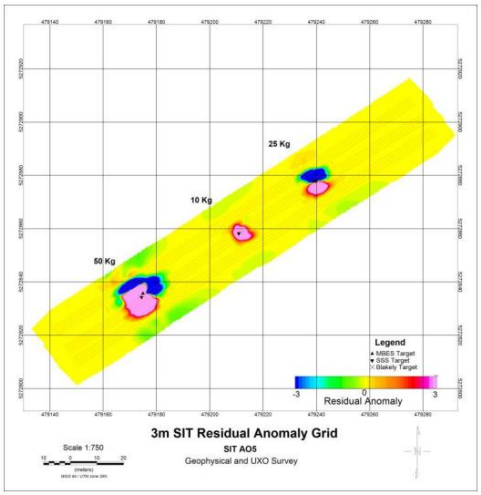
The calibration test (SIT) was carried out using ferrous surrogates, weighing 10 kg, 25 kg and 50 kg, respectively, in order to be consistent with the historical data (Ref 01) considering the lowest detectable magnetic signal and the largest ammunition size, such as German airplane- deployed magnetic mines LMA (Luftmine A) and LMB (Luftmine B). This test makes it possible to estimate the precision of the survey positioning, the amplitude of the signal to be sought and the detectability distance.

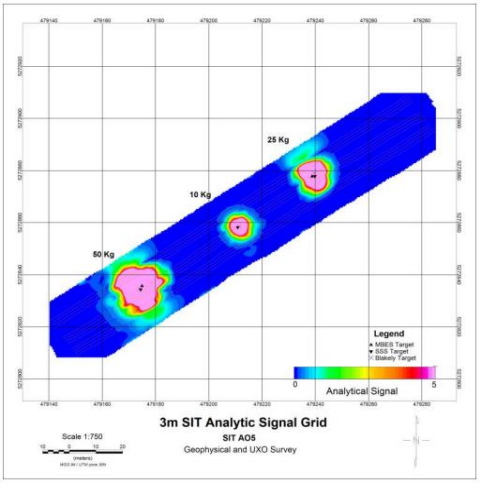
After mapping an area to make sure it was clear of potential targets, the surrogates were immerged. Several altitudes were used to perform the test above the surrogate: 3 m, 5 m, and 6 m (Figure 2-1). On the diverse altitude map, all three surrogates are detectable (Ref 05). However, the amplitude of the signal at a 6 m altitude for the 10kg weight is only 0.8 nT/m, well under the used cut-off of 2 nT/m.

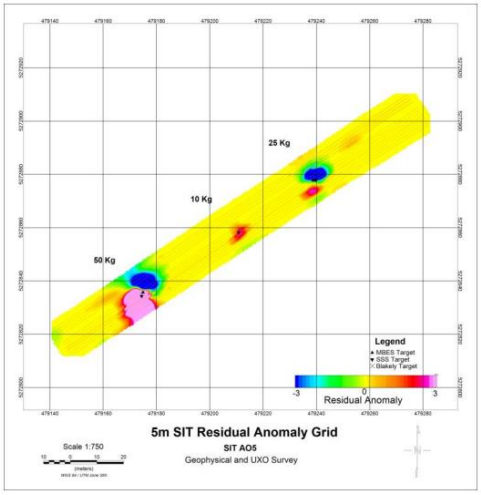
From these SIT data we were able to estimate:

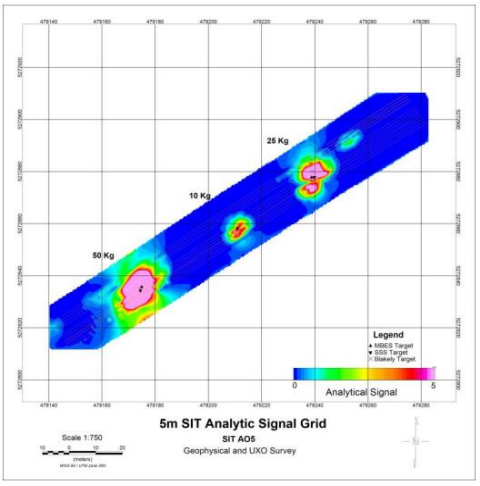
- The uncertainty of the survey at 2.5 m. average (Tables 3, 4 and 5)

- A detection range of 6 m for a ferrous mass greater than 25 kg
- A detection range of 4 m for a ferrous mass of about 10 kg, which may/may not correspond to LMB/LMA munitions









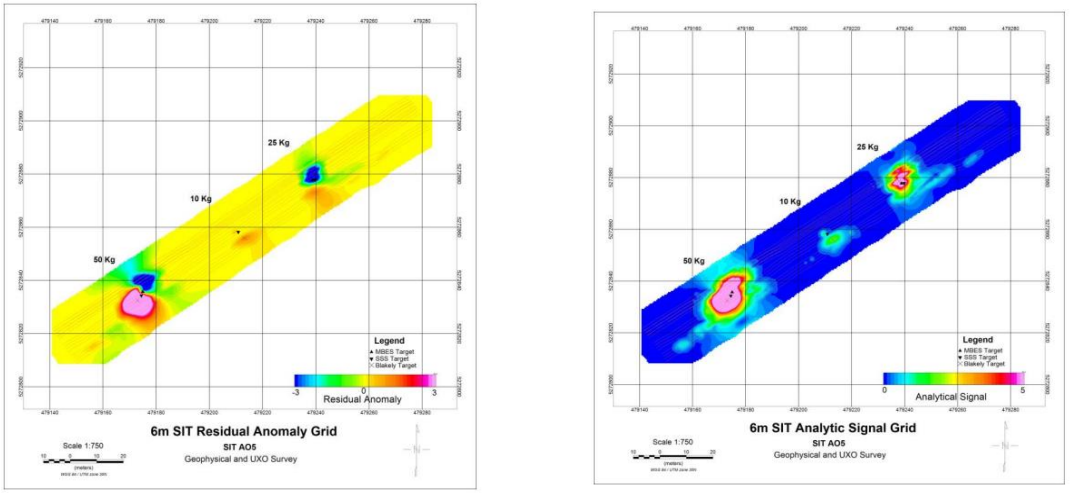


Figure 2-1: Result from the SIT, Residual field, and Analytic signal at 3m and 6 m altitude.

Table 3: Position verification of 10 Kg item.

	Source	Easting (m)	Northing (m)	Δ Easting (m)	Δ Northing (m)	Total Deviation (m)
10 Kg Surrogate Item	SSS position	479210.87	5272858.14	N/A	N/A	N/A
	Blakely test @ 3m	479211.5	5272859.0	0.63	0.87	1.08m
	Blakely test @ 5.0m	479212.50	5272857.50	1.64	0.64	1.72
	Blakely test @ 6.0m	479213.00	5272856.00	2.13	2.14	3.01

Table 4: Position verification of 25 Kg item.

	Source	Easting (m)	Northing (m)	Δ Easting (m)	Δ Northing (m)	Total Deviation (m)
25 Kg Surrogate Item	SSS position	479239.83	5272877.72	N/A	N/A	N/A
	Blakely test @ 3.0m	479239.5	5272879.00	-0.33	1.28	1.32
	Blakely test @ 5.0m	479239.00	5272880.00	0.81	2.27	2.41
	Blakely test @ 6.0m	479238.00	5272878.50	1.83	0.76	1.99

Table 5: Position verification of 72 Kg item.

	Source	Easting (m)	Northing (m)	Δ Easting (m)	Δ Northing (m)	Total Deviation (m)
50 Kg Surrogate Item	SSS position	479174.40	5272834.28	N/A	N/A	N/A
	Blakely test @ 3.0m	479174.00	5272835.00	0.40	0.26	0.47
	Blakely test @ 5.0m	479174.50	5515635.50	0.1	0.72	0.81
	Blakely test @ 6.0m	479173.00	5272832.50	1.40	1.78	2.24

Thanks to the SIT trial performed before the data acquisition, it was possible to detect LMA/LMB mines that were laying on the seabed. Depth of burial data for locating buried LMA/LMB mines was found to be inaccurate and was discarded. The very low probability of finding this type of buried target is described in the ALARP certificates.

3. DATA ACQUISITION

3.1. SURVEY ACQUISITION SCHEME

To ensure full coverage of the UXO box within the AO8 offshore substation area, data acquisition during the survey was carried out as follows:

Table 6: UXO data acquisition scheme information

Methodology	Survey lines	Range
Multibeam echosounder system (MBES)	6 m	75 m
Side Scan Sonar (SSS)		100 m
Gradiometer (MAG)		8 m

The following figure shows the basic data acquisition scheme for the UXO phase.

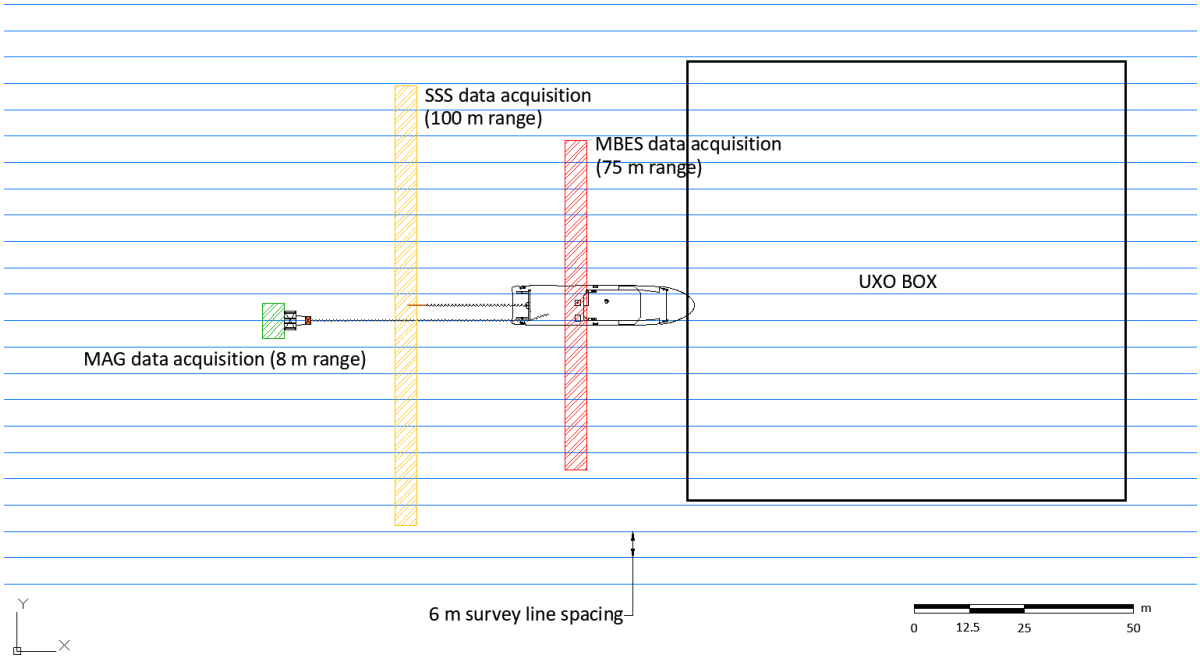


Figure 3-1: UXO data acquisition scheme.

The data acquisition of the three methodologies is performed not only in the target area, but the acquisition is extended to adjacent areas. This is done for two main reasons: on one hand, the line plan covers a larger area as a run-in/run-out zone to stabilize the sensors on the seabed; and on the other hand, to cover a larger area than the target area and thus obtain more data in case the UXO box has to be moved to a quieter area if necessary.

3.2. MULTIBEAM ECHOSOUNDER

The objective of this phase of data acquisition is the detection of possible MBES targets lying on the seabed. Due to the coverage requirements of gradiometer data acquisition, this required total coverage of the seabed within the OSS UXO box, and hence a survey line spacing of 6 metres was utilised.

During data acquisition, the vessel's master must follow previously programmed routes along the project lines, shown on the computer screen (Helmsmann indicator). If the actual

course deviates from the programmed route by more than a specified amount, or when there is a problem with a peripheral, such as a loss of GPS corrections, the vessel master is warned by the use of visual and audible alarms.

While the master follows the navigation lines, the acquisition module of the hydrography program captures all of the position data sent by the GPS, the raw values of the movement reference unit (Hydrins III) and the heading of the equipment; to correct the location of the soundings sent by the multibeam echosounder. This correction is made for each transmission pulse in real-time.

Parallel to data entry, data acquired by the equipment and peripherals are synchronized. This process is carried out by Qinsy and is complemented by the input of the time and the pulse per second (PPS) provided by the MRU, so that all data is time synchronised.

The guidelines followed by Tecnoambiente during the surveying for MBES data acquisition are as follows:

- IT-CM-36 SVP Deployment Recovery, Rev1.0
- IT-CM-01. Guidelines for Hydrography Project management, 5
- IT-CM-04. Bathymetric survey, 1
- IT-CM-14 Survey Basics Guidance, 1
- IT-CM-15 Online Surveying procedure, 3

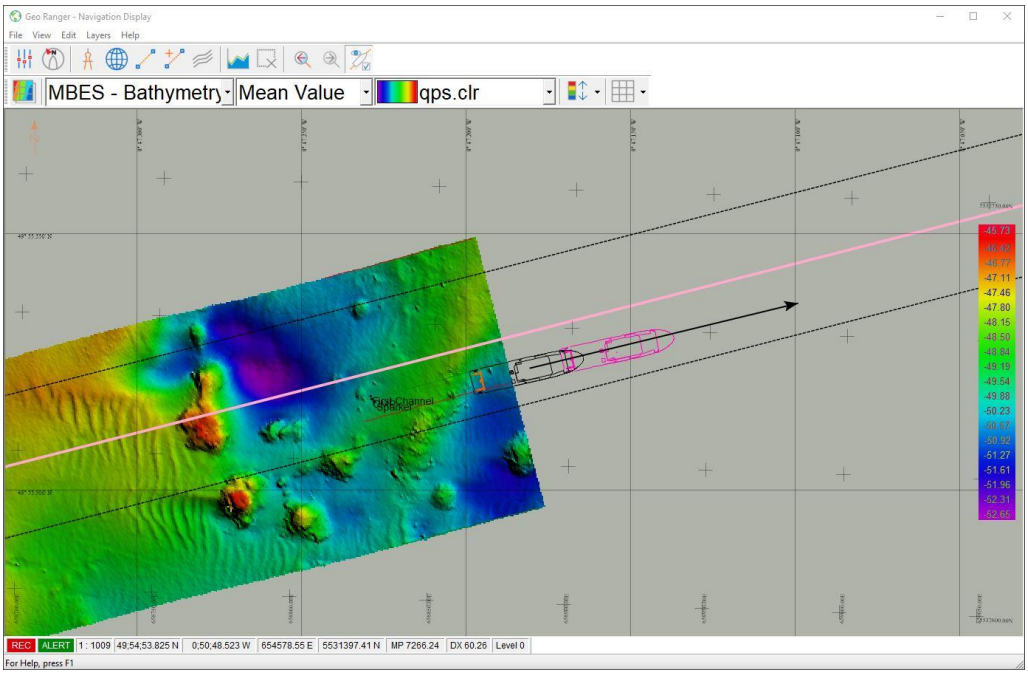


Figure 3-2: MBES bathymetry data acquisition with the Qinsy software.

During data acquisition, limits were applied to reduce soundings noise. These limits in the recording correspond to static gates of the equipment software that reduce the acquired registers noise, in accordance with statistical calculations of vertical uncertainty.

During the processing phase of acquired data, the lines on the screen are processed, in order to manually correct any noise that appears in the records. Noise is produced by multiple factors such as, multipath in position, air bubbles, cetaceans, motor interference from the vessel, etc., in the digital register of soundings. To make certain of the complete removal of any noise in the soundings, spike filters and spline filters were applied.

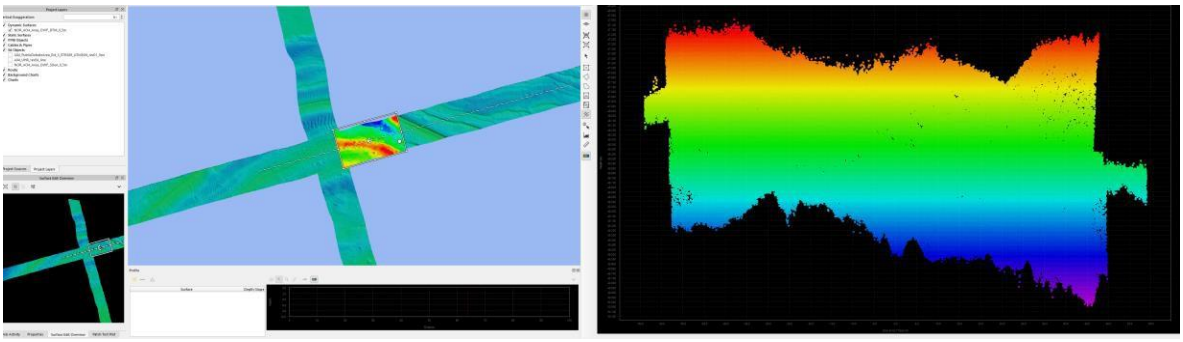


Figure 3-3: Processing screen of MBES bathymetry data with the Qimera software.

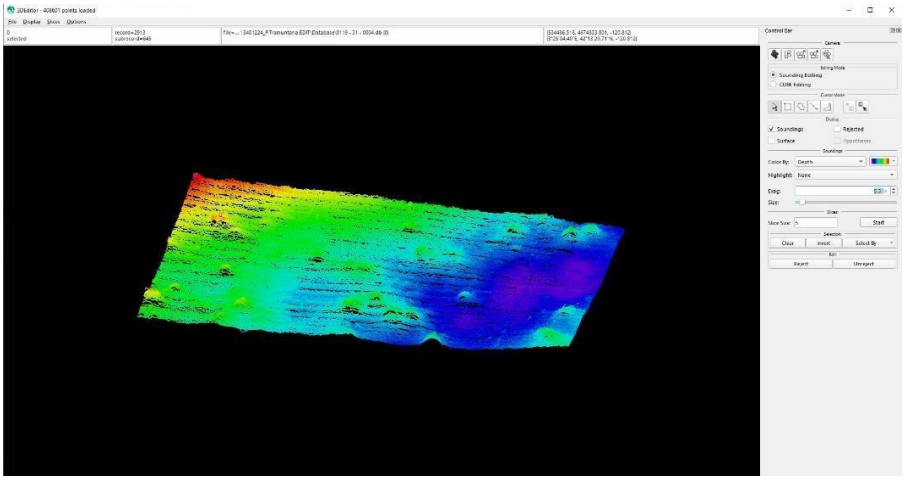


Figure 3-4: 3D image of the MBES bathymetry processing.

Once any possible existing errors in the records were deleted, a digital model of the terrain with 0.1 x 0.1 m grid size was produced, with a minimum cell size to obtain the maximum resolution of the seabed.

Digital terrain models (DTM) are created in Qimera. Once done, the DTM's are exported as 32bits RGB Geotiff, for each of the UXO boxes.

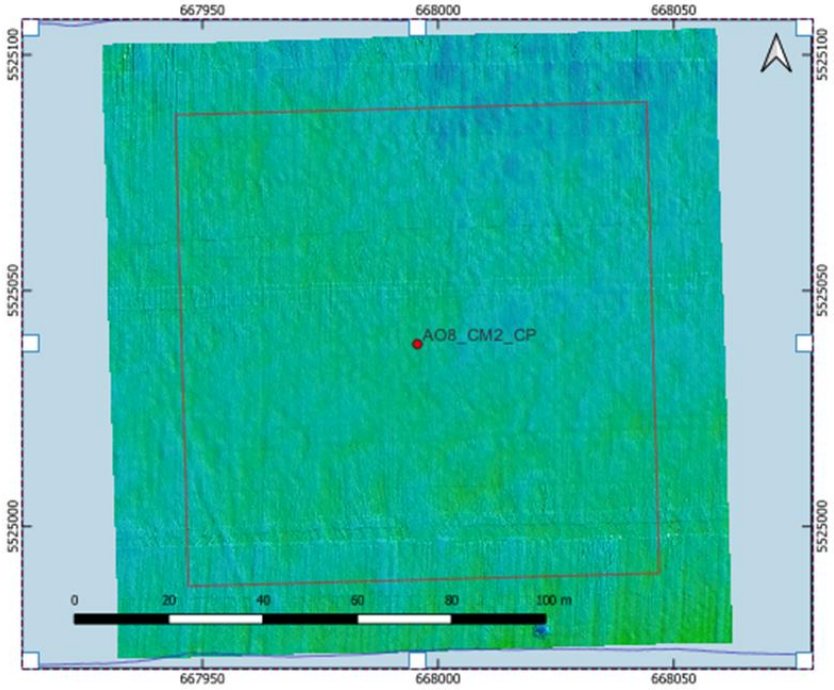


Figure 3-5: Example of the bathymetric data for AO8 OSS.

3.3. SIDE SCAN SONAR – UXO SURVEY

The objective of this phase of data acquisition is the detection of possible sonar targets lying on the seabed. Due to the coverage requirements of gradiometer data acquisition, this required total coverage of the seabed within the UXO box, and hence a survey line spacing of 6 metres was utilised.

A side scan sonar system comprises a processing unit connected through a cable to a wet unit that transmits and receives acoustic energy. Side scan sonar can determine seabed morphology and configuration by means of acoustic signals. It can also determine its composition, identifying different seabed strata as hard (rocky or consolidated), soft or sedimentary, as well as identifying areas of seagrass.

Side scan sonar systems can work in different frequency ranges: systems working in high frequencies, (between 500 kHz and 900kHz) offer higher resolution but lower ranges, with systems working in low frequencies (100 kHz), offer lower resolution but higher ranges. For this survey, a frequency of 900KHz was utilised. The reflection of the signal coming from the seabed is detected by the same transducers, amplified and transmitted to the control unit, and recorded and displayed on the computer screen, providing an acoustic map. With this data, it is possible to identify different seabed morphologies, together with the visualization of any seabed objects.

When the vessel is underway, the winch operator can start deploying cable until the fish gets to the desired working depth of about 6 m above the seabed.

The guidelines followed by Tecnoambiente during the surveying for SSS data acquisition are:

- IT-CM-01. SBL-SSS,1
- IT-CM-21. SSS Launch and Recovery, 0
- IT-CM-13. Geophysical Data Acquisition. General Procedure, 2
- IT-CM-14. Survey Basics Guidance, 0
- IT-CM-15. Online Surveying procedure, 3
- IT-CM-18. USBL Pole Deployment, 1

Once the SSS data were acquired and then exported into JSF format, the files are imported into the SonarWiz 7 software. Channels 3 and 4 were used for recording the high frequency data.

After data importation into the SonarWiz 7 software, an initial navigation correction was made for each imported file, applying smoothing filters to avoid errors in the heading of the tow fish. The track position was smoothed using a mean value of 300 pings.

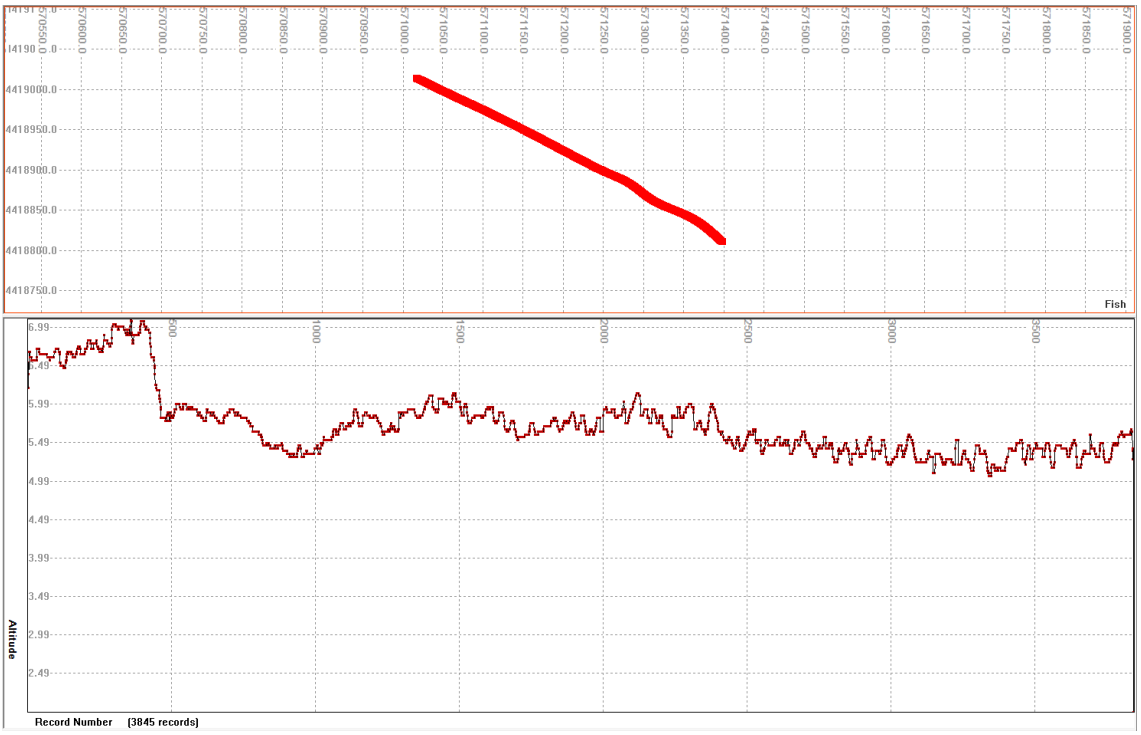


Figure 3-6: Navigation editor in SonarWiz 7.

After the aforementioned corrections were implemented, the water column for each file was eliminated, by applying the bottom-tracking acquired during the survey, as shown in Figure 3-7. If bottom-tracking of the tow fish failed during the survey, it was done automatically by applying filters or by drawing the seabed manually during post-processing. This enables slant range corrections for the digital data to be as accurate as possible.

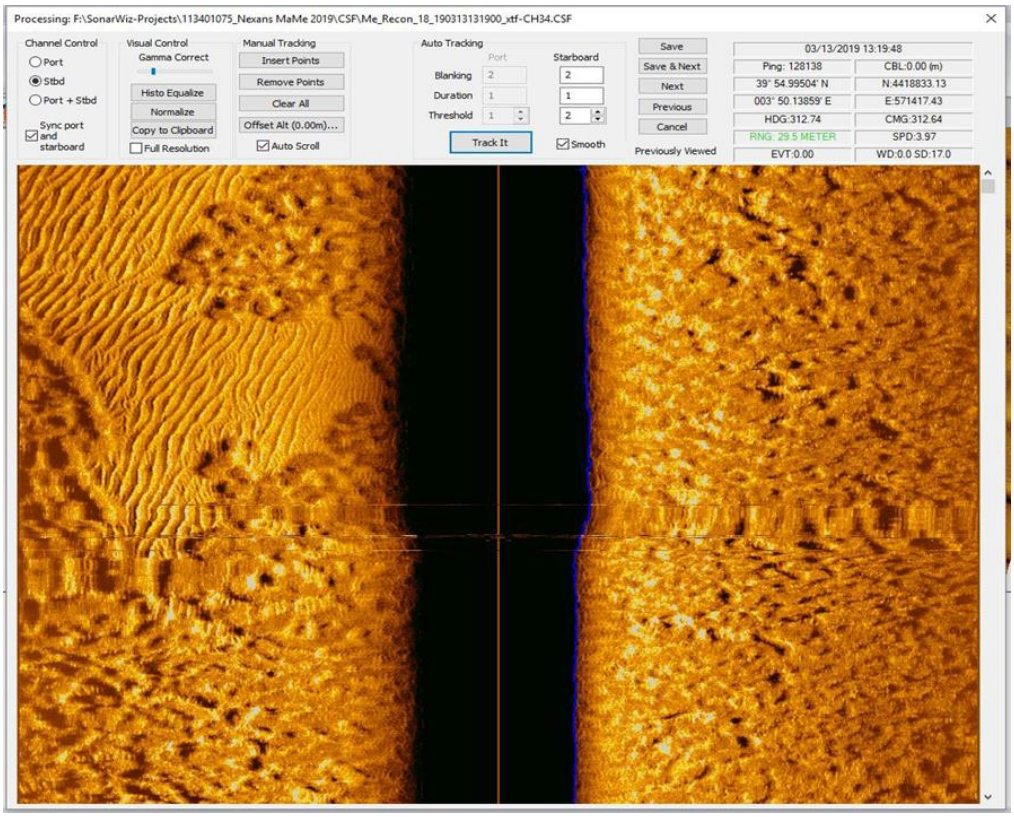


Figure 3-7: Bottom tracking processing drawn in blue in the SonarWiz software.

The following steps during SSS processing in the SonarWiz 7 software are the application and enabling of the EGN filter, and the enabling of the de-stripe filter.

At this point during data processing, a processed MBES geotiff is imported into the project. Using the MBES information, rotations to the SSS file are applied, in order to match feature orientations seen in the MBES data. Where necessary, a move offset can be applied to the SSS file, in order to match features within the MBES data.

Any observable contact within the area of interest is picked and its dimensions are measured.

The final processing step is the export of the sonar files into a GIS software package, where all of the information is integrated, and a sonar mosaic is generated. This is carried out by converting the JSF files into 32bits RGB Geotiff images, to obtain georeferenced images of the processed data, with a resolution of 0.1 m.

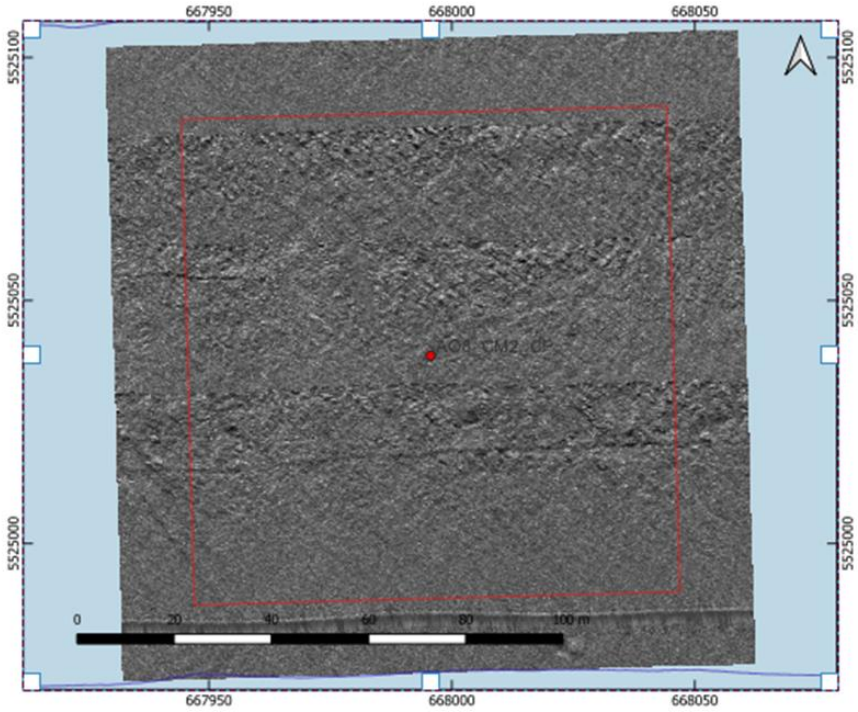


Figure 3-8: Example of the side scan sonar data for AO8 OSS.

The guidelines followed by Tecnoambiente during the surveying for SSS data processing are:

- IT-CM-01. SBL-SSS,1
- IT-CM-27. SSS Processing procedure, 0

3.4. GRADIOMETER – UXO SURVEY

Magnetometer data were recorded using four Geometrics G-882 magnetometers fitted in a custom frame and spaced 1.1 metres apart, horizontally. Survey line spacing was set at 6 metres. The frame has an automated bottom tracking function, allowing it to keep a fixed height above the seabed. After merging in Qinsy, all raw data were timestamped and output as TXT files were recorded for each magnetometer (Mag 1, Mag 2, Mag 3, and Mag 4).

Figure 3-9: ROTV with the fixed frame system for MAG acquisition.

The guidelines followed by Tecnoambiente during the surveying for MAG-UXO data acquisition are:

- IT-CM-25. UXO Mooring Procedures,0
- IT-CM-18. USBL Pole Deployment, 1
- IT-CM-26. UXO Scanfish Launch and Recovery, 0

Data was processed using UXO Marine Mag module from OASIS software.

Positioning and altitude data were corrected to eliminate outliers (despiked), then filtered, and smoothed. Incorrect positions were removed, and the positions were filtered using a non-linear filter. All altitudes greater than 4 m were removed from the database.

The magnetometer data were corrected to eliminate aberrant values (“despiking”). They were also interpolated, but were also slightly smoothed, so as not to lose the weaker components of the signal.

The magnetometer values were then processed, in order to compensate for variations in the altitude of the fish (increase in the signal when the magnetometer approaches the seabed). The magnetometer values were recalculated at a constant virtual altitude of 3 m above the seabed. The altitudes were smoothed, using a B-Spline filter. Processed positions and altitudes were then exported, to calculate dynamic coverage.

Finally, the long-wavelength component of the Earth's magnetic field was calculated using several successive non-linear filters. This long wavelength component includes diurnal variations, geological variations, and noise, as well as the International Geomagnetic Reference Field (IGRF). This was then eliminated from the data set, resulting in a residual component, comprising primarily anthropogenic magnetic anomalies.

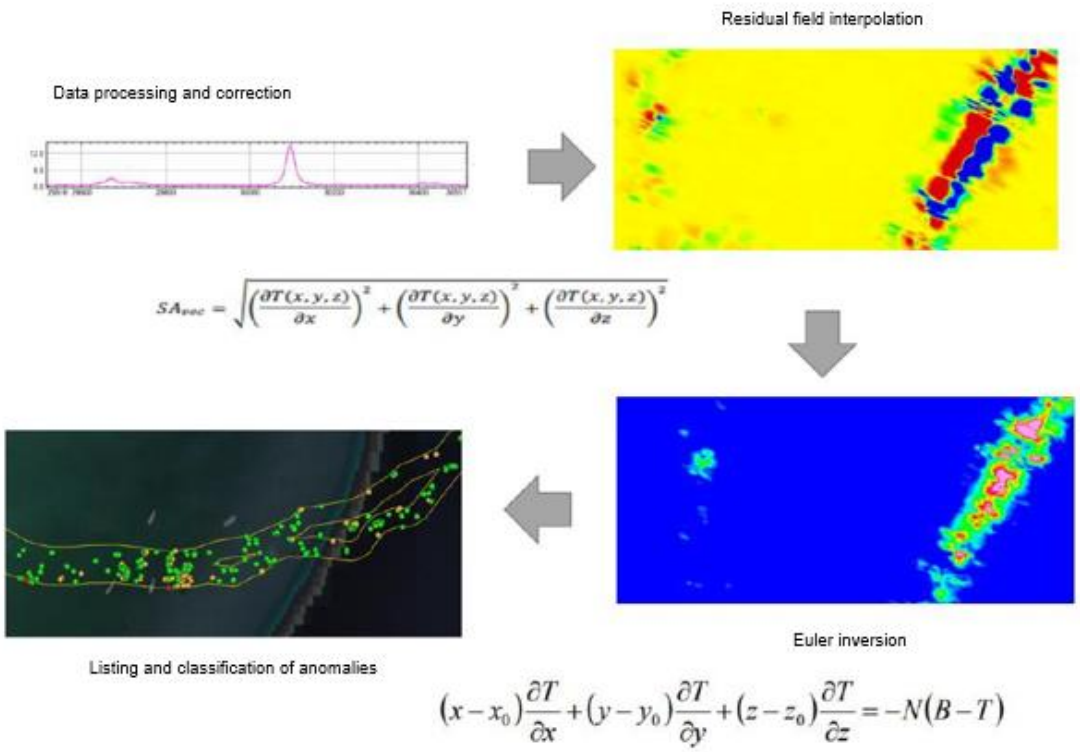


Figure 3-10: Processing workflow of magnetometer data.

A 2D map of the magnetic anomalies within the survey area was produced by interpolating these data, using a 0.25 m grid and 5 m blanking distance. The amplitude of the analytic signal was calculated using a 3D grid. The analytic signal is utilized for the mapping of structures and for the more precise positioning of any targets.

The results of the magnetometric measurements are included as two maps:

- A map of the residual magnetic field (in nT)
- A map of the analytical signal (in nT/m)

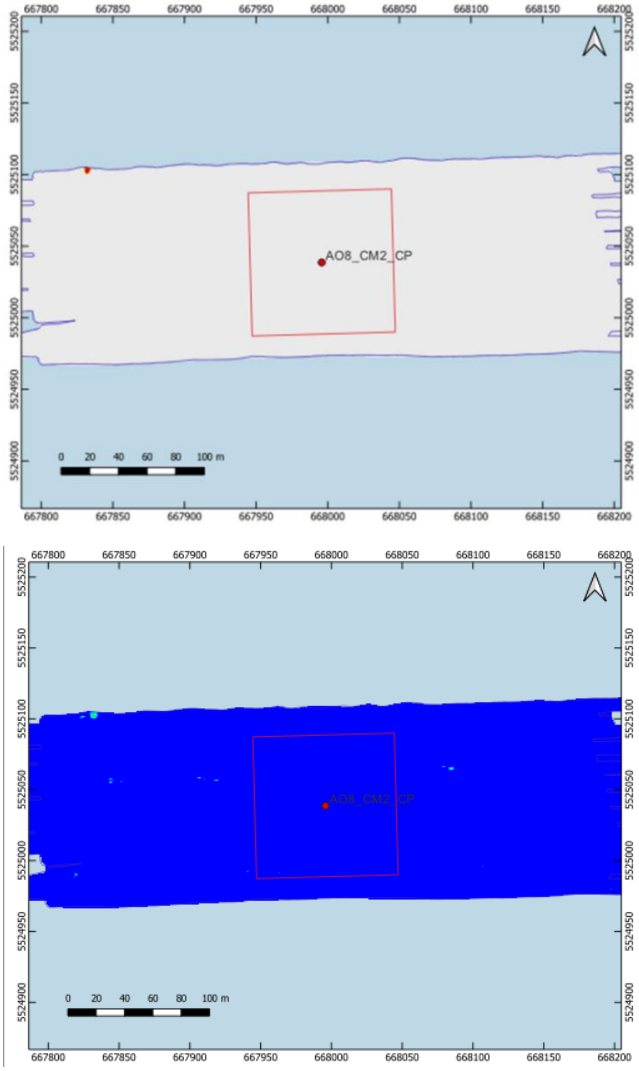


Figure 3-11: Example of the maps of the residual field and the analytic signal for AO8 OSS.

The magnetometer coverage depended on the spacing width of the surveyed lines and the height above seabed of the measuring device, making it possible to ensure the detection of an object at any point, by knowing the distance between the measuring sensor and the object. The requirements of the Scope of Work were met throughout the surveyed areas, i.e. detection of a 25 kg ferrous mass at a depth of 2 m and a maximum detection distance of 6 m (*Penella 1982*).

The dynamic coverage was calculated for a detection range (Δ) determined by the mass of the smallest object we were looking for and the depth below seabed of the soil intrusive activity.

The detection radius (d) under sensor was then calculated for each point with the formula:

$$d = \sqrt{\Delta^2 - (alt + DBSF)^2}$$

Where:

Δ = Detection range

DBSF= Depth below seafloor

alt= Altitude of sensor

For the detection range of 6 m and depth of 2 m defined for this survey, the formula is defined as follows:

$$d = \sqrt{6^2 - (alt + 2)^2}$$

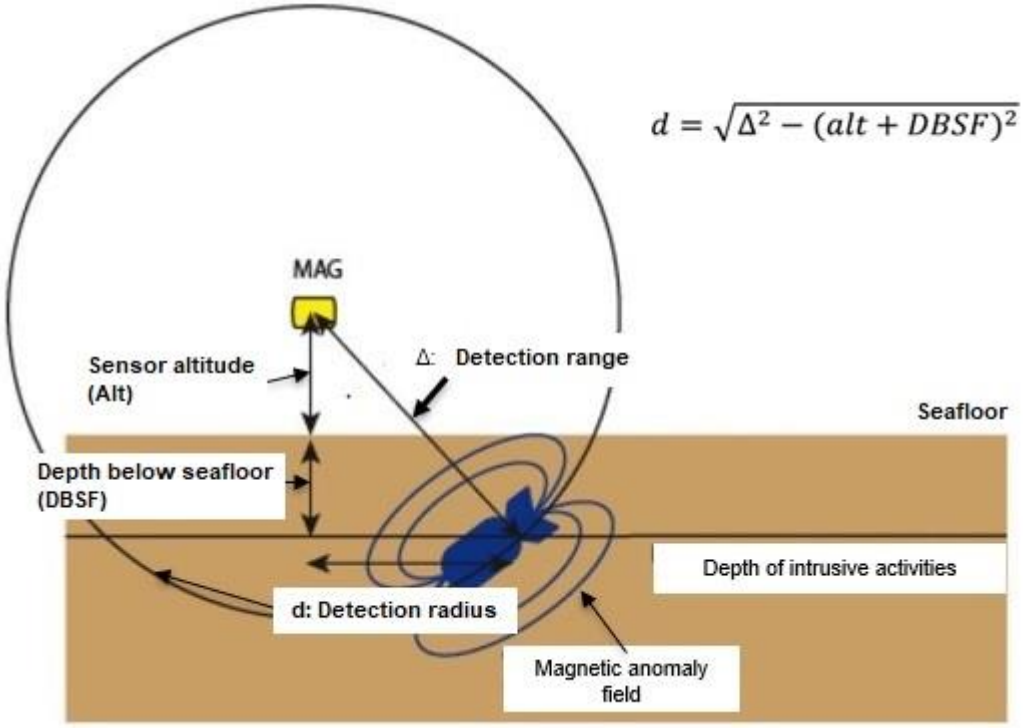


Figure 3-12:.Dynamic coverage calculations.

This means that for each point of data, a circle of detection with radius d is drawn around this point. The data were opened within a GIS software package (QGIS). Drawing these circles in the GIS software, using a buffer of detection ranges, enables us to map the detection coverage and identify any data gaps.

4. RESULTS

4.1. COVERAGE AREA

The survey took place over the OSS GI box for a magnetometer coverage of 10,000 m^2.

Table 7: Magnetometer coverage area (centroid of the GI box).

BOX	MAGNETOMETER SURVEY AREA WITH 100% DYNAMIC COVERAGE (m2)
AO8_OSS	10000

TOTAL	10000

4.2. ANOMALY PICKING

4.2.1. Magnetic anomalies

Visualization of the residual field map (in nT) makes it possible to locate any dipole anomalies present. The map analysis threshold (sensitivity of the display via the adjustment of the colour scale) is very important to validate the interpretation. By gradually decreasing the analysis threshold, it is possible to image anomalies of lower intensity. After analysis of the data, anomalies were manually picked, using the colour scale presented in Figure 4-1.

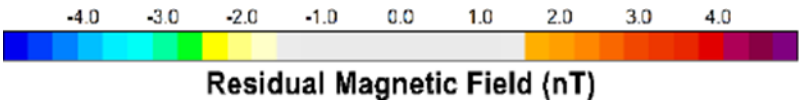


Figure 4-1: Colour scale and threshold used for analysis of magnetic anomalies.

Anomalies are also detected automatically from the analytical signal grid with a 1.0 nT/m threshold (grid value cut-off of 1nT/m).
Two (2) magnetic anomalies were detected within the OSS survey area (listings are provided in Appendix I).

4.2.2. MBES and side scan sonar contacts

MBES and side scan sonar data were only analysed within a 65 m radius of the central point of the original OSS box location. One (1) sonar contact and one MBES contact were detected within (Listings in Appendix II and III).

4.3. DISCRIMINATION OF pUXO TARGETS

Magnetic anomalies indicate the presence of ferrous elements at or below the seabed. This is true for most types of unexploded ordnance (UXO), with the exception of the aluminium LMB.

Any magnetic anomaly can therefore correspond to a potential UXO

The historical study shows a proven risk of LMA/LMB for the AO8 region. These objects are weakly magnetic and can be considered as the equivalent of a 10 kg iron weight. This is the reason that this weight of ferrous mass was considered, during the preparation of the SIT. Consequently, the LMA/LMB risk is currently considered at seabed level, both by magnetometer detectability (about 13nT) and by the analysis of side scan sonar and MBES images.

Therefore:

- Any side scan sonar and MBES contact with a magnetic signature are considered as pUXO.
- Shape and length of side scan sonar and MBES data were analysed carefully for discrimination as non-UXO.

- Side scan sonar and MBES contacts without magnetic signatures and without any corresponding shape and length criteria are considered as non-UXO. But as these contacts correspond to potential obstructions on the seabed, they were mapped without any avoidance area indicated on the ALARP certificate maps.

5. AVOIDANCE DISTANCES

Following the analysis, we are looking for as low as reasonably practicable (ALARP), areas that can be considered clear of any pUXO. The avoidance criteria have been defined following the UXO threat and risk assessment with geotechnical investigation risk mitigation strategy recognised and desktop studies (**Ref. 01**):

Thus, the avoidance distance can be calculated as follows (Figure 5-1):

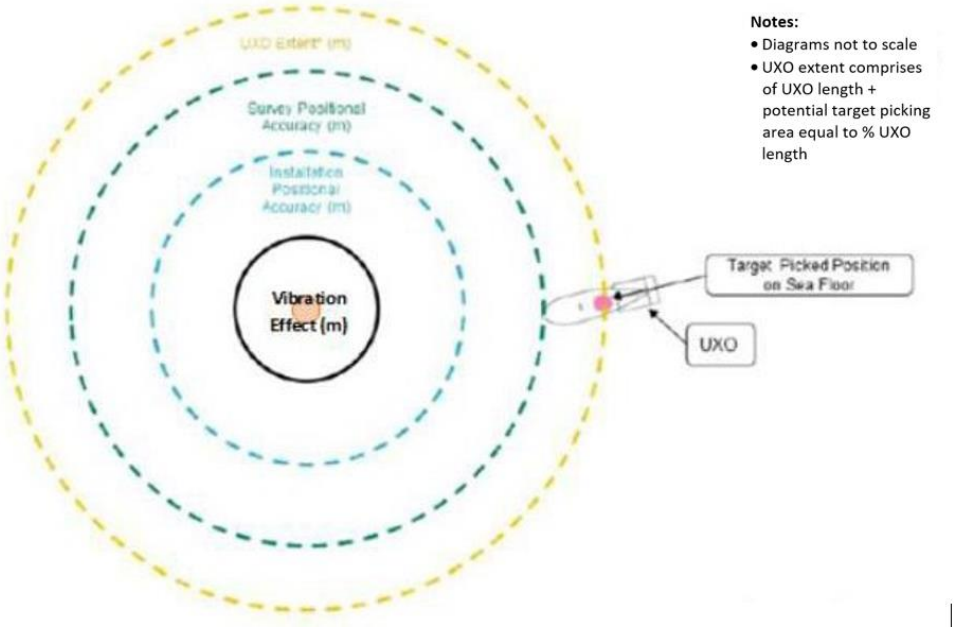


Figure 5-1: Avoidance distances.

Avoidance distance = Geotechnical tool width + Vibration effect distance + Geotechnical tool positioning accuracy + UXO survey accuracy + Ammunition length

The effect of the generation of seismic waves during vibro-driving or pile driving has to be considered in the case of geotechnical drilling or pile driving. These machines generate a wide variety of seismic waves (pressure, Rayleigh, shear) (Study report DRS17-164706-11171B, INERIS) that can trigger UXO detonation. This effect need not be considered for other geotechnical work, such as jack up or anchor installation.

In order to reduce the safety buffer to the necessary distance, a precise calculation of avoidance distance has been explained and detailed in a Technical advisory note (Ref. 07) for the EC corridor. The calculation considers the following elements:

Avoidance distance: Vibration effect (6m) + Geophysical survey accuracy distance (1.9m) + Geotechnical frame (1.25m) + Geotechnical survey accuracy (1m) + UXO extent (3.12m) = 13.27m

A safety buffer of 13.5 m for the AO8 OSS is to be employed from any isolated magnetic anomaly.

This was achieved through geospatial processing by QGIS software.

Firstly, the areas that could not be considered as clear of any pUXO are mapped, grouping the pUXO targets (magnetic anomalies and/or sonar and MBES contacts) and potential saturated areas. Afterwards, the “avoidance areas” were mapped with an avoidance zone of 13.5 metres radius (a 13.5 m safety buffer around the anomaly) away from all the potential UXO (pUXO) anomalies or any saturated or excluded areas. This avoidance area was also applied from the edge of the dataset inwards, towards the centre of the survey area.

The free space between these avoidance areas and the detection surface and the survey limits was then mapped, and a workable area was obtained. This defined the outline of the ALARP certificate (Figure 5-2).

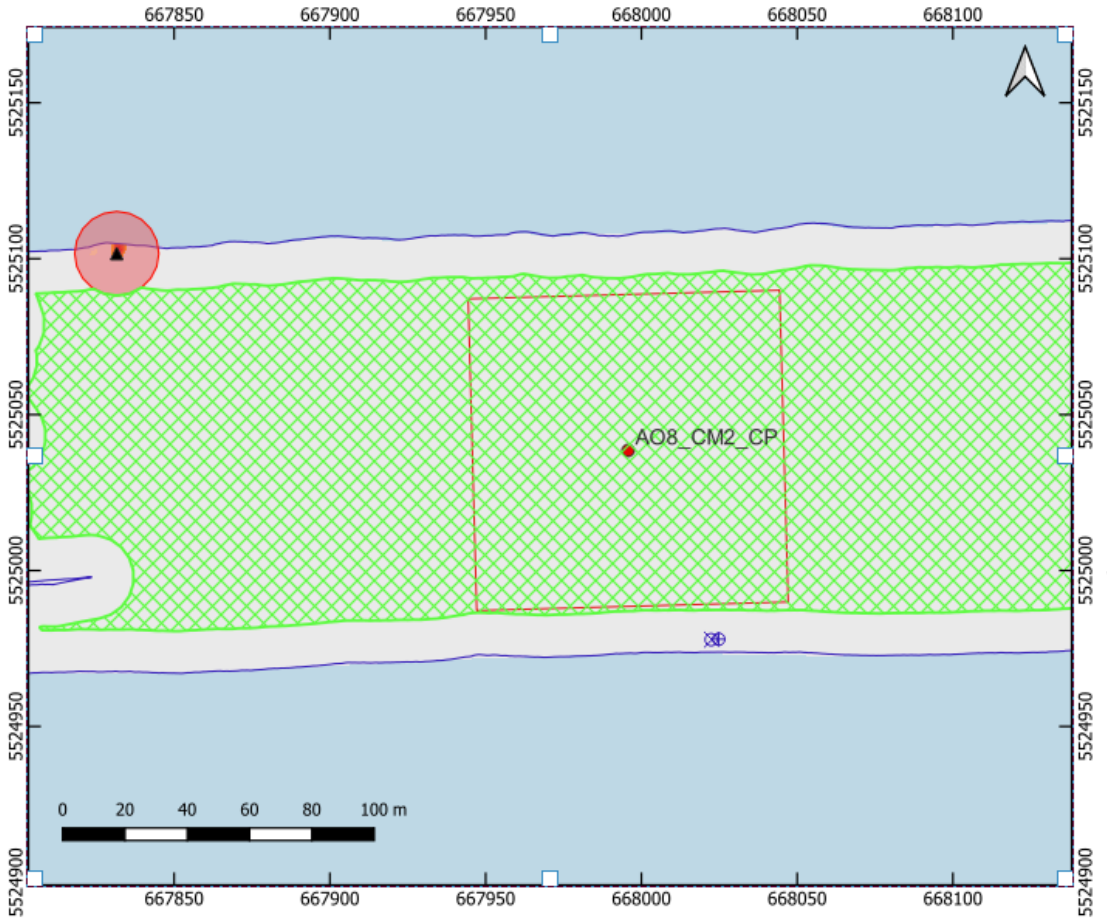


Figure 5-2: Case where the OSS box location is not impacted or little impacted by avoidance areas: an ALARP zone is defined (in green).

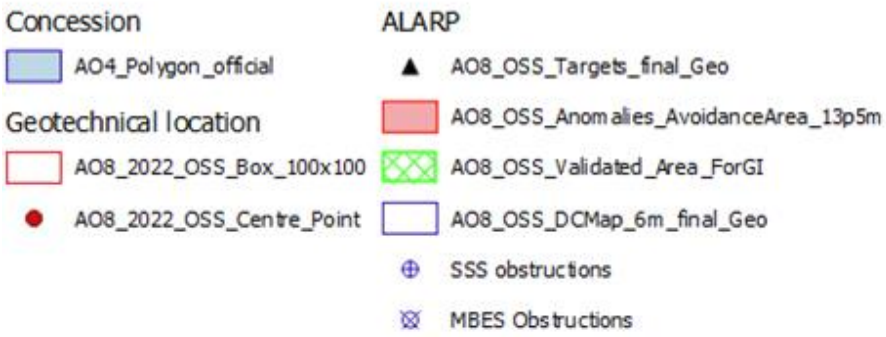


Figure 5-3: Legend of the ALARP maps.

6. CONCLUSION

ALARP areas totalling 10,000 m^2 were identified for the OSS_AO8_CM2 (Table 8).

Table 8: Final ALARP workable areas and GI box location.

ID	Name GI	Easting UTM30N	Northing UTM30N	Workable area (m^2)
1	AO8_CM2_OSS	667995.51	5525038.69	10000
Total				10000

REFERENCES

In accordance with:

- Letter the "*Inspection des poudres et explosifs*" of the French Ministry of Defence and the *"Direction générale du Travail"* of the French Ministry of Labour of September 18th, 2013, relating to pyrotechnic clearance carried out on civil land.
- Decree No. 2014-381 of March 28, 2014, regulatory part Art. R.733-1 to 16 and legislative part Art. L. 733-1 to 3.

In reference to:

- Decree No. 2005-1325 of October 26, 2005, amended from the Ministry of Defence relating to the safety rules applicable during work in the context of a pyrotechnic clearance site and the two implementing decrees.

Ref.01. Unexploded Ordnance Threat and Risk Assessment with Geotechnical Investigation Risk Mitigation Strategy: *8492_1_A04 Normandy_DNGVL_UXO_TARA_with_RMS_Client Draft_V3.0*

Ref.02. Project AO4 De-risk Surveys Scope of Work: *SOS-01 - Scope of Service AO4*

Ref.03. Employer's Requirements Marine Operations: *SVY-ERS-03 – Survey Specification*

Ref.04. Specification for UXO Survey Verification Test RTE Export Cables: *ERS-03-A – SVT Specification*

Ref.05. UXO Surrogate Items report: *SIT report – AO4 and A05 geophysical and UXO survey*

Ref.06. NOR_AO4 Area - Seismic, geophysical and UXO survey - Mobilization Report: *NOR_TEC_21_Mob report - AO4 survey 2022_1.0*

Ref.07. Technical advisory note - Avoidance distance AO4.

Pennella 1982 Magnetometer techniques in the detection of projectiles Final Report, TR239, Naval explosive ordnance technology center

Rapport d'étude DRS 17-164706-11171-B, Impact des vibrations sur la stabilité des carrières souterraines, INERIS, 2017.

APPENDIX I – LIST OF THE MAGNETIC ANOMALIES DETECTED

Nb	Target ID	Easting UTM30N (m)	Northing UTM30N (m)	Status
1	AO8_CM2_01	667831.35	5525101.82	pUXO
2	AO8_CM2_02	668473.57	5525013.13	pUXO

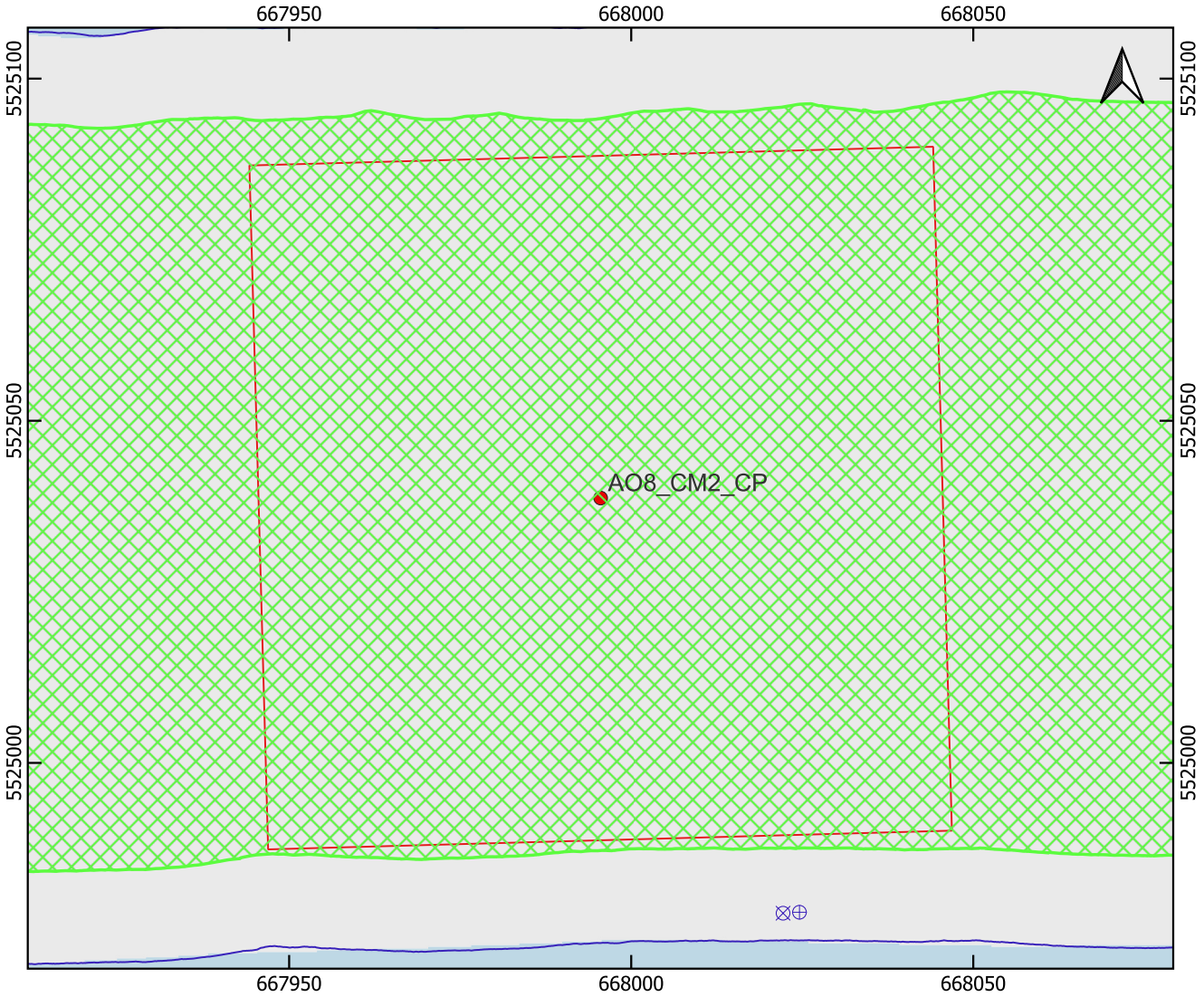
APPENDIX II – LIST OF THE SIDE SCAN CONTACTS DETECTED

Nb	Target ID	Easting UTM30N (m)	Northing UTM30N (m)
1	AO8_CM2_SSS-01	668024.57	5524978.15

APPENDIX III – LIST OF THE MBES CONTACTS DETECTED

Nb	Target ID	Easting UTM30N (m)	Northing UTM30N (m)
1	AO8_CM2_MBES-01	668022.18	5524978.01

APPENDIX IV – ALARP CERTIFICATE MAP



Rte

TECNOAMBIENTE
A TRADEBE COMPANY

MINISTÈRE
DE LA TRANSITION
ÉCOLOGIQUE

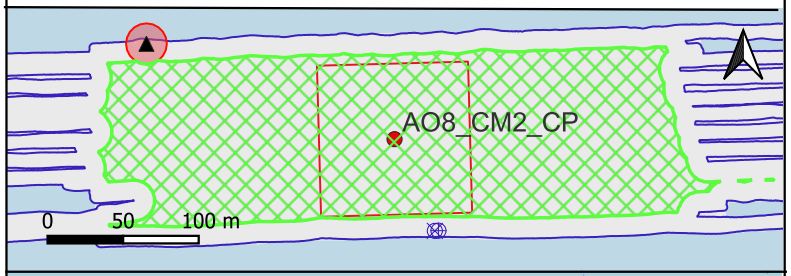
GEOQUIPMARINE

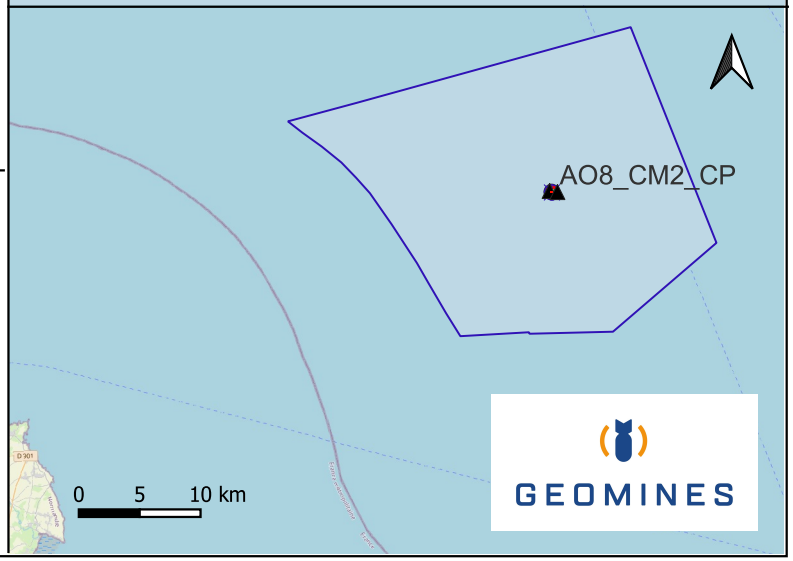
ANNEXE A: AO8 CM2 OSS
ALARP CERTIFICATE GIS

Scale: 1/1000
Geodesy : WGS 84 - UTM 30N

Date: 2022-05-24
Version: V0

0 10 20 30 40 50 m





GEOMINES

Concession

- AO4_Polygon_official

Geotechnical location

- AO8 CM2_OSS_Box_100x100
- AO8 CM2_OSS_center point

ALARP

- CM2_OSS_magnetic anomalies pUXO
- CM2_OSS_Anomalies_Avoidance Area
- CM2_OSS_Validated_Area_ForGI
- CM2_OSS_Dynamic coverage
- SSS obstructions
- MBES Obstructions

Location of center point:

Easting: 667995.51, Northing: 5525038.69

-3.0 -2.0 -1.0 0.0 1.0 2.0 3.0

Residual total magnetic field
(nT)