

Frequency Scanning Interferometry QD0 Alignment



University of Michigan ILC Group

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ALCPG Meeting – Eugene, Oregon

March 21, 2011

Gave a presentation at December 16, 2010 SLAC MDI telecon:

<http://ilcagenda.linearcollider.org/materialDisplay.py?contribId=1&materialId=slides&confId=4937>

This presentation is very similar

What is new since December?

LCRD funding for FSI R&D for SiD tracker arrived

**(supports visiting graduate student wages and part of Haijun's salary,
TianXiang Chen has visa and arrives from China next week to start work)**

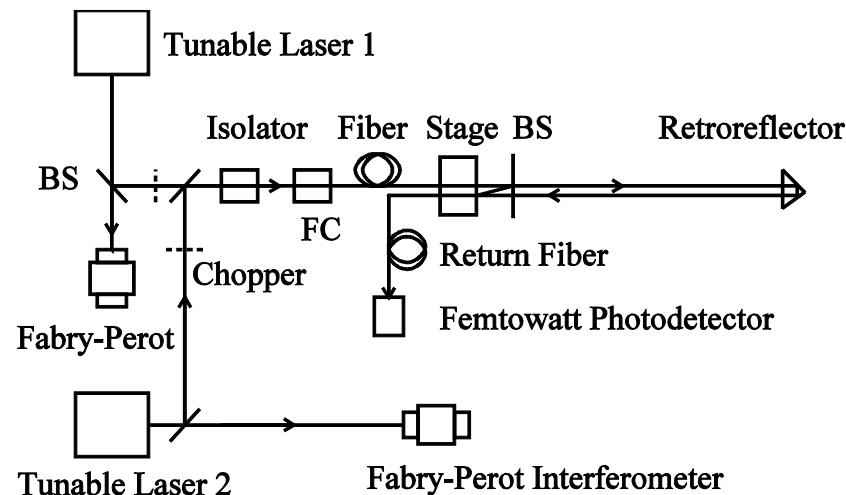
SLAC funding for FSI R&D for FF magnets “imminent” (lawyers done yet?)

(supports equipment, supplies, travel)

Overview of FSI Method

- Measure hundreds of absolute point-to-point distances of detector elements in 3 dimensions by using an array of optical beams split from a central laser.
- Absolute distances are determined by scanning the laser frequency and counting interference fringes.
- Grid of reference points overdetermined → Infer positions, orientations, distortions

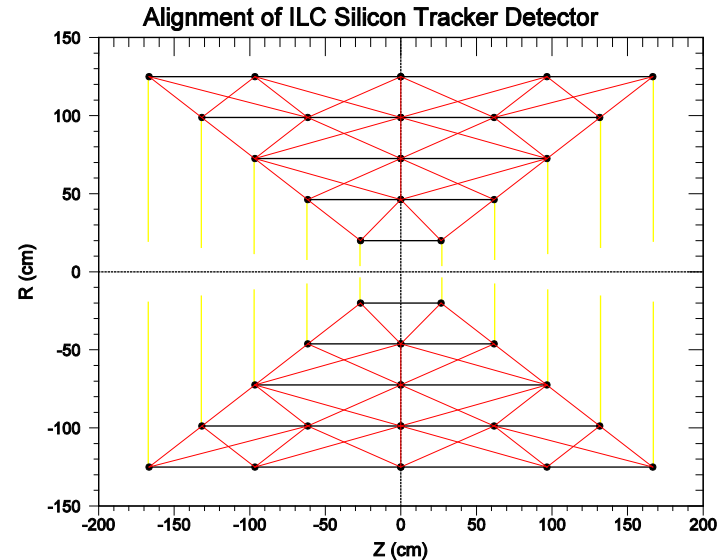
Dual-Laser Frequency Scanned Interferometer



Background on Michigan FSI work

Began R&D work in 2003 on FSI system for an ILC tracker

Applied the principles pioneered by the Oxford ATLAS group



Built basic infrastructure on bench in Michigan lab and came up to speed over ~3 years

**Many presentations at LC workshops and two articles:
Appl. Opt 19: 3937 (2005); *Nuc. Inst. Meth. A* 575:395 (2007)**

Background on Michigan FSI work

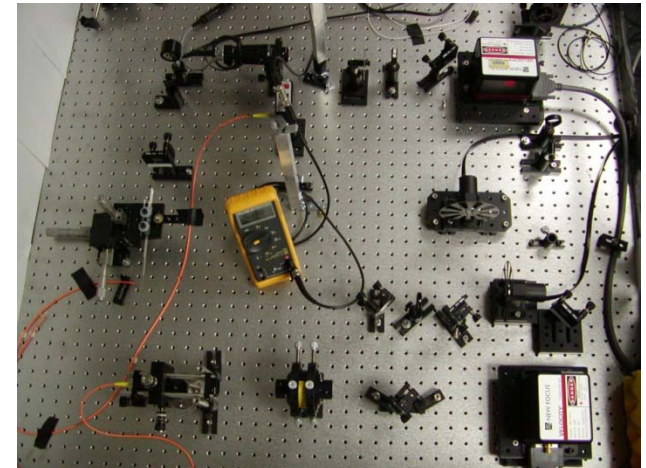
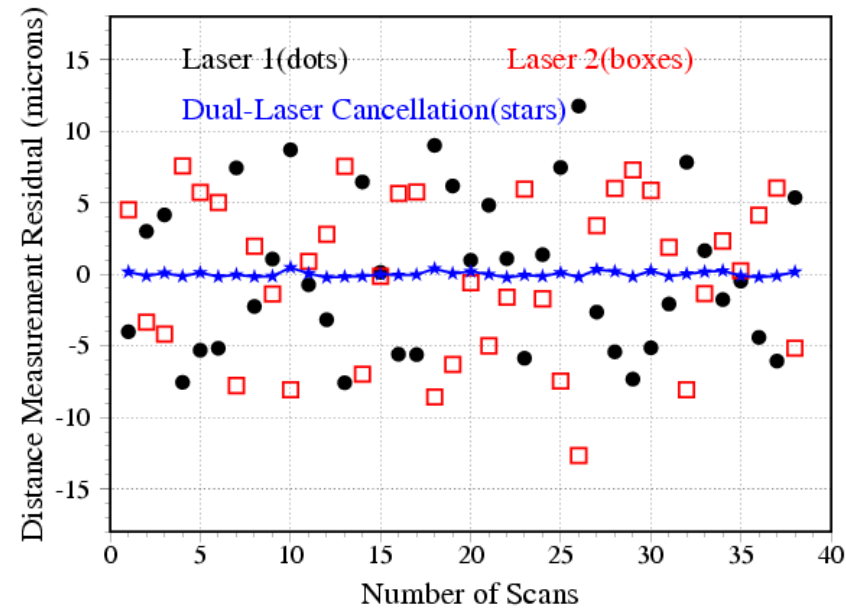
Achieved **O(200 nm)** precision in hostile environment (**air currents, temperature gradients**) using dual-laser approach pioneered by Oxford – good robustness

Checks:

- Verified micrometer offset of 125 μm
- Verified thermal-driven 60 μm expansion
- Verified piezo-driven 2 μm displacement
- Verified piezo-driven 0.15 μm vibrations

Caveats:

- **Single-channel system**
- **Used (large) commercial retroreflectors locked to table**
- **Manual alignment**



Background on Michigan FSI work

Funding dried up three years ago

Modest work since then:

- **Looked at lightweight retroreflector arrays**
- **Talked with rapid prototyping companies, but didn't have funds to proceed**
- **Experimented with metallic coatings on PMMA using campus facility**
- **Some simulation work by undergraduate**
- **Recently “inherited” 3-D translation stage with tens of cm range and submicron precision in 2-D**
- **But project largely mothballed on optical table in Michigan lab**

**Happy to be resuming alignment R&D
(magnets & tracker) after long hiatus**

First Simulations

Accuracies for QD0 support in functional requirements document (Mar 09):

- **50 μm in x, y**
- **20 mrad in roll**
- **20 μrad in pitch and yaw**

Have tried some simple simulations of beam launcher / retroreflector layouts (Minuit fitting to a grid of lines “attached” to QD0 ends)

Monitoring alignment of QF1 to bedrock should be relatively easy:

- **Bedrock nearby with many good lines of sight from wall / floor to QF1 sides**
- Have focused on QD0 alignment w.r.t. QF1**

Initial stab at simulations: (rework of old tracker simulation)

- **Align e+ and e- sides separately (without bridging gap)**
- **In longer term will pursue bridging gap with lines of sight through open SiD tracker (bootstrap from both ends)**

First Simulations

QD0 alignment simulation:

- Beam launchers placed on outside of QF1 front ends (~2 cm out in radius)
- Beam launchers placed on inner edge of innermost Hcal endcap layer
- Tried N launchers / reflectors spaced uniformly in φ (N = 4, 6)
- Tried lines of sight for three launcher/reflector combinations:
 - Option A – 1 line of sight / reflector [$\varphi_i^{\text{launch}} \rightarrow \varphi_i^{\text{refl}}$]
 - Option B – 2 lines of sight / reflector [$\varphi_i^{\text{launch}} \rightarrow \varphi_{i-0.5}^{\text{refl}}, \varphi_{i+0.5}^{\text{refl}}$]
 - Option C – 3 lines of sight / reflector [$\varphi_i^{\text{launch}} \rightarrow \varphi_{i-1}^{\text{refl}}, \varphi_i^{\text{refl}}, \varphi_{i+1}^{\text{refl}}$]
- Tried aligning from only back end of QD0
- Tried aligning from both back and front ends of QD0
- Took accuracy on lines of sight to be 0.5 μm (despite 0.2 μm demonstration)

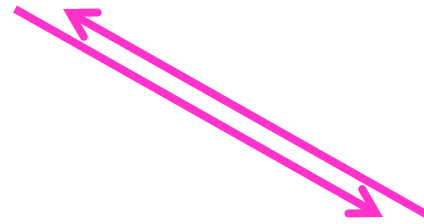
Useful analog for thinking about overconstrained FSI fitting:

- Imagine the lines of sight as steel rods attached to ball joints at each end
- Degrees of freedom that allow all rods to move easily are poorly measured
- “Cross bracing” good for removing degenerate DOFs

First Simulations

Following figures show sampling of layouts tried so far

- Beams launched from **blue asterisks** (“reference points”)



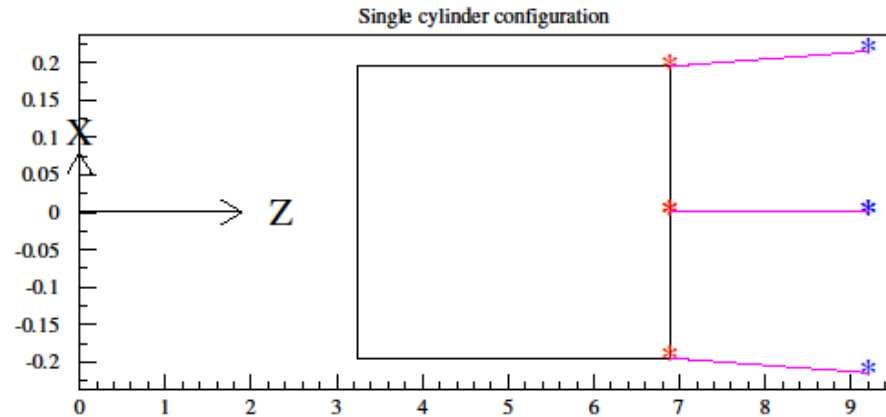
to **red asterisks (retroreflectors)**

- **Magenta lines** indicate launched beams (arrows omitted)
- Diagrams shown for X-Z and X-Y projections
- Minuit fits performed to determine quoted **precisions (blue)** on QD0 **c.m. position** and cylinder **orientation (pitch, yaw, roll)**

First Simulations

Bare bones: (4 lines)

- N=4
- Option A
- Back end only



* Detector point
* Reference point
- Line of sight

Cylinder dimensions

Radius = 0.19 m

Half-length = 1.83 m

Refer. offsets from cylinder ends

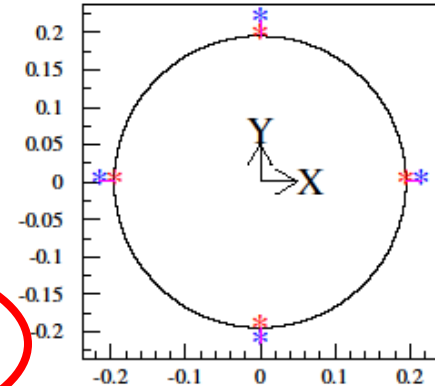
$r = 2.0 \text{ cm}$ $z = 231.4 \text{ cm}$

CM position precisions (μm)

$x = 495.3$ $y = 507.9$ $z = 2.5$

Axis rotation precisions (μrad)

pit = 25.4 yaw = 25.5 roll = ***.***

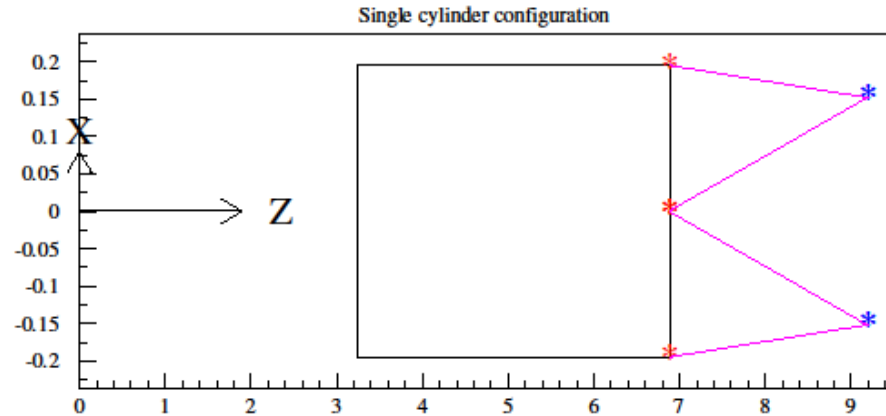


Tolerances not met!

First Simulations

8 lines:

- N=4
- Option B
- Back end only



* Detector point
* Reference point
-- Line of sight

Cylinder dimensions

Radius = 0.19 m
Half-length = 1.83 m

Refer. offsets from cylinder ends

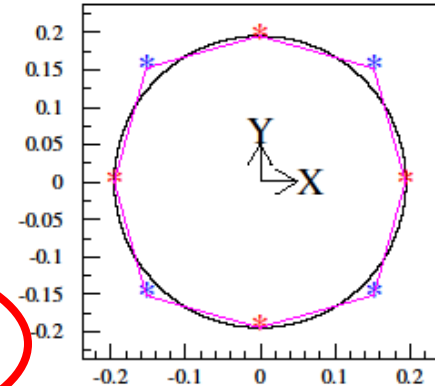
r = 2.0 cm z = 231.4 cm

CM position precisions (μm)

x = 5.1 y = 5.1 z = 0.2

Axis rotation precisions (μrad)

pit = 1.3 yaw = 1.3 roll = 13.8



All tolerances met!

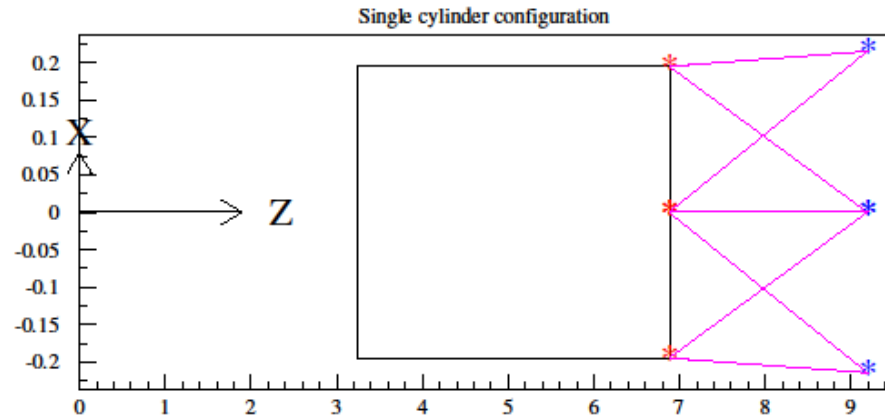
First Simulations

12 lines:

- N=4
- Option C
- Back end only

But can we really align from one end only?

Prudent to monitor other end too...

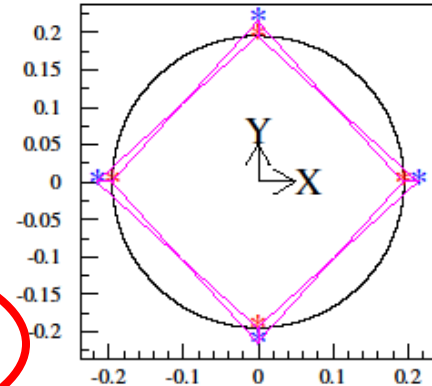


* Detector point
* Reference point
-- Line of sight

Cylinder dimensions
Radius = 0.19 m
Half-length = 1.83 m

Refer. offsets from cylinder ends
r = 2.0 cm z = 231.4 cm

CM position precisions (μm)
x = 4.0 y = 4.0 z = 0.1
Axis rotation precisions (μrad)
pit = 1.2 yaw = 1.2 roll = 9.8



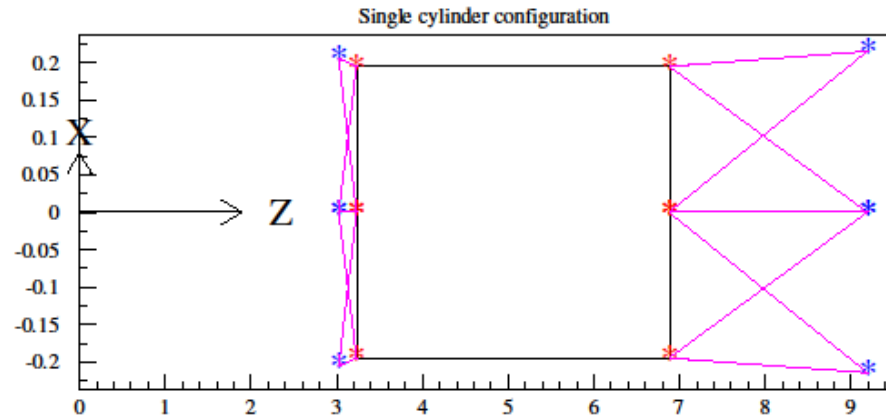
All tolerances met

First Simulations

24 lines:

- N=4
- Option C
- Both ends

Now back off to
Option B...

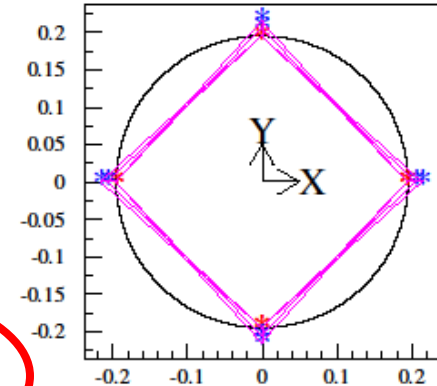


* Detector point
* Reference point
- Line of sight

Cylinder dimensions
Radius = 0.195 m
Half-length = 1.825 m

Refer. offsets from cylinder ends
r = 2.0 cm z = 231.4 cm
r = 1.1 cm z = -20.8 cm

CM position precisions (μm)
x = 0.8 y = 0.8 z = 0.1
Axis rotation precisions (μrad)
pit = 0.4 yaw = 0.4 roll = 1.5

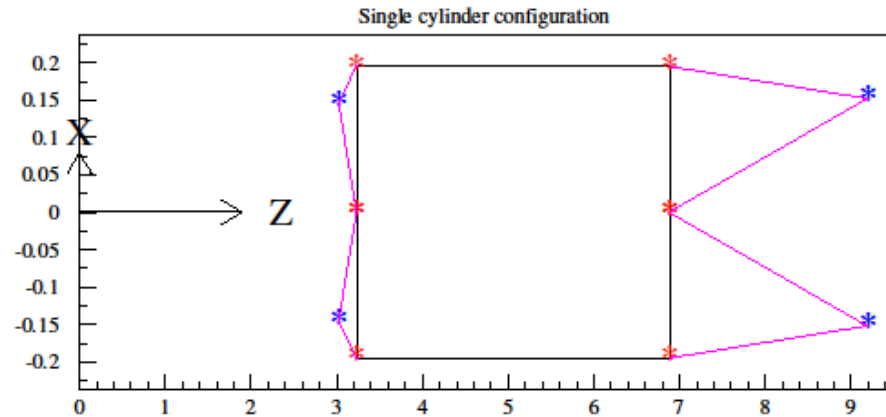


All tolerances met

First Simulations

16 lines:

- N=4
- Option B
- Both ends



* Detector point
* Reference point
-- Line of sight

Cylinder dimensions

Radius = 0.195 m
Half-length = 1.825 m

Refer. offsets from cylinder ends

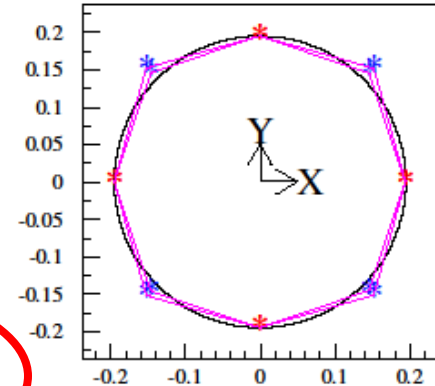
r = 2.0 cm z = 231.4 cm
r = 1.1 cm z = -20.8 cm

CM position precisions (μm)

x = 1.3 y = 1.3 z = 0.1

Axis rotation precisions (μrad)

pit = 0.6 yaw = 0.6 roll = 1.6

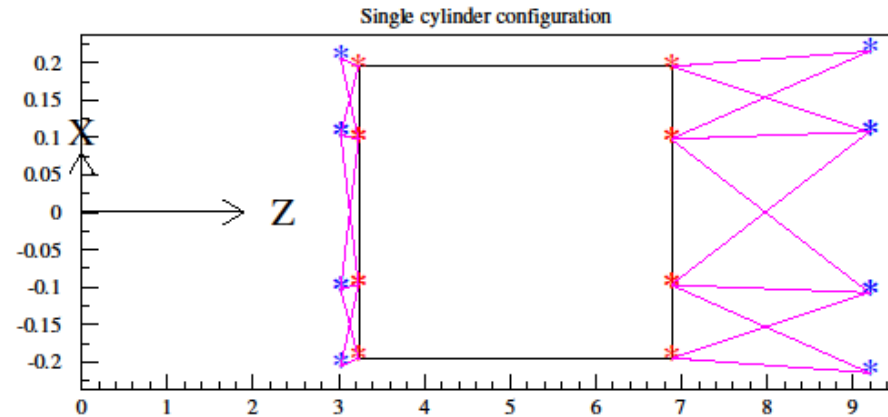


All tolerances met

First Simulations

Deluxe (36 lines):

- N=6
- Option C
- Both ends



* Detector point
* Reference point
-- Line of sight

Cylinder dimensions

Radius = 0.195 m
Half-length = 1.825 m

Refer. offsets from cylinder ends

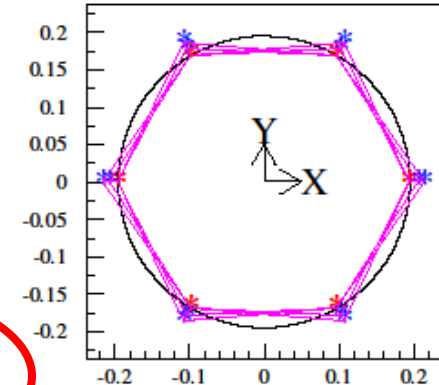
r = 2.0 cm z = 231.4 cm
r = 1.1 cm z = -20.8 cm

CM position precisions (μm)

x = 0.8 y = 0.8 z = 0.1

Axis rotation precisions (μrad)

pit = 0.4 yaw = 0.4 roll = 1.2



All tolerances met

First Simulations

Conclusion:

16 lines probably fine

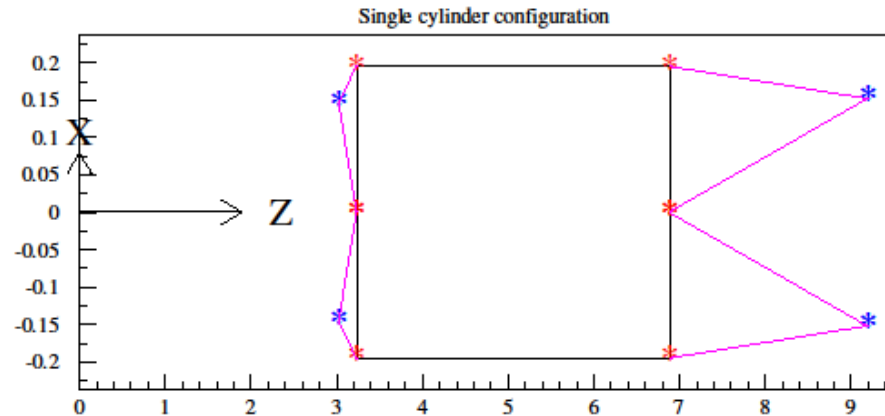
- Precision better than needed
- Tolerant of channel loss

→ Need four retroreflectors on each end of QD0

→ Need four launch points (2 beams each) on QF1 and Hcal

Caveats:

- Assumes reference points on Hcal known!
- Bridging detector gap is important → Future simulation



* Detector point
* Reference point
- Line of sight

Cylinder dimensions

Radius = 0.195 m

Half-length = 1.825 m

Refer. offsets from cylinder ends

r = 2.0 cm z = 231.4 cm

r = 1.1 cm z = -20.8 cm

CM position precisions (μm)

x = 1.3 y = 1.3 z = 0.1

Axis rotation precisions (μrad)

pit = 0.6 yaw = 0.6 roll = 1.6

