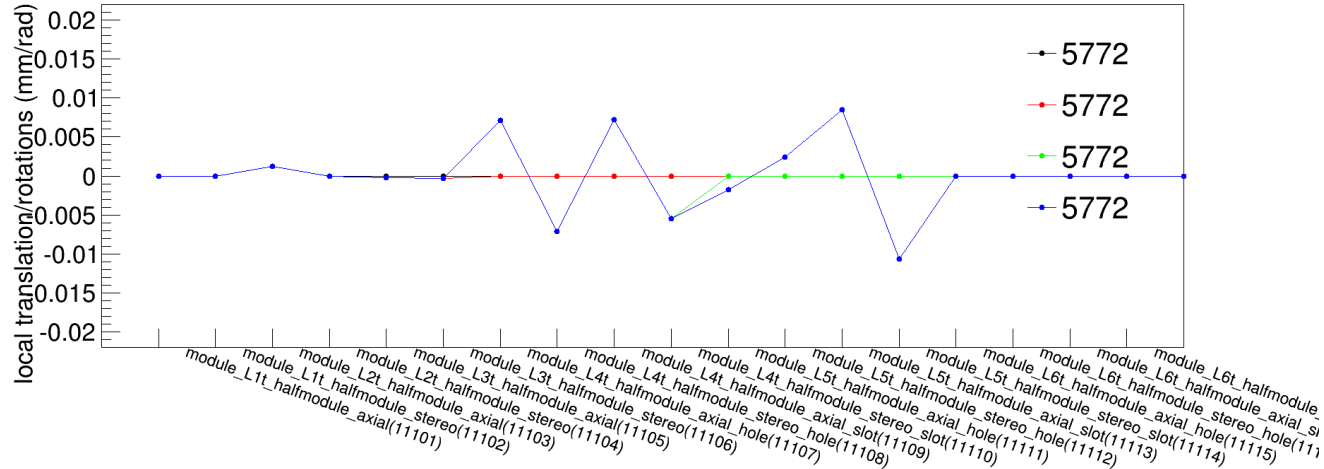


# V3-1-fieldmap

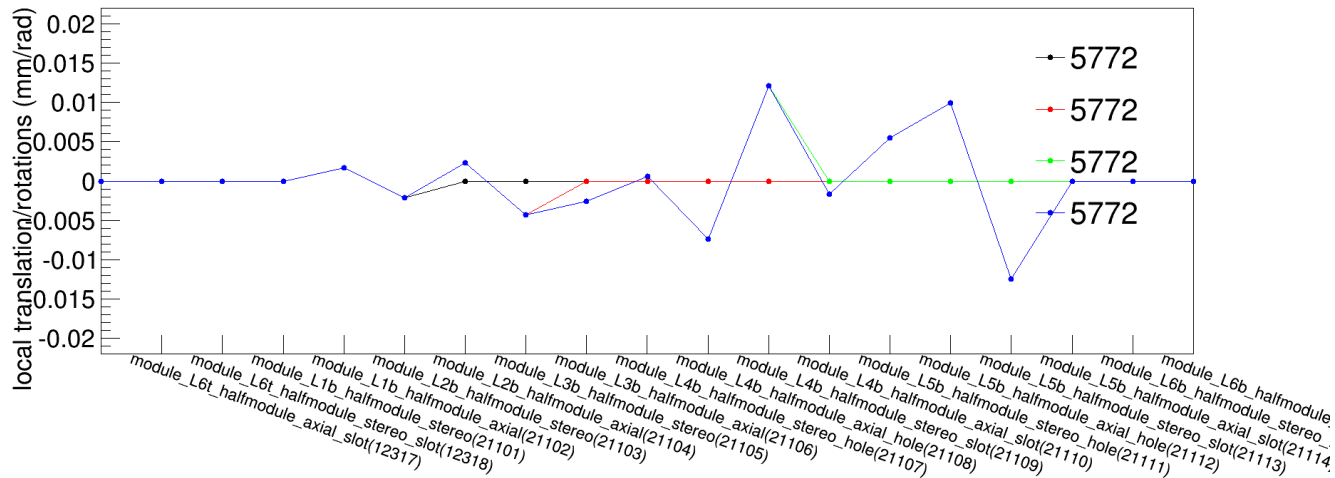
Per Hansson Adrian 10/6/2015

# Float L2->L3->L4->L5 (only few k tracks)

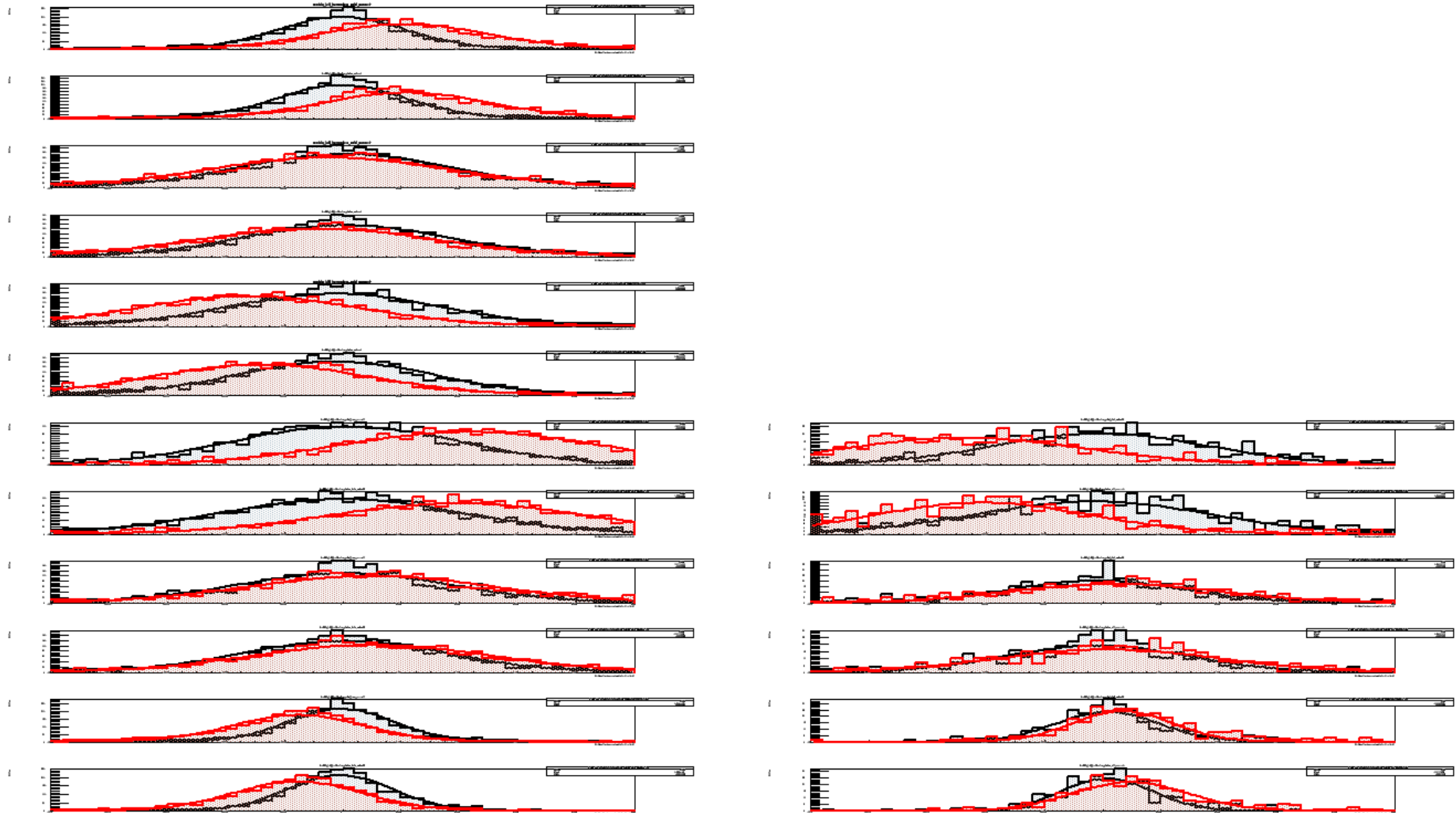
Millepede corrections per sensor



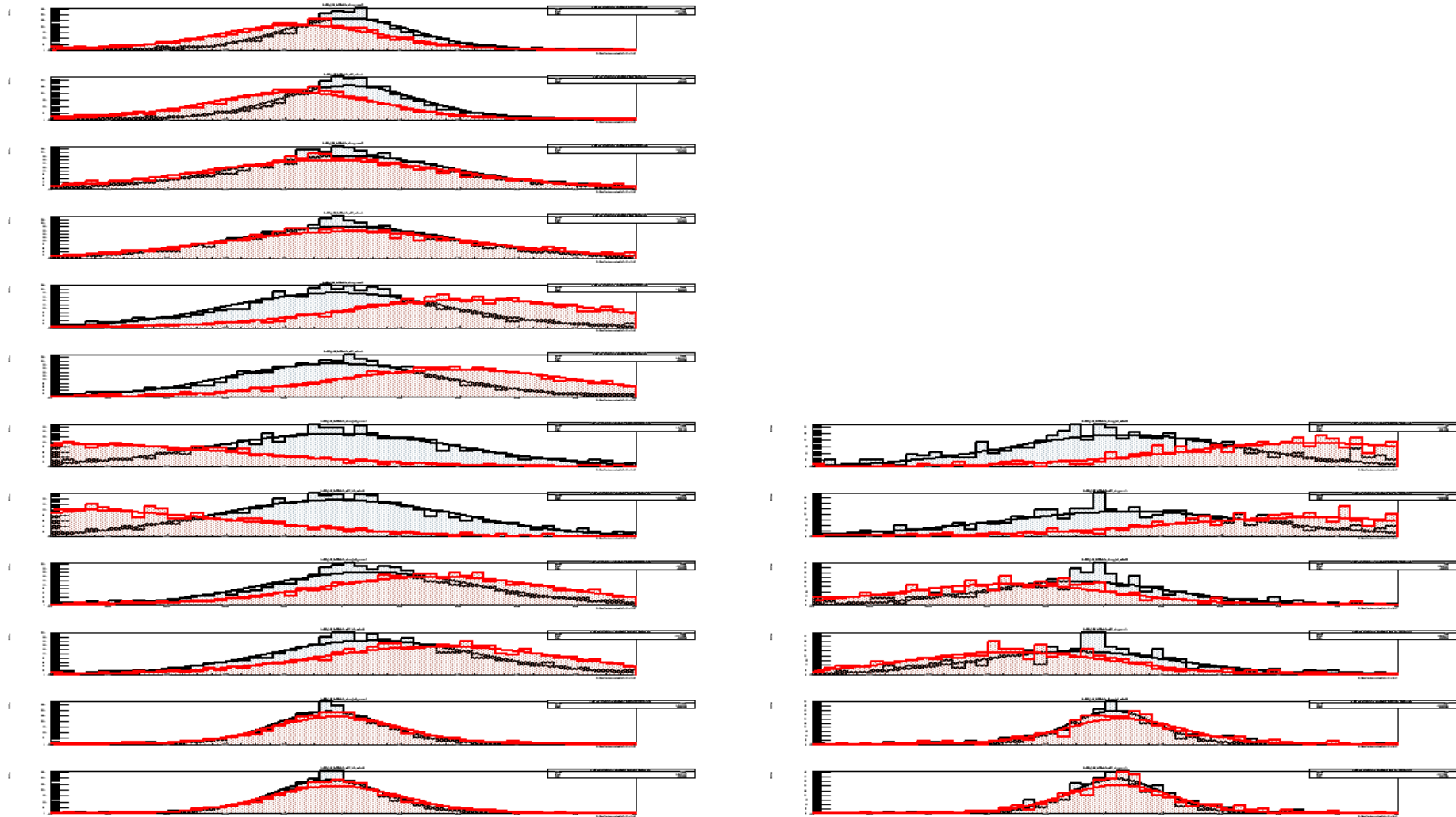
Millepede corrections per sensor



# V3-1-fieldmap top residuals before/after MP



# V3-1-fieldmap bottom residuals before/after MP





# Overview

Compare releasing translations in u and rotations around w

Always float both

Iteratively float 3 layers (axial and stereo) at a time, so

- L1,2,3 then L4,5,6 would be “L123\_456”, and so on

In the following I compare two paths

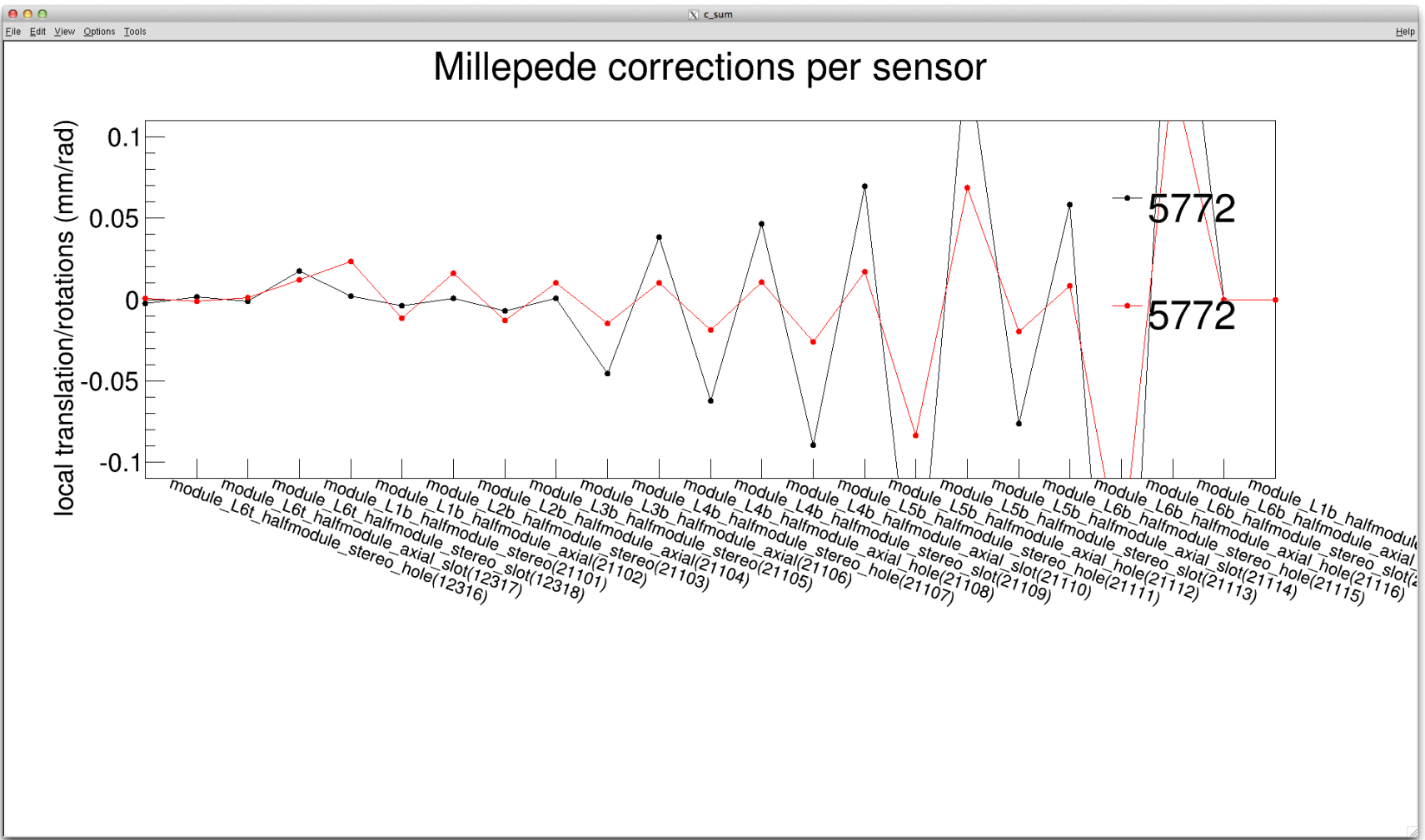
- Starting by floating L123 or L456
- Then add internal floats
- Then float L123 and L456 again to see if it stabilizes

In most cases the statistics seems ok at each minimization, these are 200k tracks from run 5772.



# Translation bottom

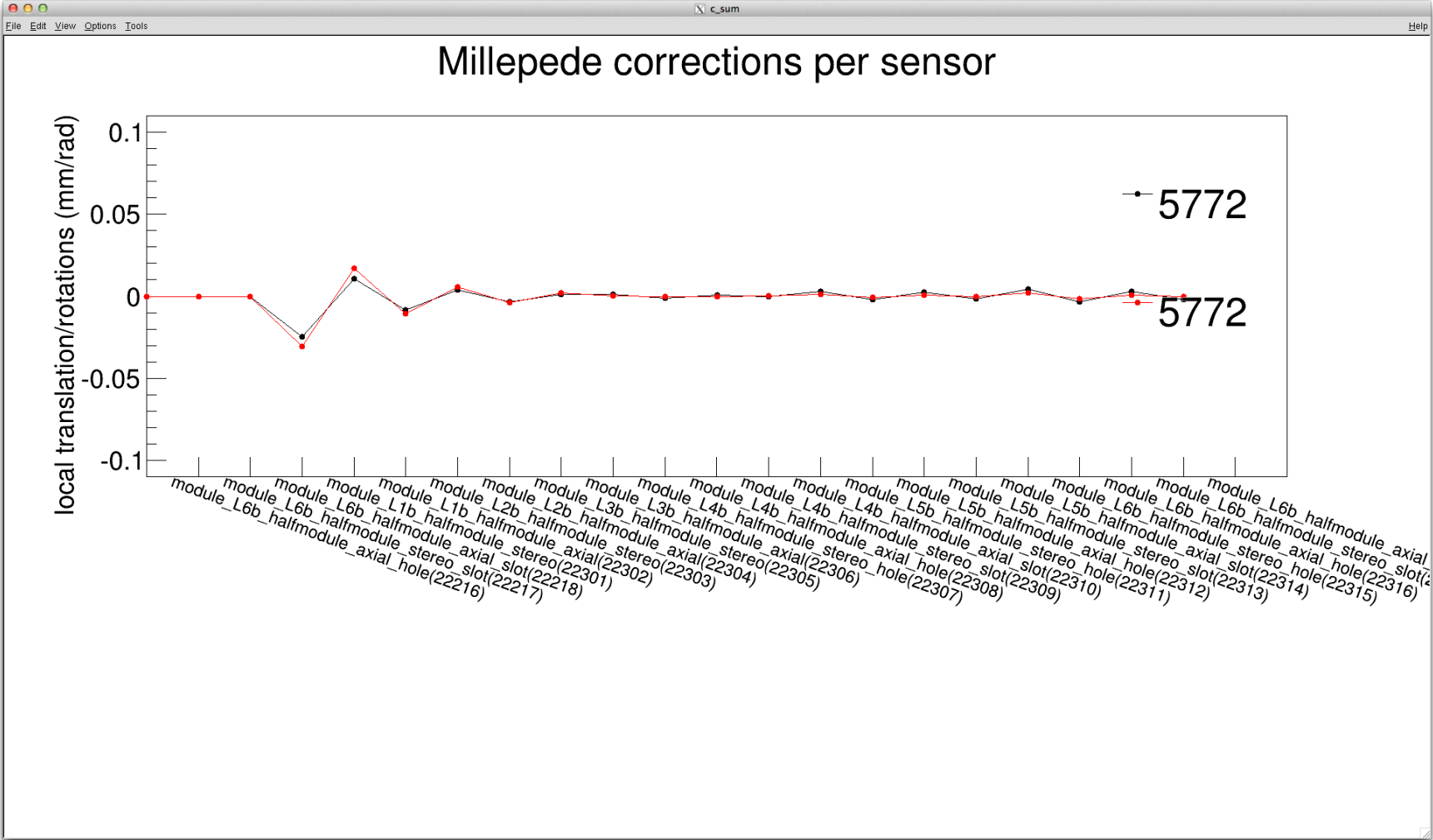
Legend: 123\_456, 456\_123\_tu\_rw





# Rotations bottom

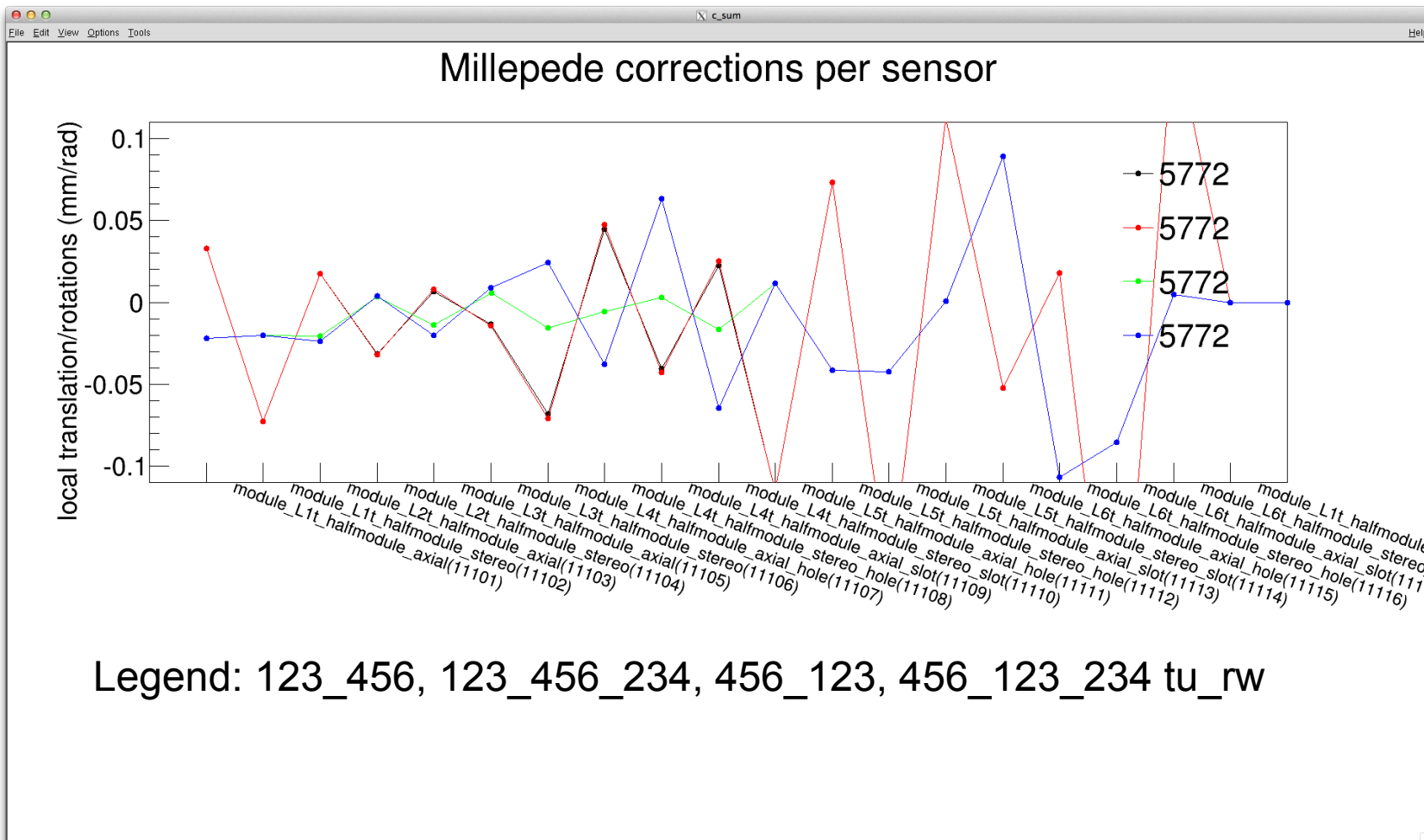
Legend: 123\_456, 456\_123\_tu\_rw





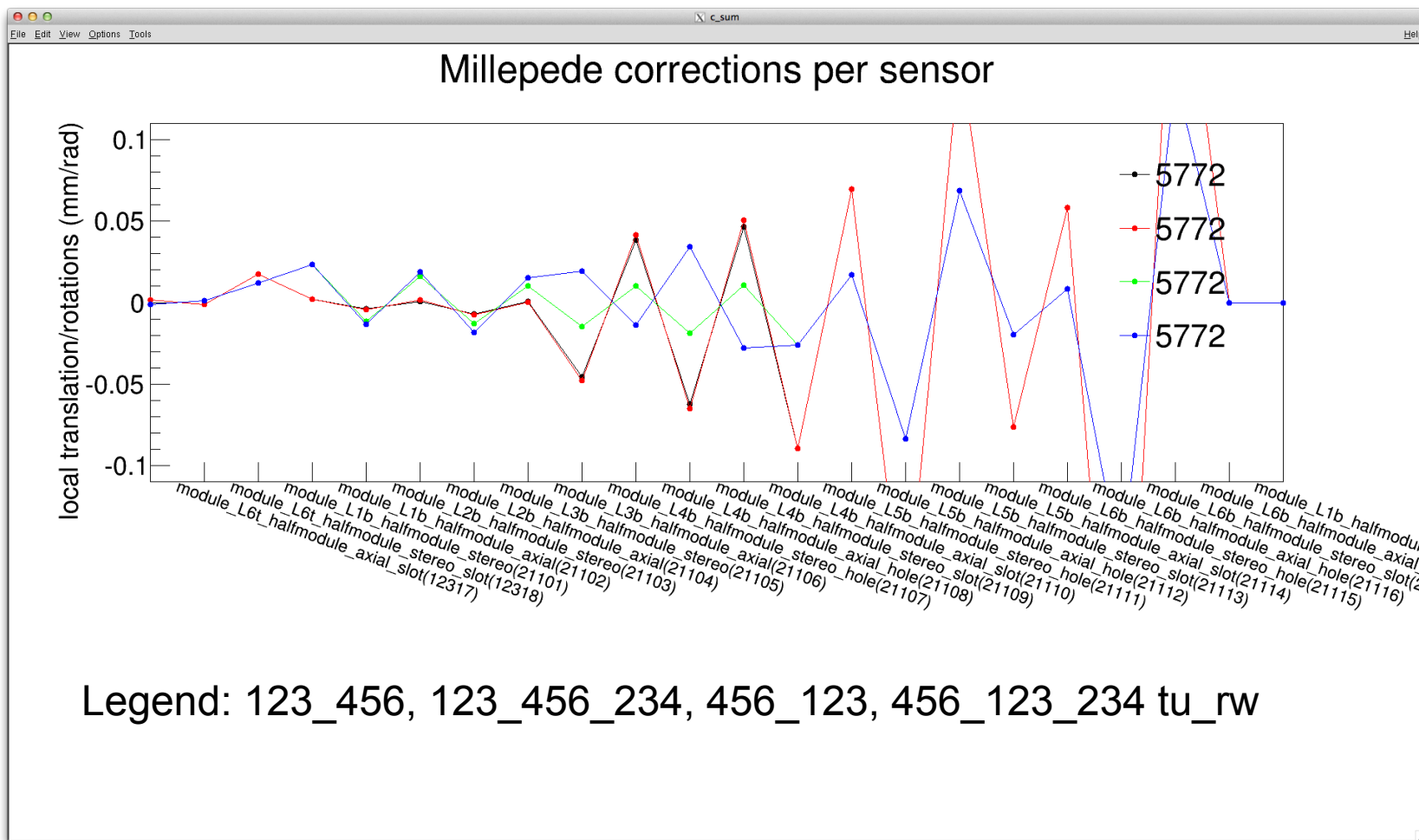


# Translation top



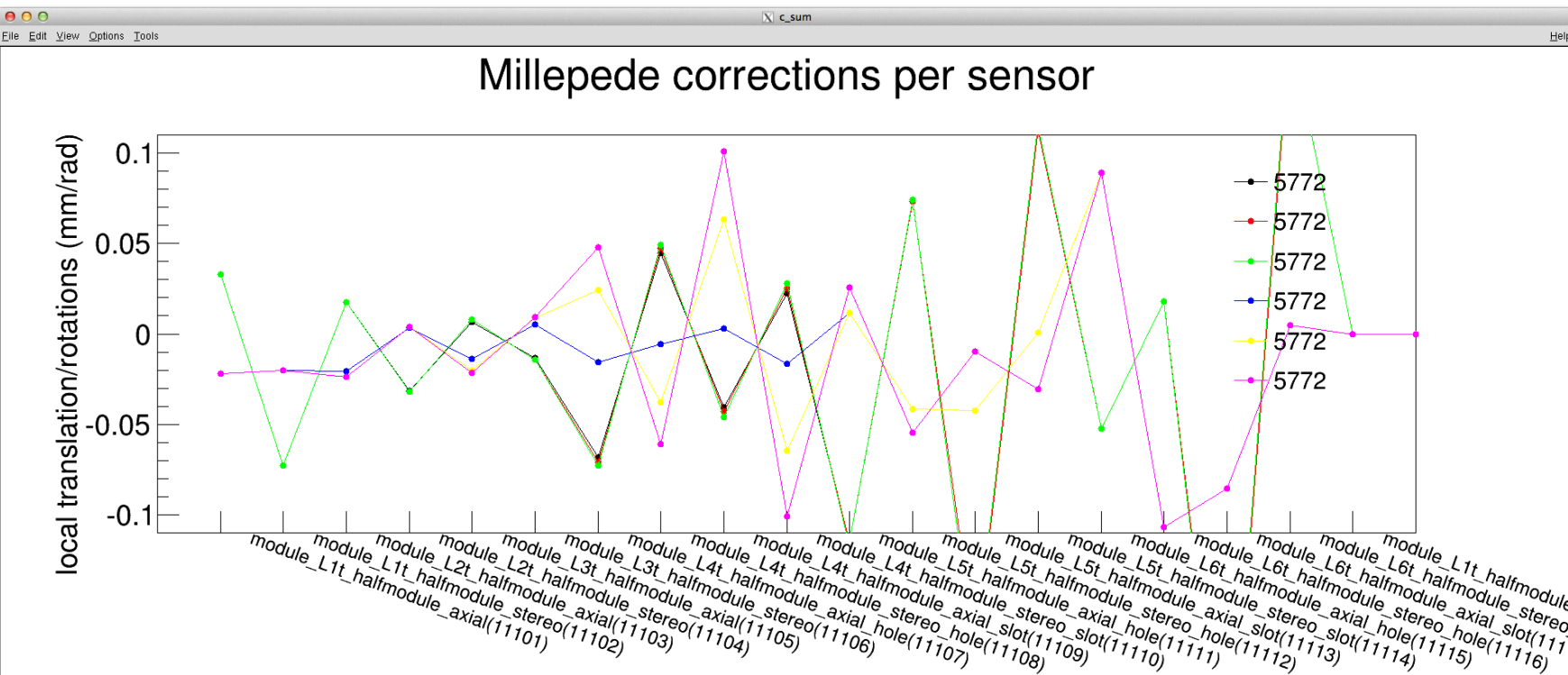
Legend: 123\_456, 123\_456\_234, 456\_123, 456\_123\_234 tu\_rw

# Translation bottom



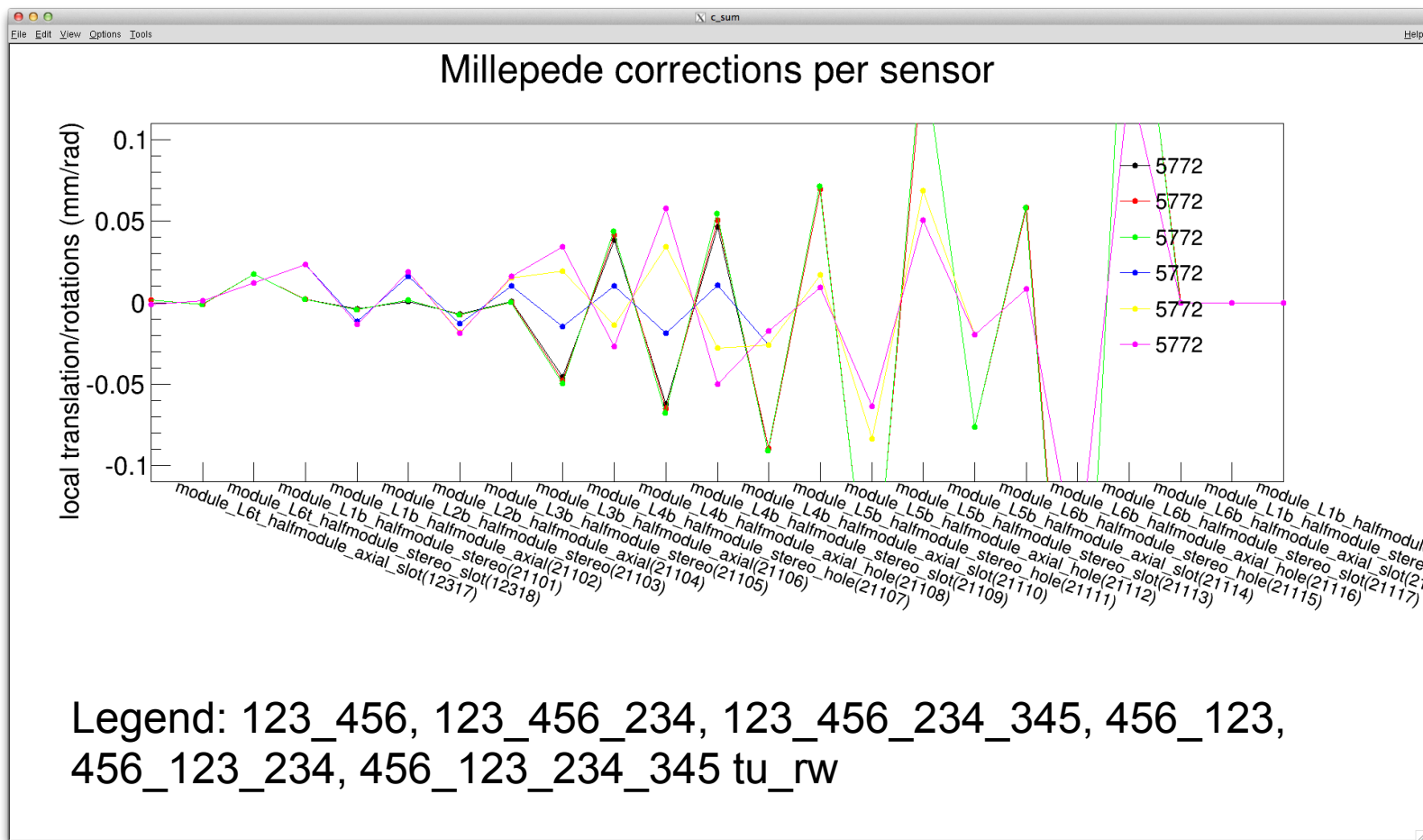


# Translation top



Legend: 123\_456, 123\_456\_234, 123\_456\_234\_345, 456\_123, 456\_123\_234, 456\_123\_234\_345 tu\_rw

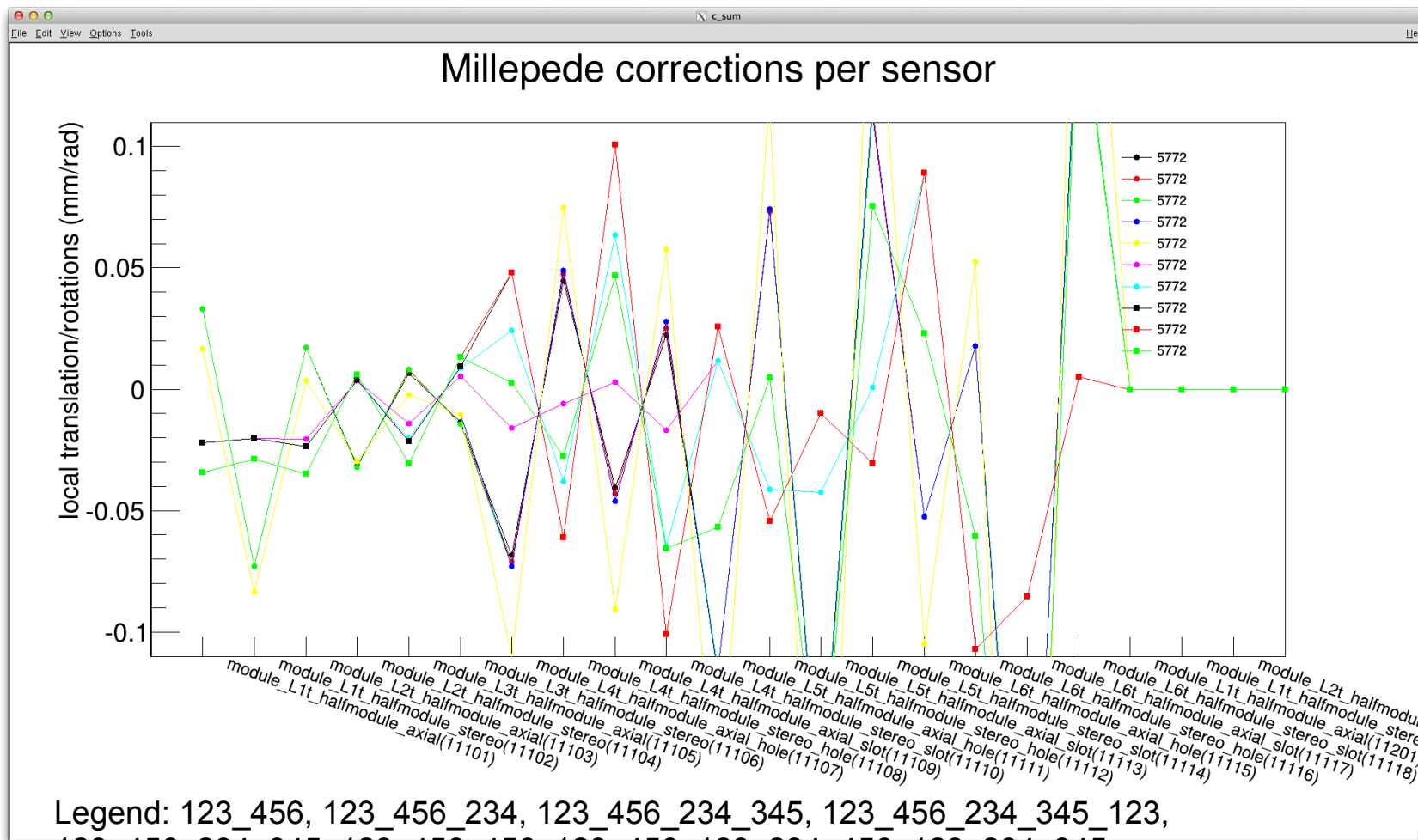
# Translation bottom





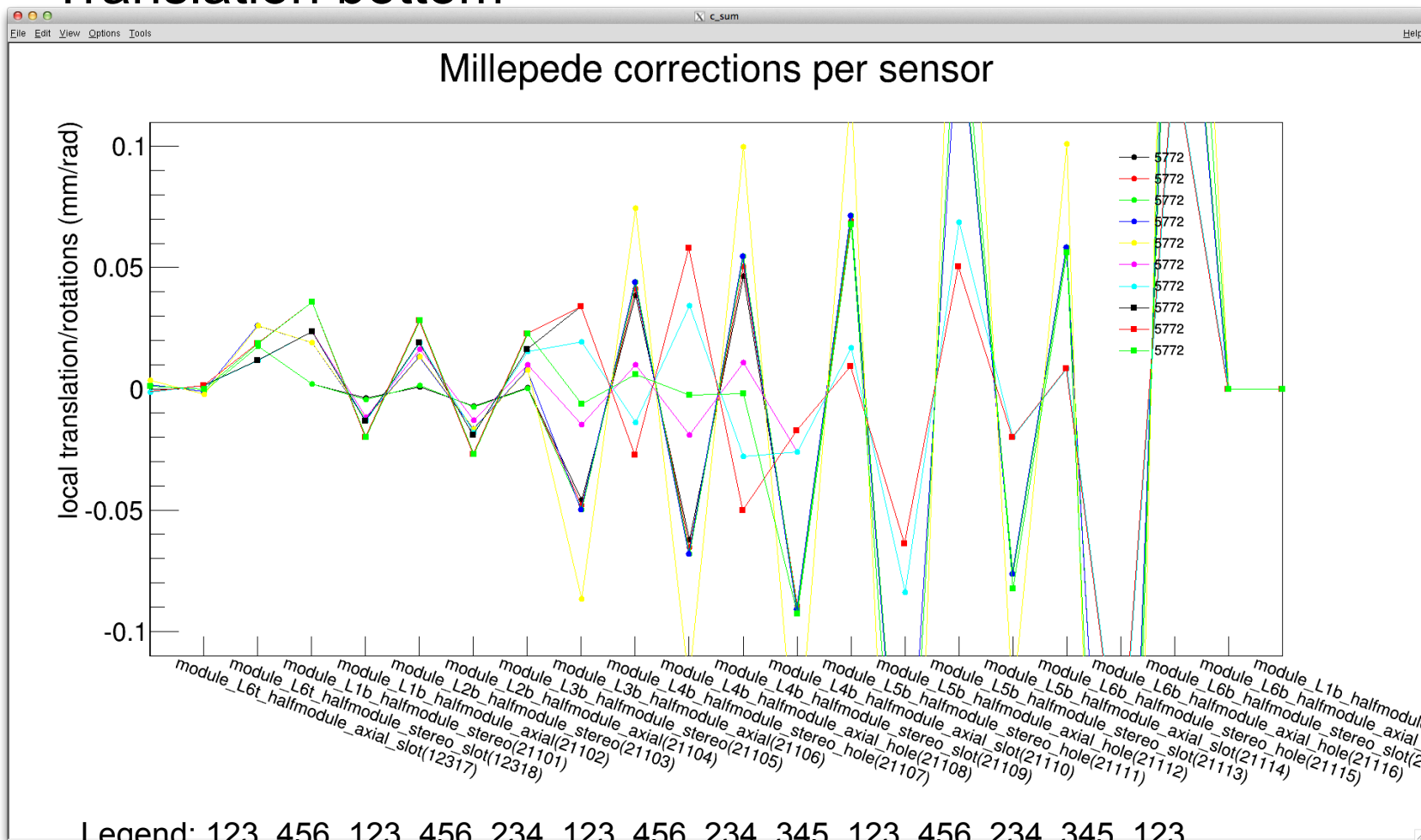


# Translation top



Legend: 123\_456, 123\_456\_234, 123\_456\_234\_345, 123\_456\_234\_345\_123,  
 123\_456\_234\_345\_123\_456, 456\_123, 456\_123\_234, 456\_123\_234\_345,  
 456\_123\_234\_345\_123, 456\_123\_234\_345\_123\_456 tu\_rw

# Translation bottom



Legend: 123\_456, 123\_456\_234, 123\_456\_234\_345, 123\_456\_234\_345\_123,  
 123\_456\_234\_345\_123\_456, 456\_123, 456\_123\_234, 456\_123\_234\_345,  
 456\_123\_234\_345\_123, 456\_123\_234\_345\_123\_456 tu\_rw