MOST2 offline tracking reconstruction and alignment

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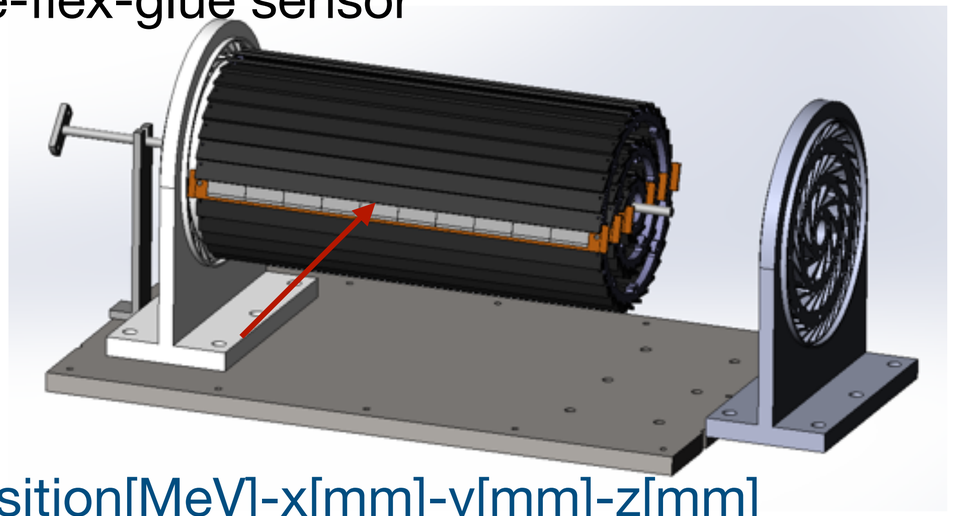
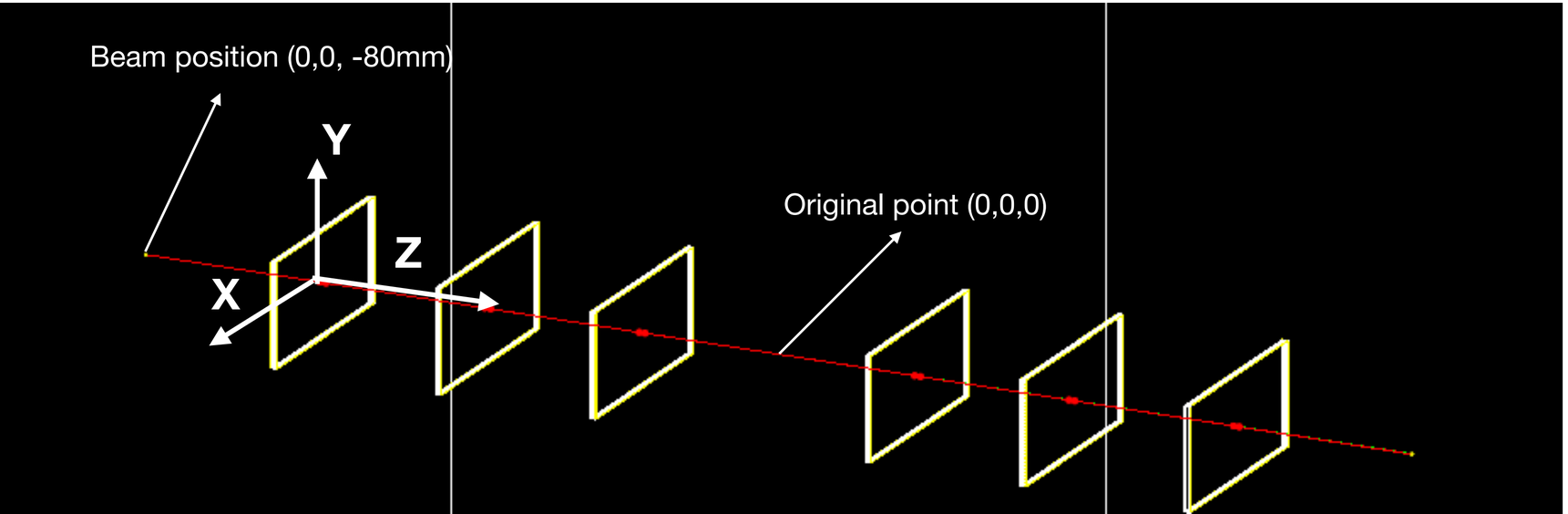
Simulation setup

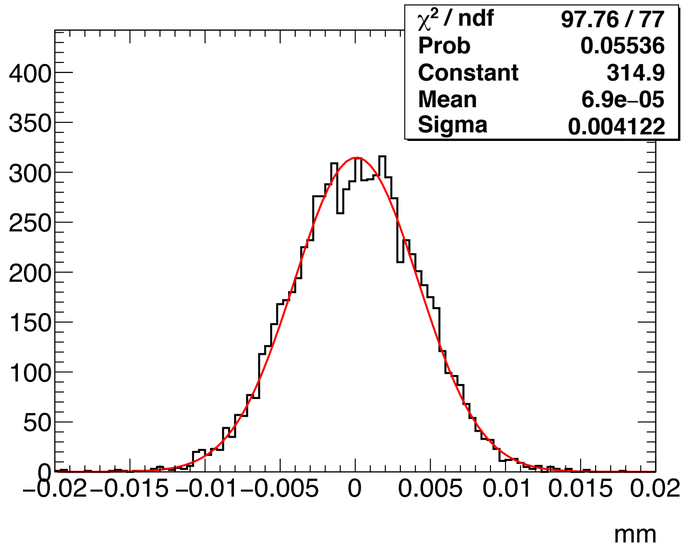
- Electron Beam: 5GeV
- 低能电磁过程
- module structure：sensor-glue-flex-glue- carbon fiber- glue-flex-glue sensor
- module components thickness:
  - sensor(G4_Si): 50um;
  - glue(Epoxy): 60um;
  - flex(Kapton+Al): 74um+26.8um;
  - support(carbon fiber): 250um
- information saved in ROOT File:
  - EventID-TrackID-PlaneID (where the hit at)-Energy deposition[MeV]-x[mm]-y[mm]-z[mm]



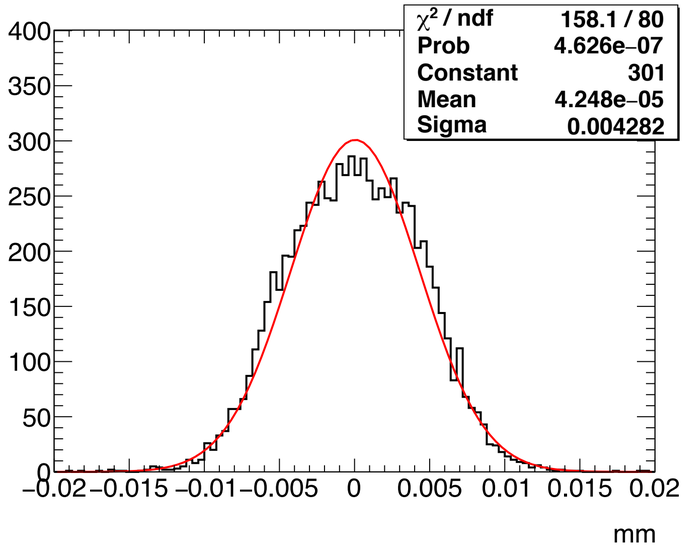


Fitting

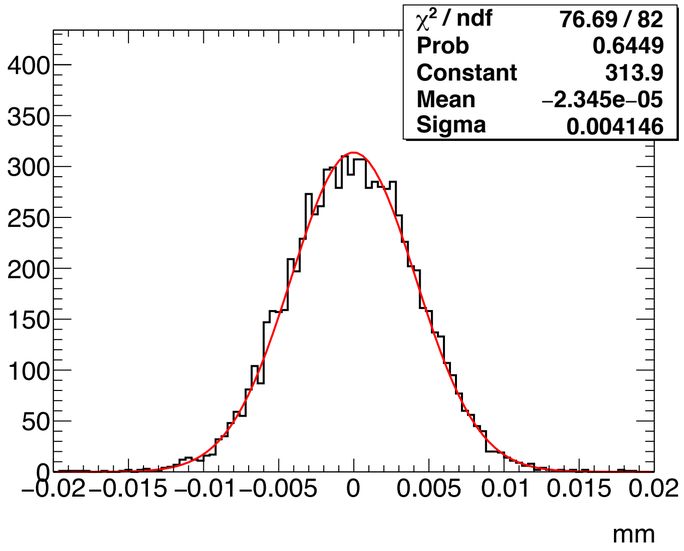
- f(x)=a1*z+b1+x; f(y)=a2*z+b2+y
- Residual for every sensor plane on x, y direction
- Considering detector smearing, sigma = 7um



plane0 x residual



plane6 x residual



plane11 x residual

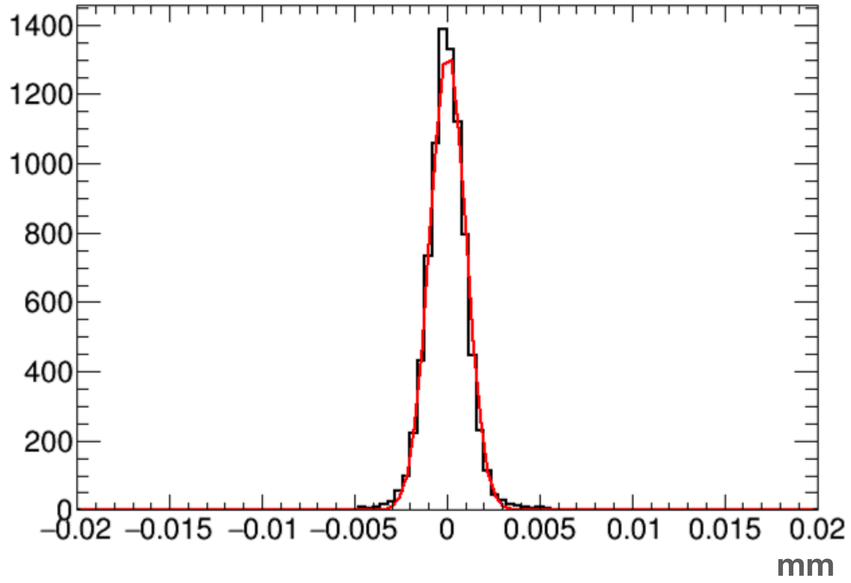
Simulation for different chip thickness

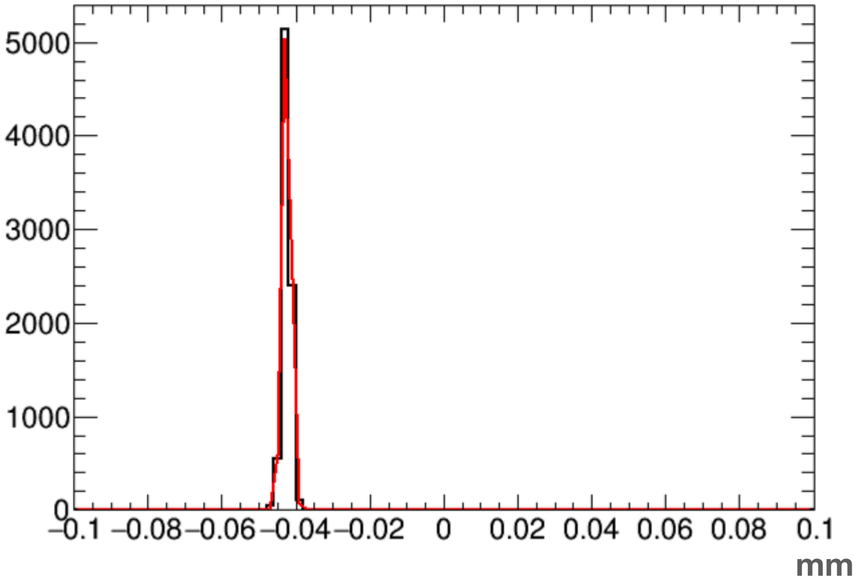
	material budget (X/X0 %)	chip0 sigma (um)	chip2 sigma (um)	chip4 sigma (um)	chip6 sigma (um)	chip8 sigma (um)	chip10 sigma (um)
50um	0.44	4.12	3.62	4.24	4.28	3.66	4.11
100um	0.57	4.58	3.70	4.66	4.60	3.74	4.61
150um	0.69	4.88	3.85	4.77	4.83	3.88	4.75

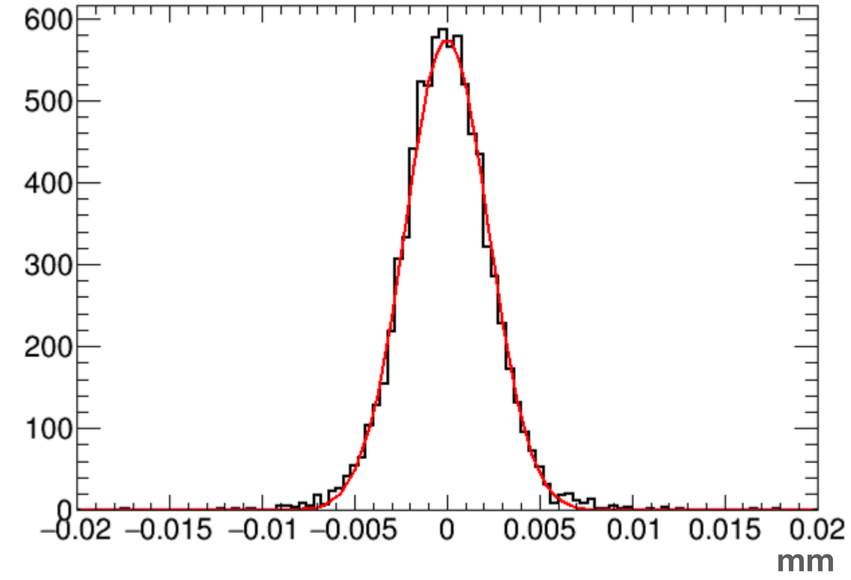
- module structure：sensor-glue-flex-glue- carbon fiber- glue-flex-glue sensor
- module components thickness:
  - sensor(G4_Si): 50um/100um/150um;
  - glue(Epoxy): 60um;
  - flex(Kapton+Al): 74um+26.8um;
  - support(carbon fiber): 250um

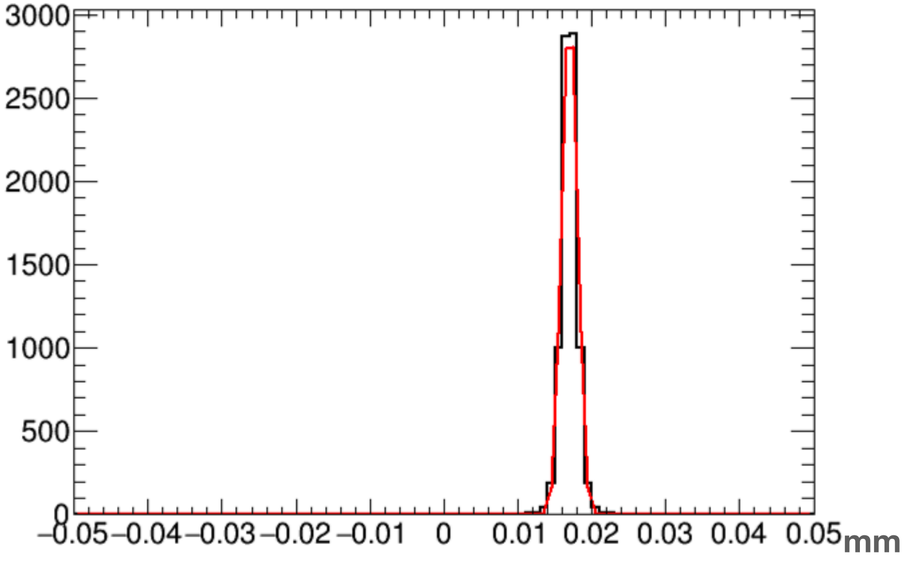
Backup

- translation along x -0.05mm for plane3
- translation along y +0.02 mm for plane8
- Residual plots









Rotation matrix R, translation matrix Δr $\quad R = \begin{pmatrix} 1 & \Delta\gamma & \Delta\beta \\ -\Delta\gamma & 1 & \Delta\alpha \\ -\Delta\beta & -\Delta\alpha & 1 \end{pmatrix} \quad \Delta r = \begin{pmatrix} \Delta x \\ \Delta y \\ \Delta z \end{pmatrix}$

From the local to global frame $\quad \vec{r}_{hit}^{\,local} = R \cdot (\vec{r}_{hit}^{\,global} - (\vec{r}_{0}^{\,global} + \Delta r))$

If perfect aligned: $\quad \vec{r}_{hit}^{\,local} = \vec{r}_{hit}^{\,global} - \vec{r}_{0}^{\,global} = \vec{r}_{hit}^{\,global} - \begin{pmatrix} 0 \\ 0 \\ z^{global} \end{pmatrix}$ (3) $\quad \vec{r}_{0}^{\,global} = \begin{pmatrix} 0 \\ 0 \\ z^{global} \end{pmatrix}$

If misaligned:

$$\vec{r}_{hit}^{\,local,new} = R(\vec{r}_{hit}^{\,global,new} - (\vec{r}_{0}^{\,global} + \Delta r)) \quad (1)$$

considering straight line model：

$$x^{global} = az^{global} + b;\ y^{global} = cz^{global} + d;\ \Delta x^{global} = a\Delta z^{global};\ \Delta y^{global} = c\Delta z^{global}$$

$$\therefore \vec{r}_{hit}^{\,global,new} = \vec{r}_{hit}^{\,global} + h \cdot \begin{pmatrix} a \\ c \\ 1 \end{pmatrix};\ h = \Delta z^{global} \quad (2)$$

from equation (1) (2) (3)

$$\therefore \vec{r}_{hit}^{\,local,new} = R(\vec{r}_{hit}^{\,global,new} - (\vec{r}_{0}^{\,global} + \Delta r)) = R(\vec{r}_{hit}^{\,global} + h \cdot \begin{pmatrix} a \\ c \\ 1 \end{pmatrix} - (\vec{r}_{0}^{\,global} + \Delta r)) = R(\vec{r}_{hit}^{\,local} + h \cdot \begin{pmatrix} a \\ c \\ 1 \end{pmatrix} - \Delta r) \quad (4)$$

$$\therefore \vec{r}_{hit}^{local,new} = R(\vec{r}_{hit}^{global,new} - (\vec{r}_0^{global} + \Delta r)) = R(\vec{r}_{hit}^{global} + h \cdot \begin{pmatrix} a \\ c \\ 1 \end{pmatrix} - (\vec{r}_0^{global} + \Delta r)) = R(\vec{r}_{hit}^{local} + h \cdot \begin{pmatrix} a \\ c \\ 1 \end{pmatrix} - \Delta r) \quad (4)$$

Simplifying: $R \cdot \Delta r \approx \begin{pmatrix} \Delta x \\ \Delta y \\ \Delta z \end{pmatrix}$

$$\therefore \vec{r}_{hit}^{local,new} = \begin{pmatrix} 1 & \Delta\gamma & \Delta\beta \\ -\Delta\gamma & 1 & \Delta\alpha \\ -\Delta\beta & -\Delta\alpha & 1 \end{pmatrix} \begin{pmatrix} x^{global} + ah \\ y^{global} + ch \\ z^{global} + h - z^{global} \end{pmatrix} - \begin{pmatrix} \Delta x \\ \Delta y \\ \Delta z \end{pmatrix}$$

$\vec{r}_{hit}^{local,new}$ z component should be equal to 0

$$\therefore -\Delta\beta(x^{local} + ah) - \Delta\alpha(y^{local} + ch) + h - \Delta z = 0$$

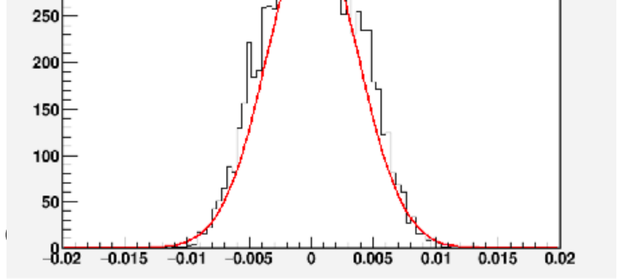
$$\therefore h = \frac{\Delta z + \Delta\beta x^{local} + \Delta\alpha y^{local}}{1 - a\Delta\beta - b\Delta\alpha} \approx \Delta z + \Delta\beta \cdot x^{local} + \Delta\alpha \cdot y^{local} \quad (5)$$

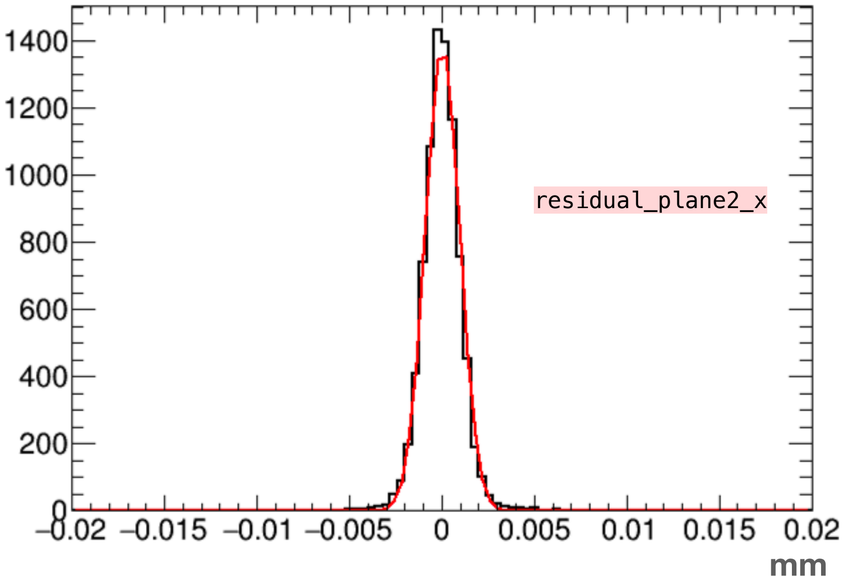
最小二乘直线拟合 **斜率**

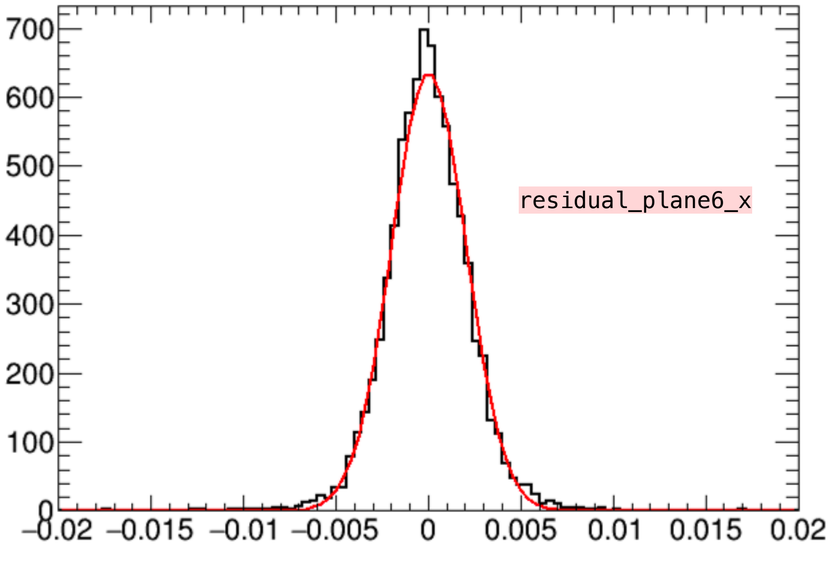
$$\begin{cases} x_{hit}^{new} = x_{hit} - \Delta_x + y_{hit} \cdot \Delta_\gamma + a \cdot (\Delta_z + x_{hit} \cdot \Delta_\beta + y_{hit} \cdot \Delta_\alpha) \\ y_{hit}^{new} = y_{hit} - \Delta_y - x_{hit} \cdot \Delta_\gamma + c \cdot (\Delta_z + x_{hit} \cdot \Delta_\beta + y_{hit} \cdot \Delta_\alpha) \end{cases}$$

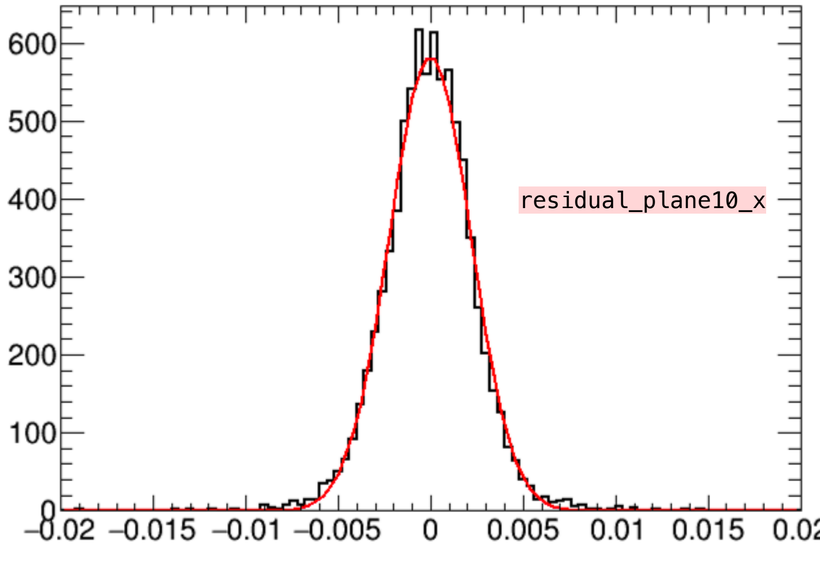
Fitting

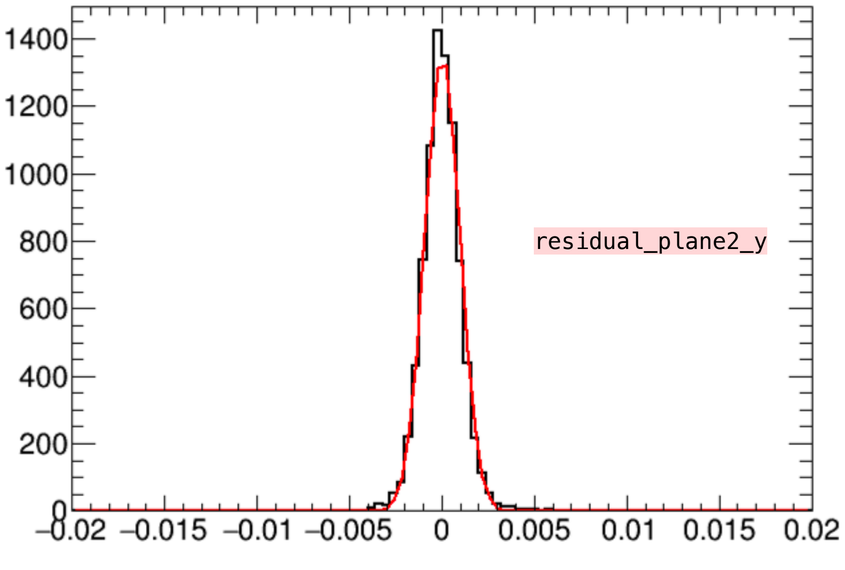
- f(x)=a1*z+b1+x; f(y)=a2*z+b2+y
- Residual for every sensor plane

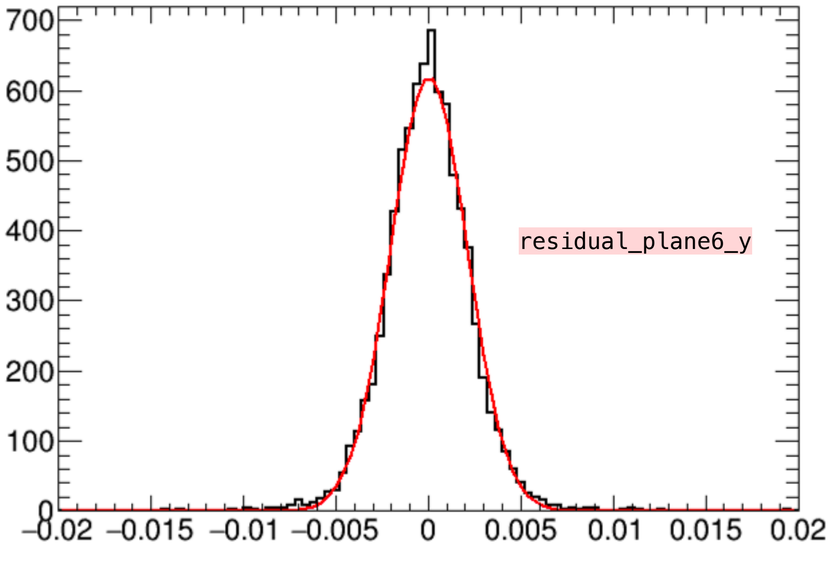


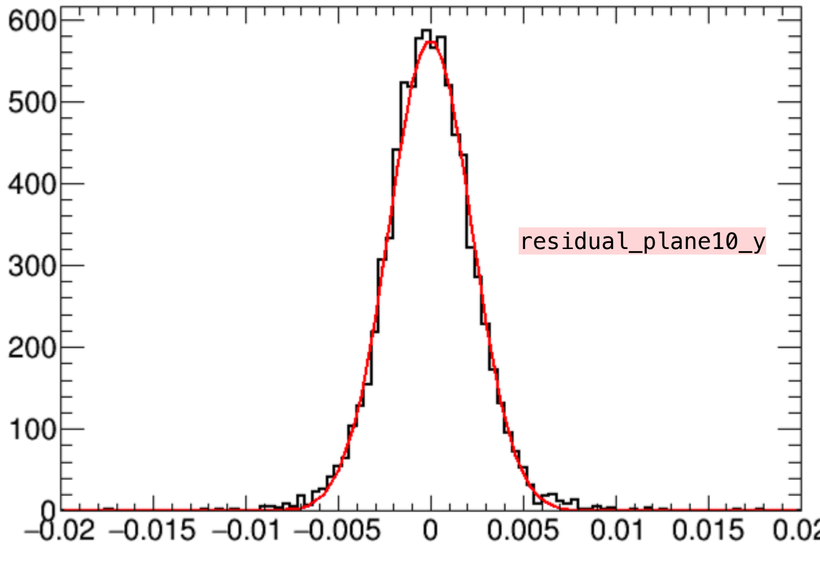








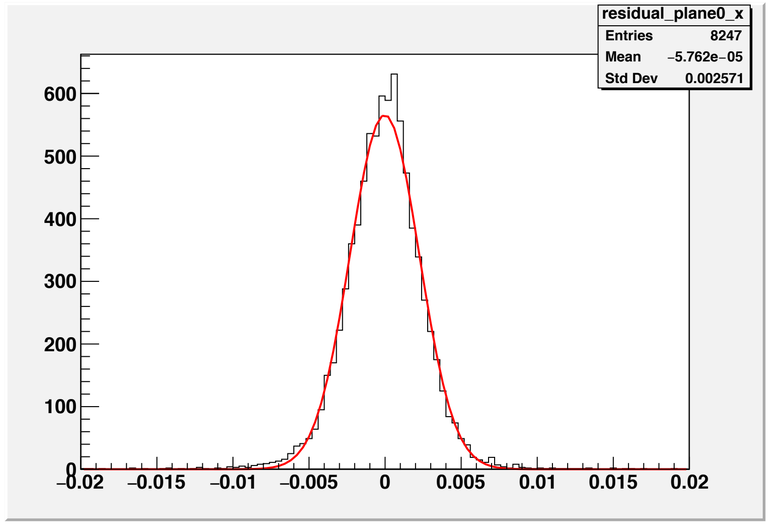


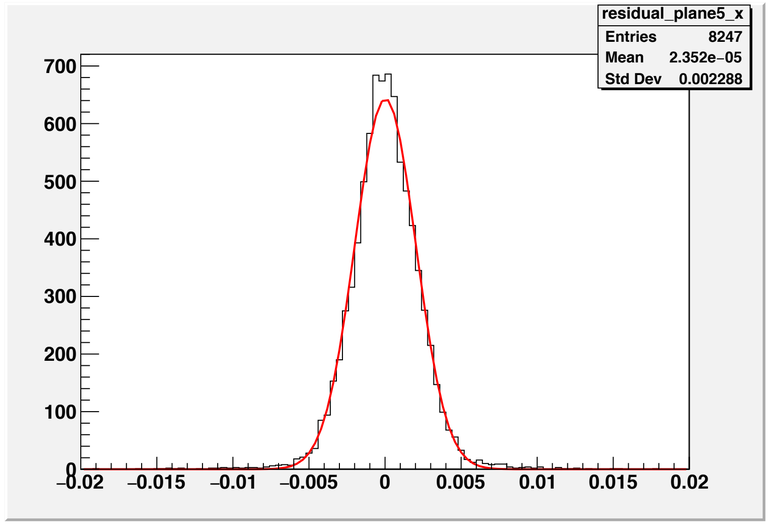


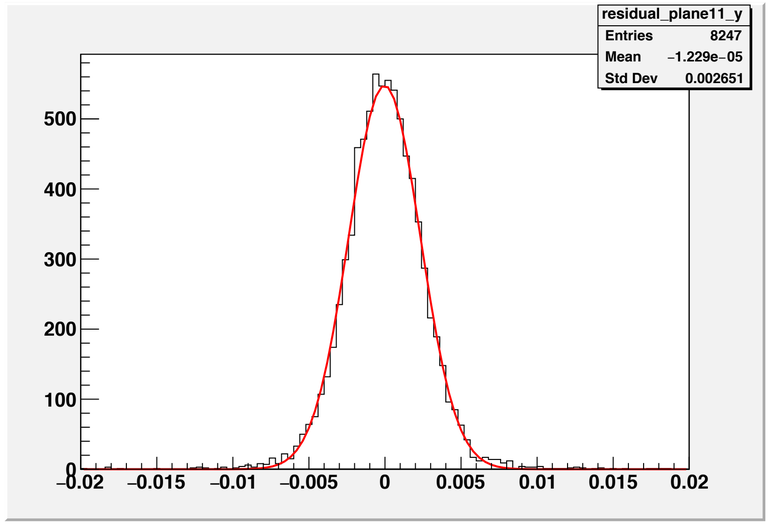
Next plan

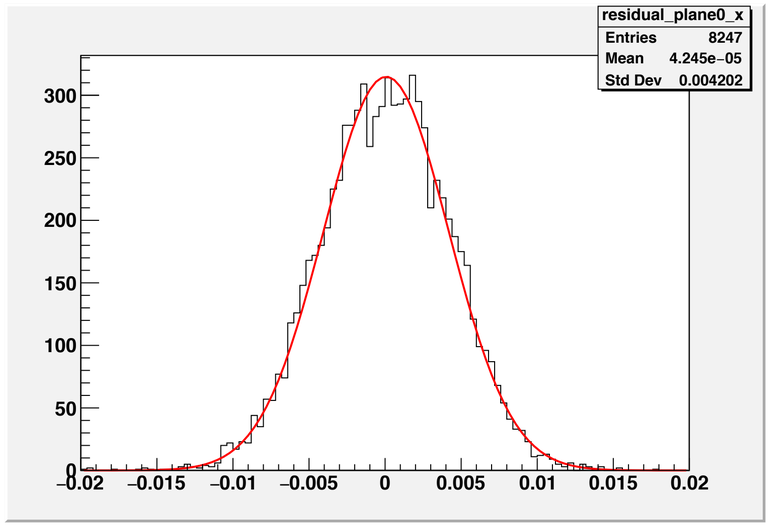
- simulated hit information digitation
- applied simple alignment free degree (translation along x,y and rotation around Z)

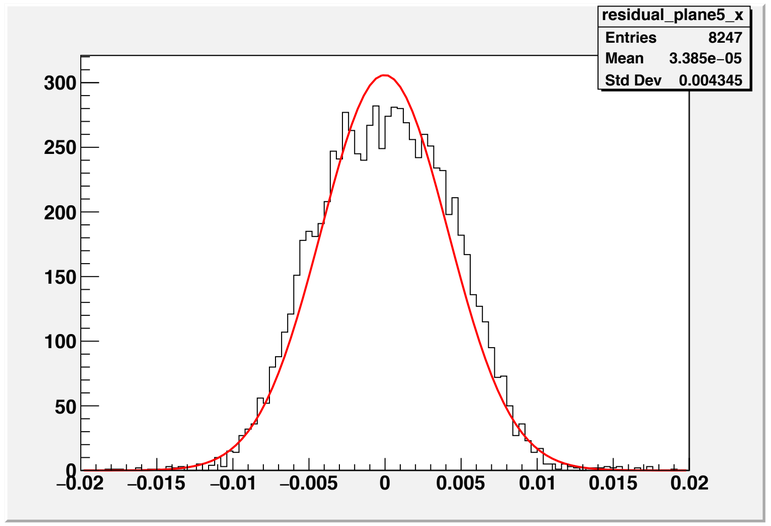
Added detector smearing effect 7um

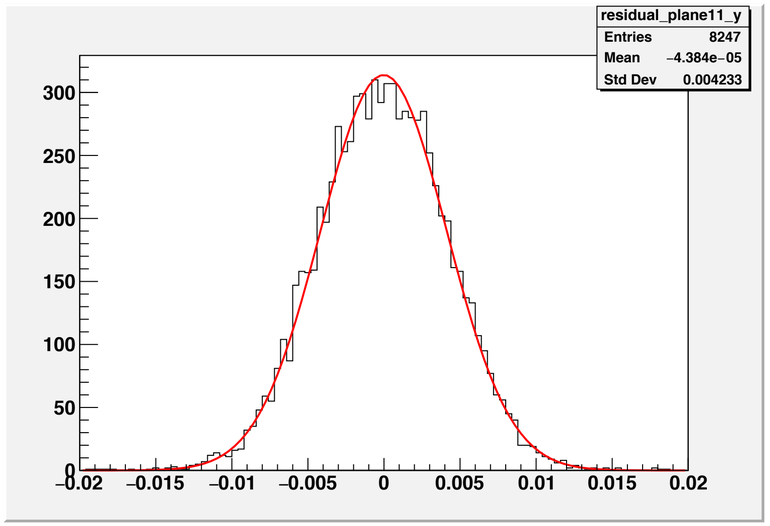


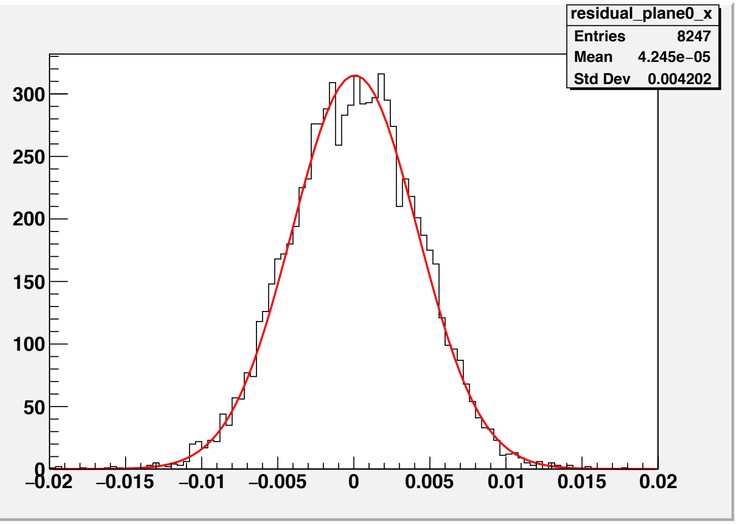




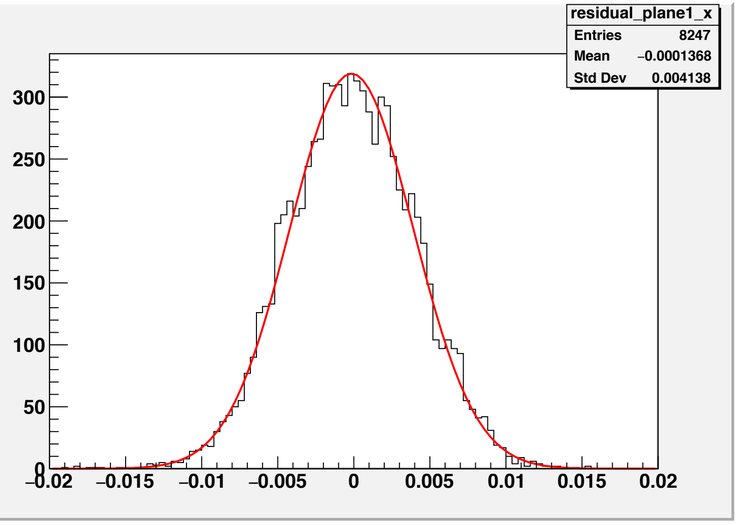


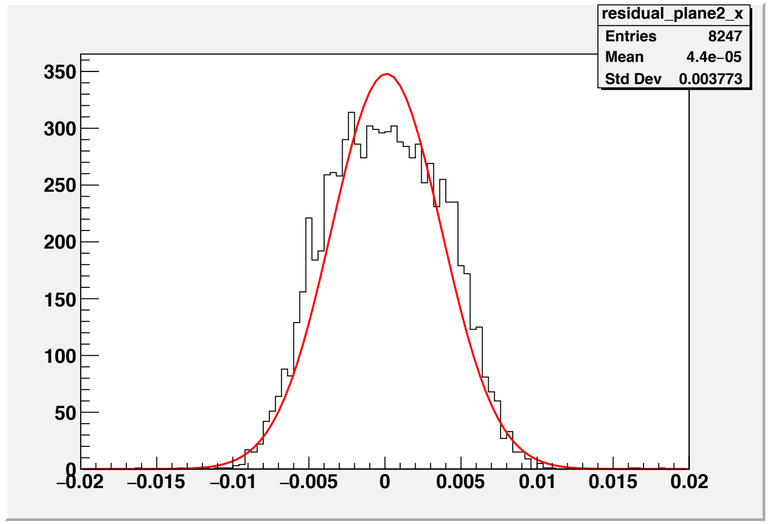




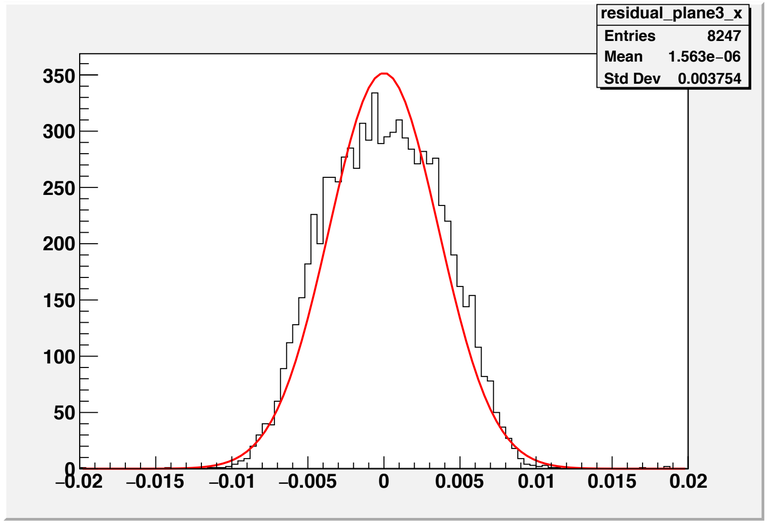


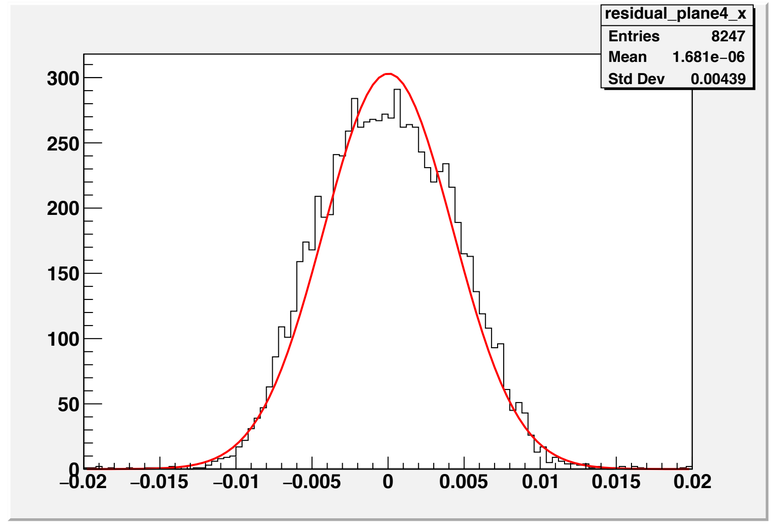
sigma=4.2um





sigma=3.7um





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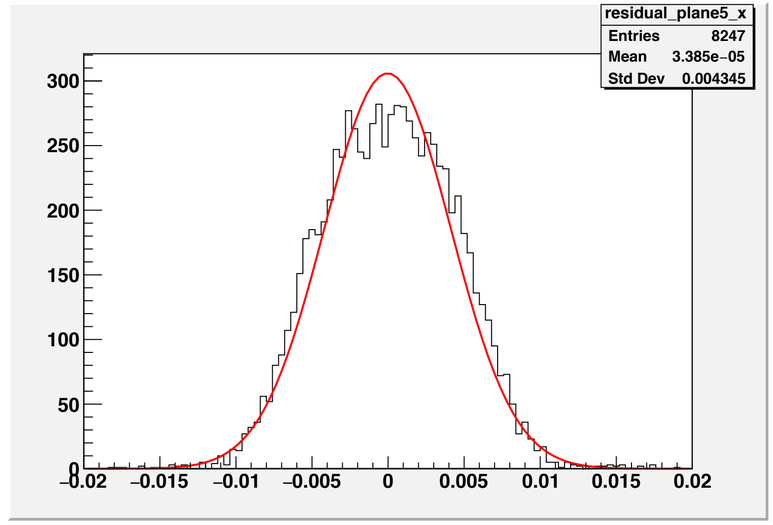
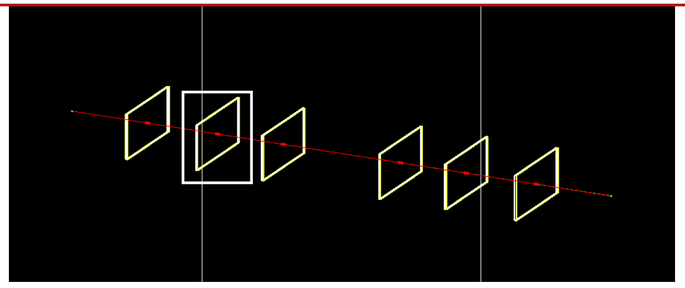
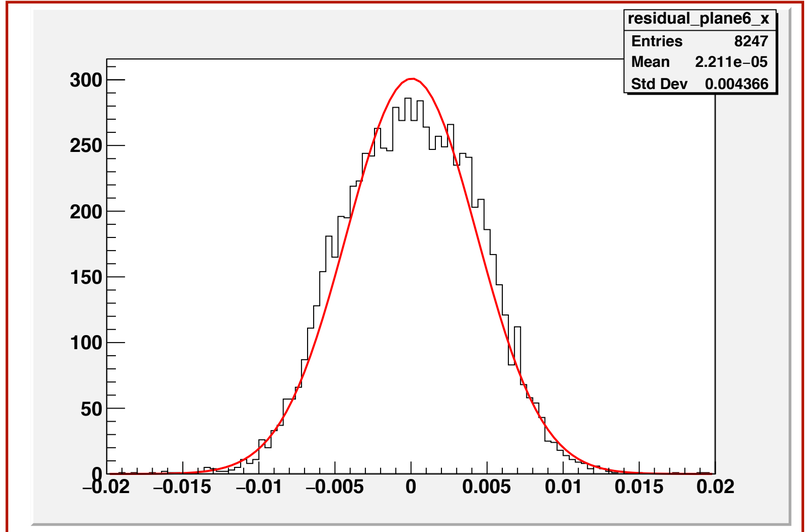
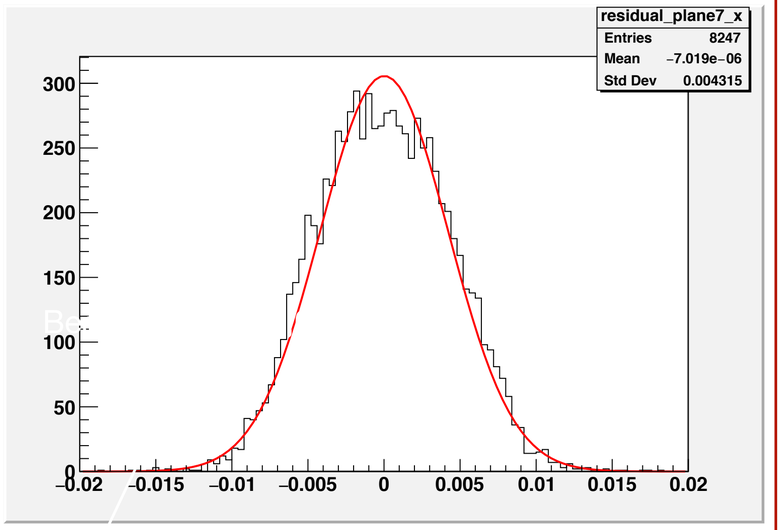


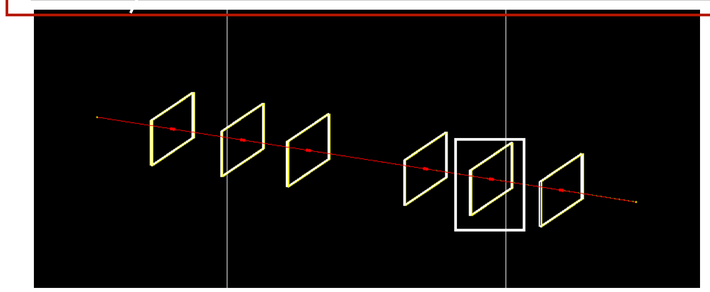


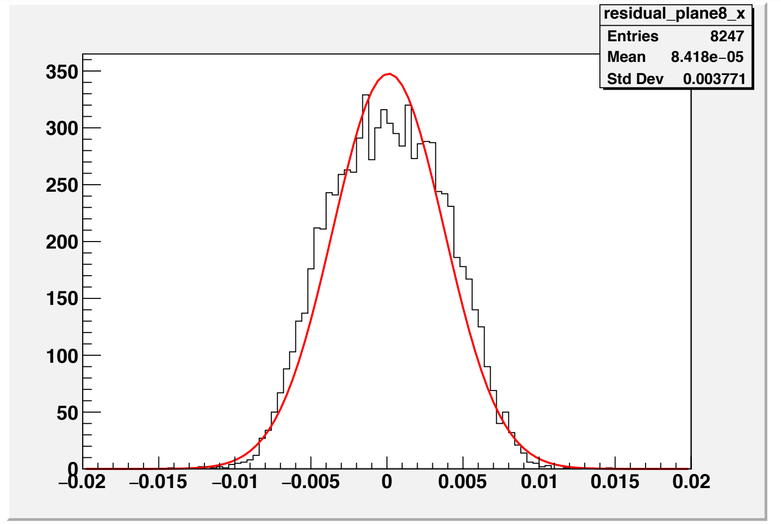
Adding detector smearing effect 7um



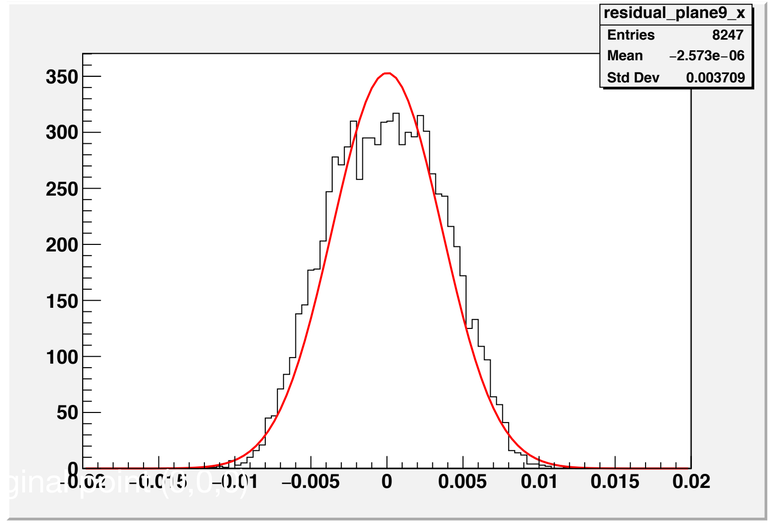
sigma=4.35um

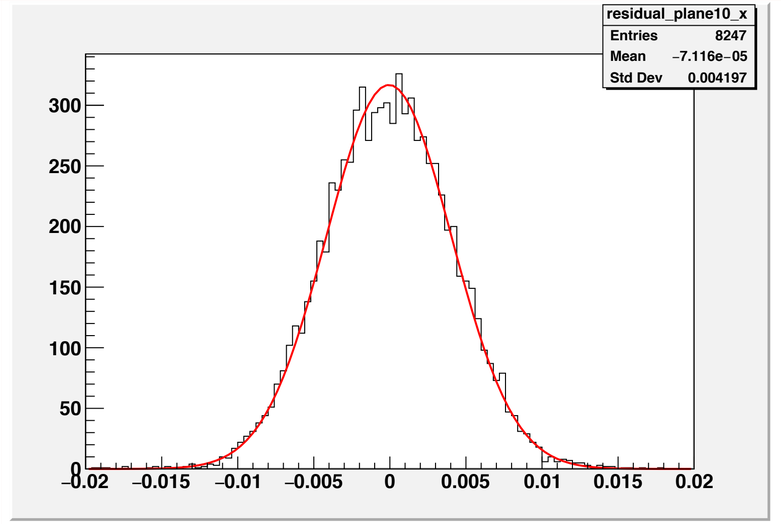






sigma=3.7um





sigma=4.2um