

Reconstruction of particle tracks using Deep Neural Networks and estimation of reconstruction errors

Karol Białaś Mateusz Słysz

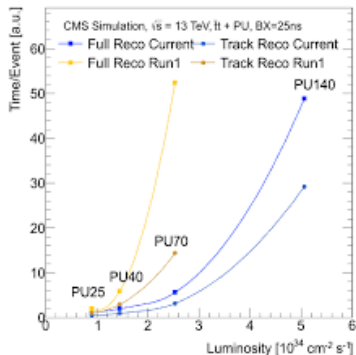
Supervisor: dr hab. Marcin Wolter

PPSS Programme, IFJ

August 2, 2019

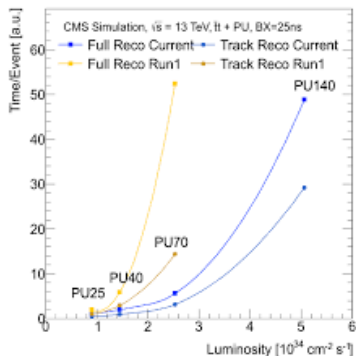
Motivation

- For currently used algorithms tracking time needed to process one event grows quickly (worse than $O(n^2)$) with luminosity.



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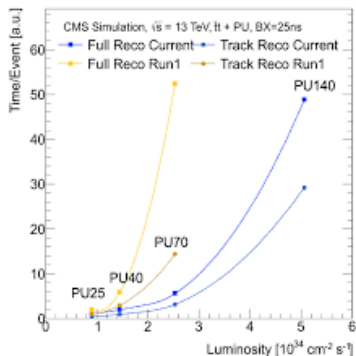
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- Training neural networks can also be long, but can be parallelized.
- Once trained, neural networks work much faster.

Classical Approach - Convolutional Neural Network

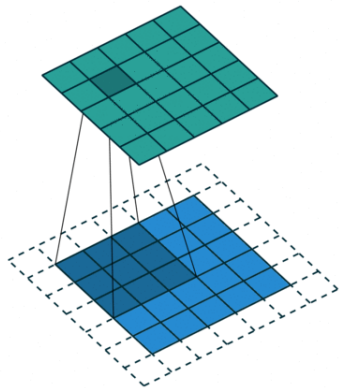


Fig. 1: Convolutional Layer [1]

Classical Approach - Convolutional Neural Network

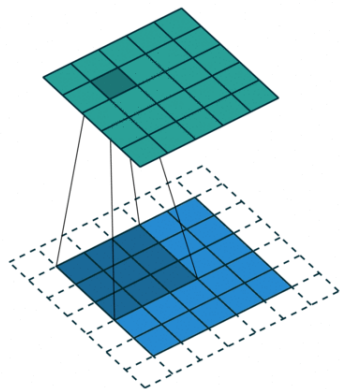


Fig. 1: Convolutional Layer [1]

CNN returns only a single value \rightarrow no error estimation!

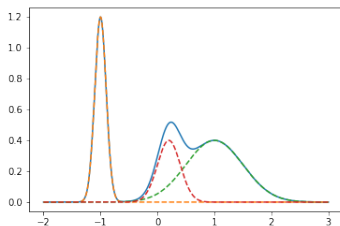
New Idea - Mixture Density Network

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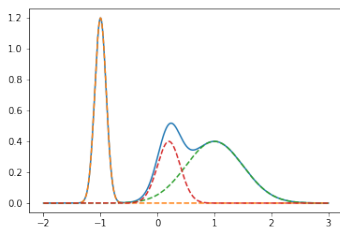
$$\rho(y) = \sum_{i=1}^M w_i \mathcal{N}_i(\mu_i, \sigma_i^2, y)$$



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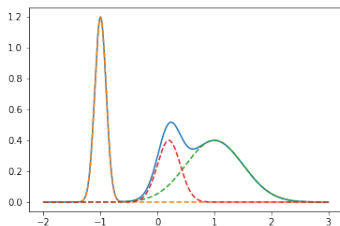


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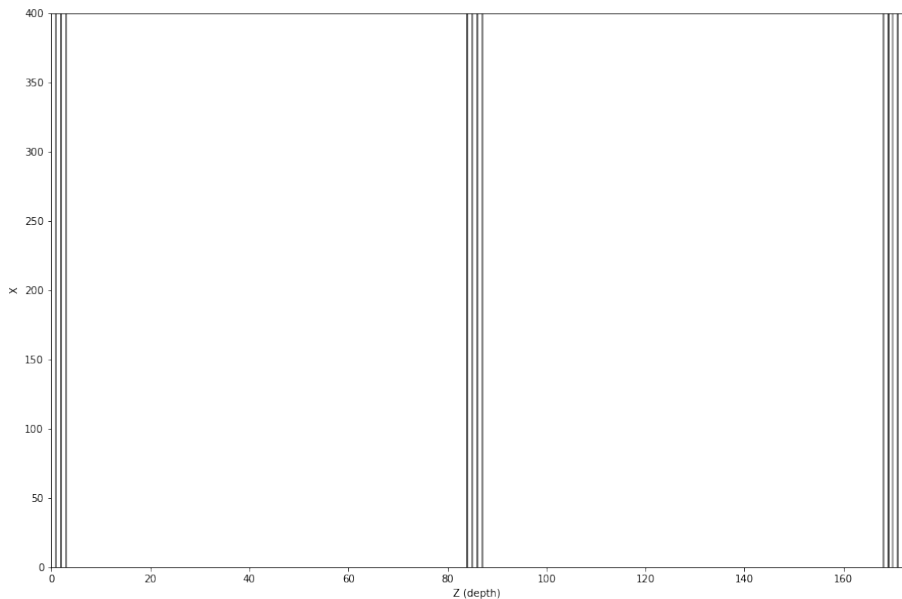
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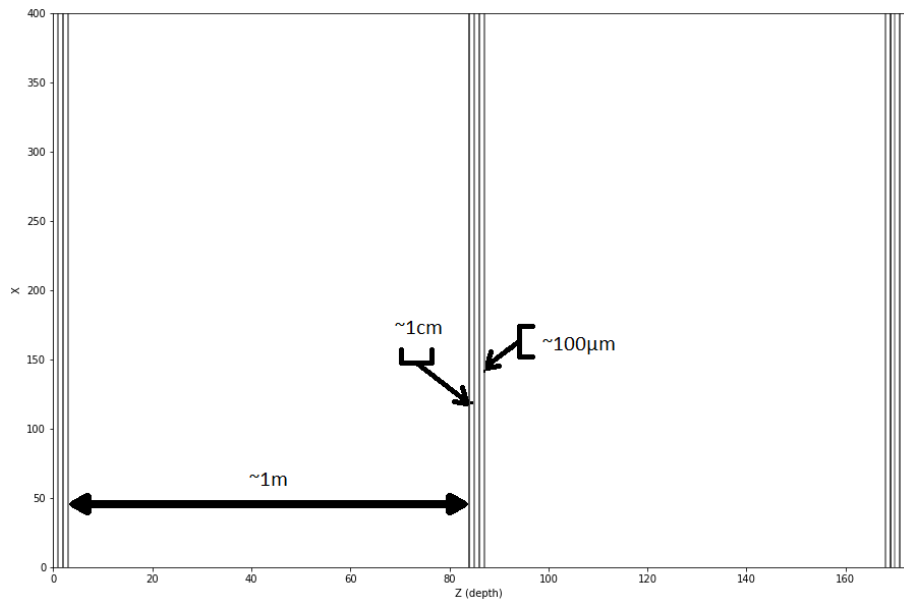


- Only one track parameters are given to the network during training
- Works well with variable output size (number of tracks may differ)

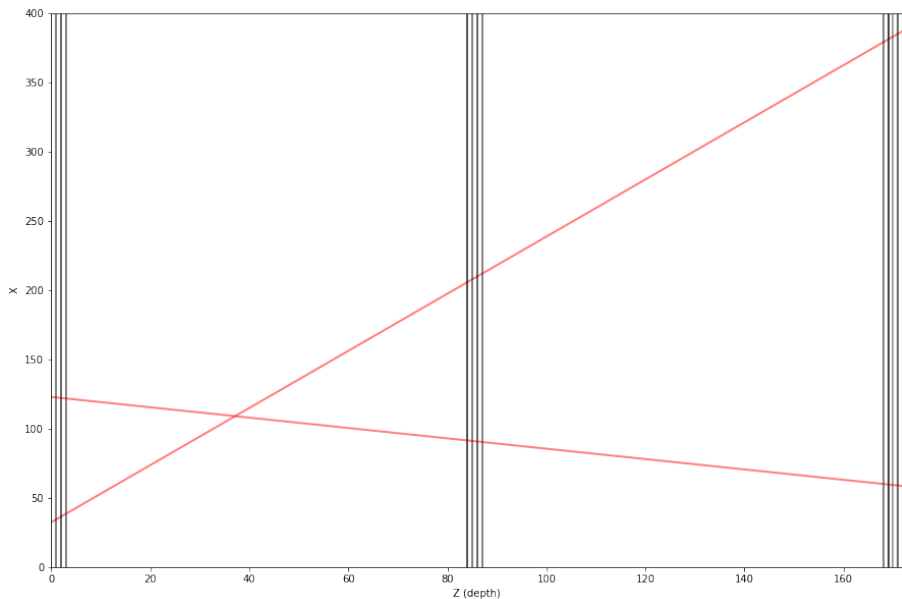
Goal - reconstruction of particle tracks



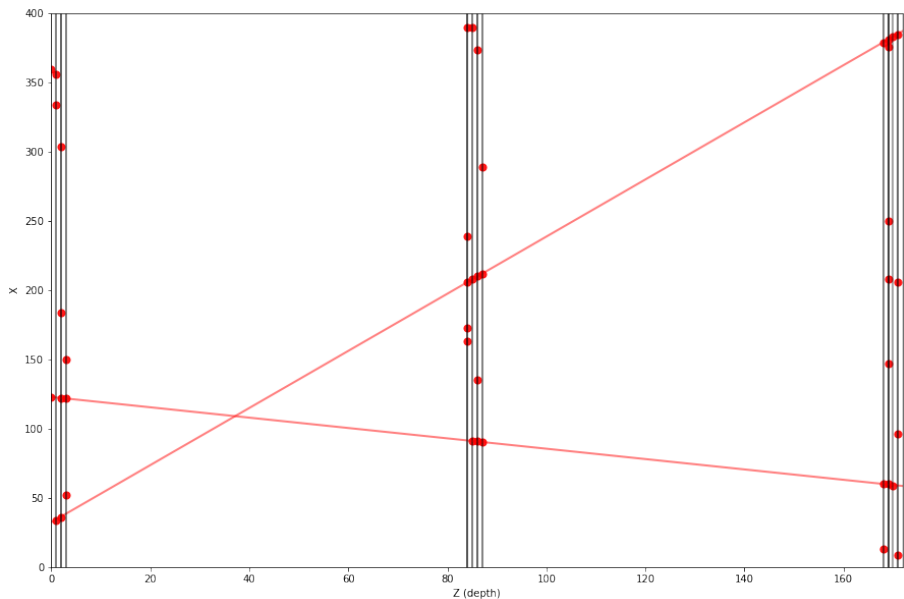
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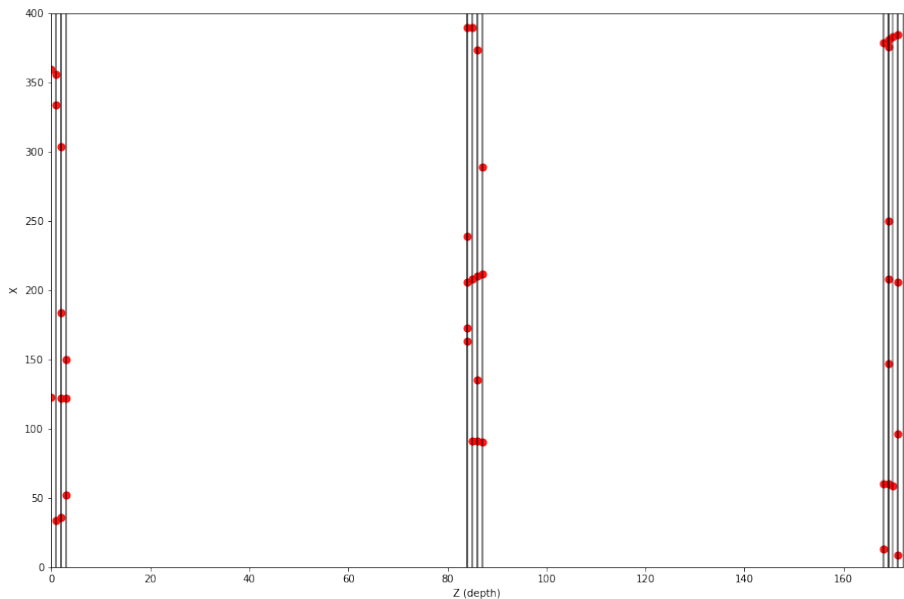
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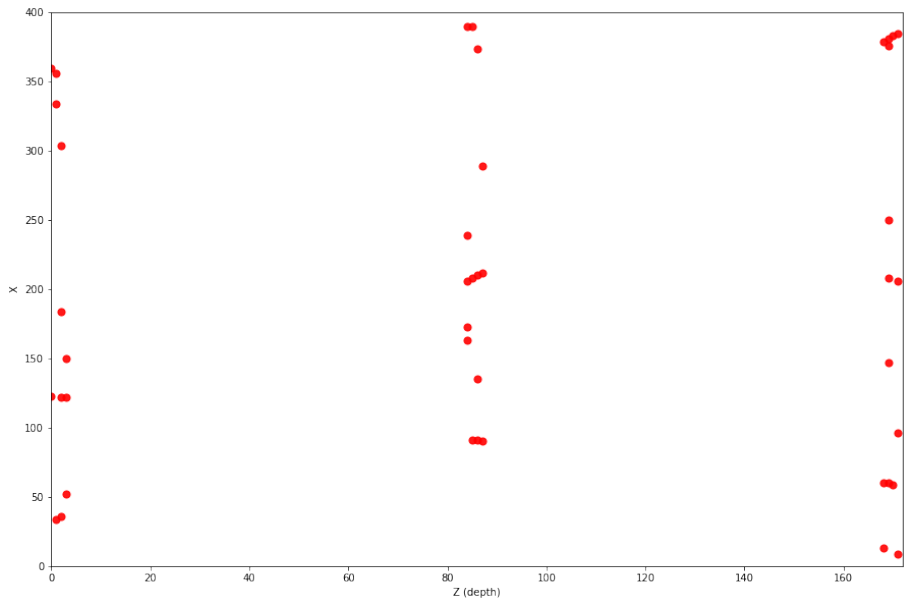
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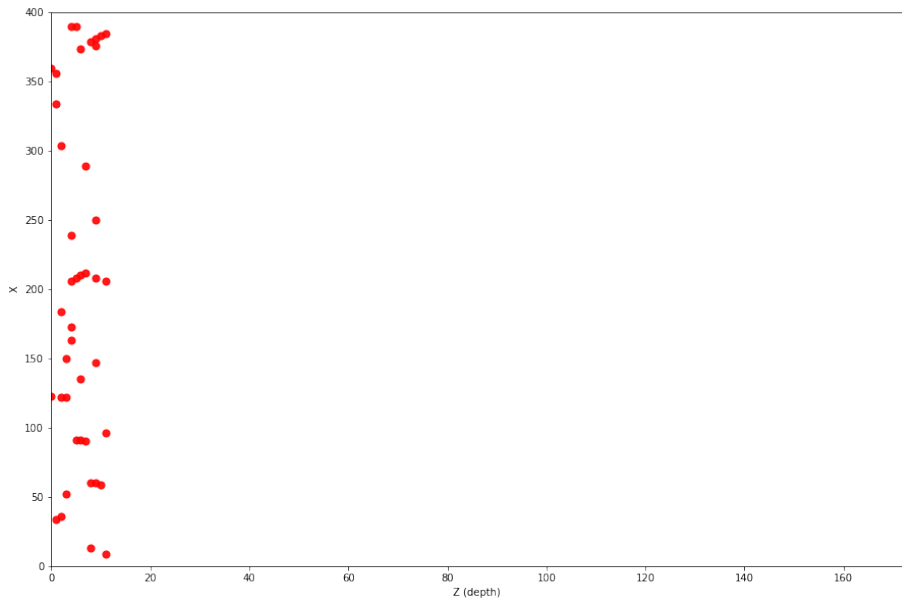
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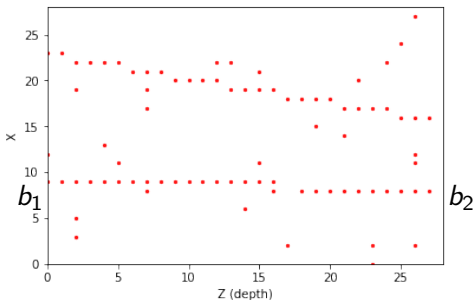


Goal - reconstruction of particle tracks



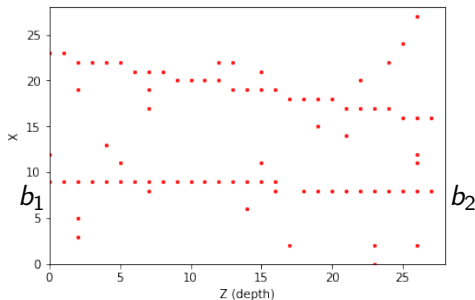
Toy Problem - Generating Data

- Generating images of size 28x28 pixels with straight lines and some random noise (matrix of 0s and 1s)



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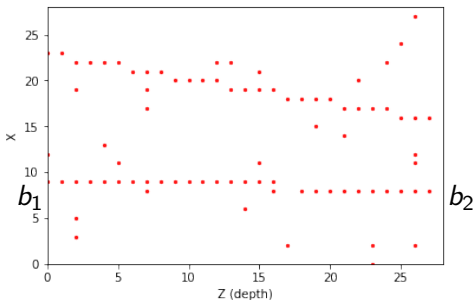
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- Training vector (single track): $[b_1, b_2]$

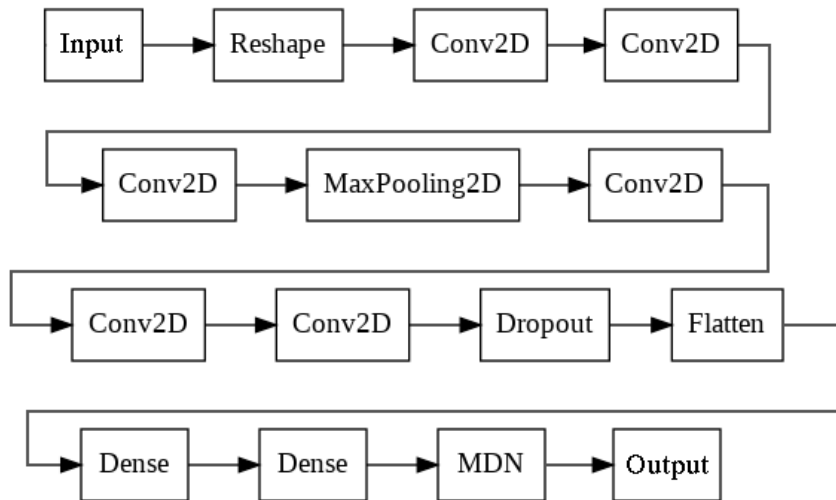
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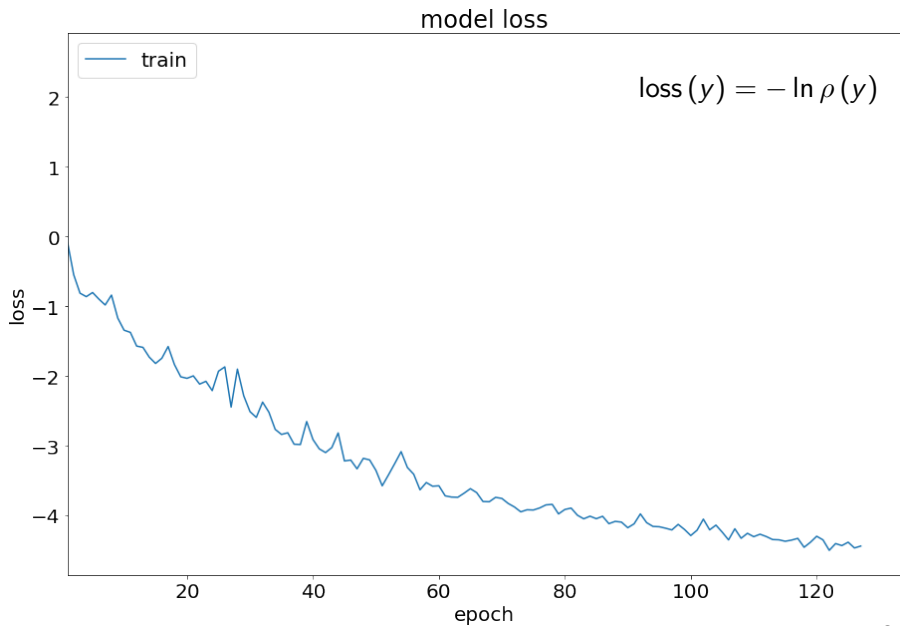


- Training vector (single track): $[b_1, b_2]$
- Prediction vector (3 mixtures):
 $[b_1^1, b_2^1, b_1^2, b_2^2, b_1^3, b_2^3, \sigma_1^1, \sigma_2^1, \sigma_1^2, \sigma_2^2, \sigma_1^3, \sigma_2^3, w^1, w^2, w^3]$

Neural Network used

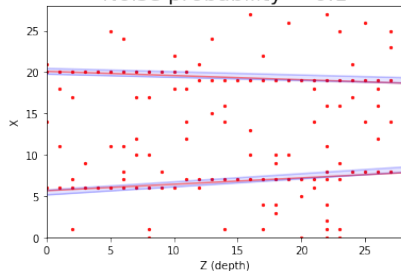


Learning process

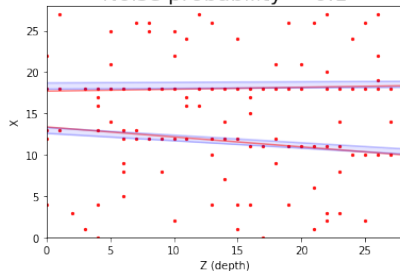


Toy Problem - Results

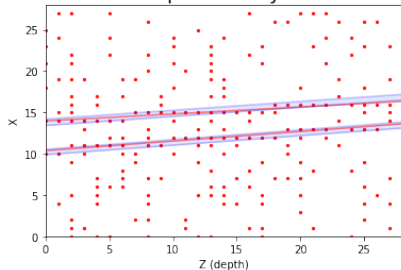
Noise probability = 0.1



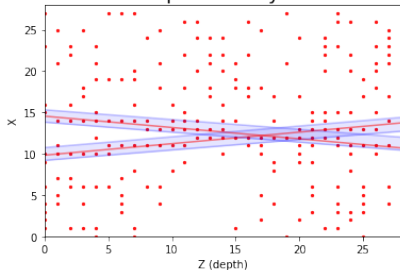
Noise probability = 0.1



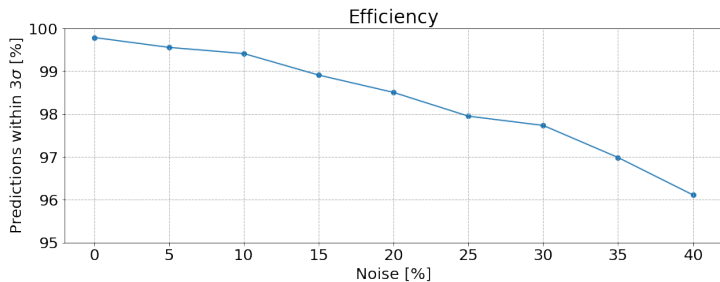
Noise probability = 0.2



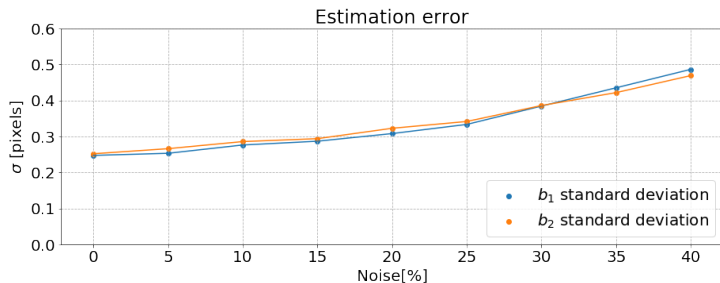
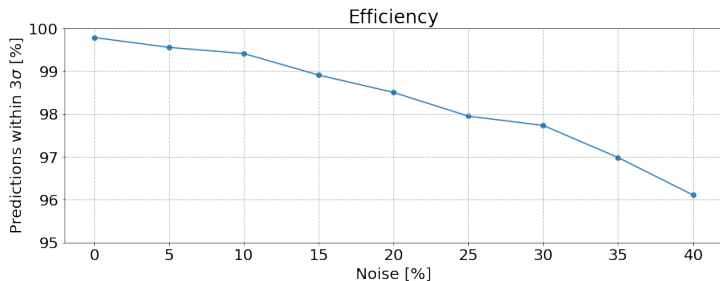
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How does random noise affect prediction ability?

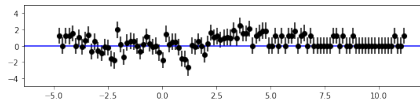
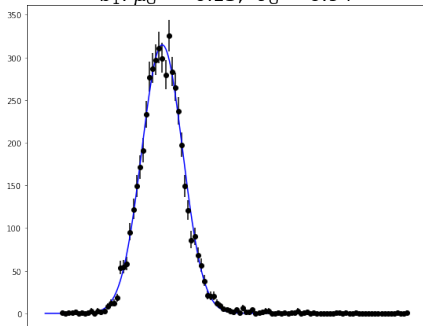


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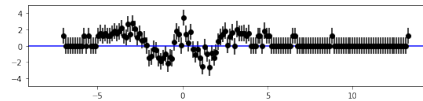
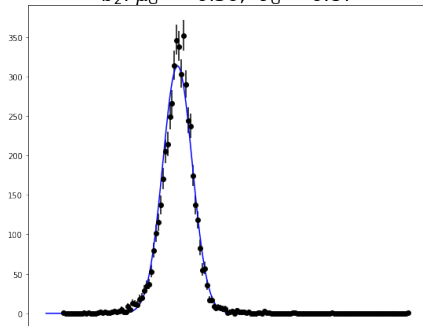


Pull plots - error estimation

$b_1: \mu_G = -0.13, \sigma_G = 0.94$

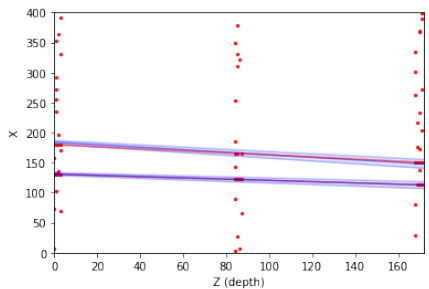
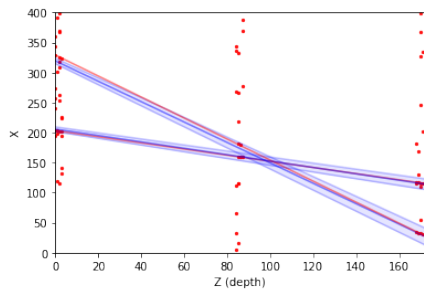
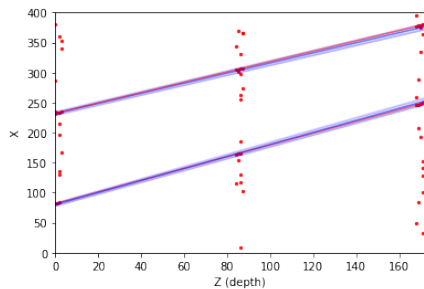
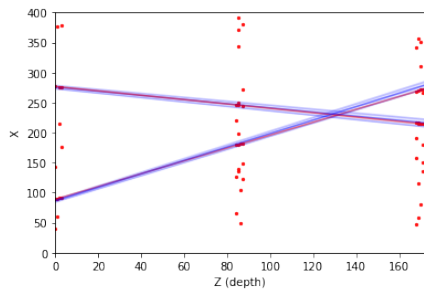


$b_2: \mu_G = -0.30, \sigma_G = 0.87$



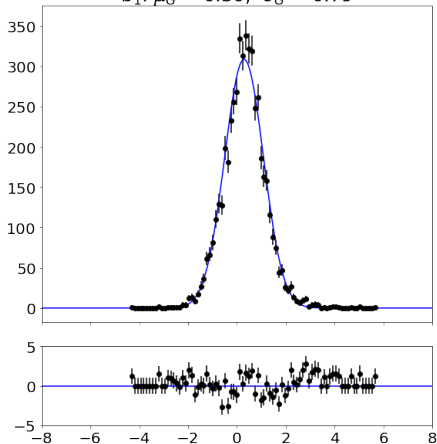
$$\frac{y_{true} - \mu}{\sigma}$$

Results - Realistic Data

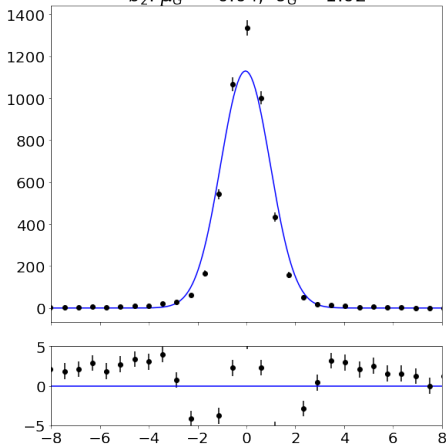


Pull plots - realistic case

$b_1: \mu_G = 0.30, \sigma_G = 0.79$



$b_2: \mu_G = -0.04, \sigma_G = 1.02$



- There are plans to use neural network tracking in MuonE experiment operating at the SPS accelerator at CERN



Fig. 2: MUonE experiment logo[2]

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Fig. 2: MUonE experiment logo[2]

- Including magnetic fields → more layers
- Extending the model to 3D



Keras



TensorFlow



python™

colab










Link to PPSS-Particle-Tracking Repository:

<https://github.com/Matek1731/PPSS-Particle-Tracking>

Questions?

Bibliography

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Backup

Loss - 400x12

