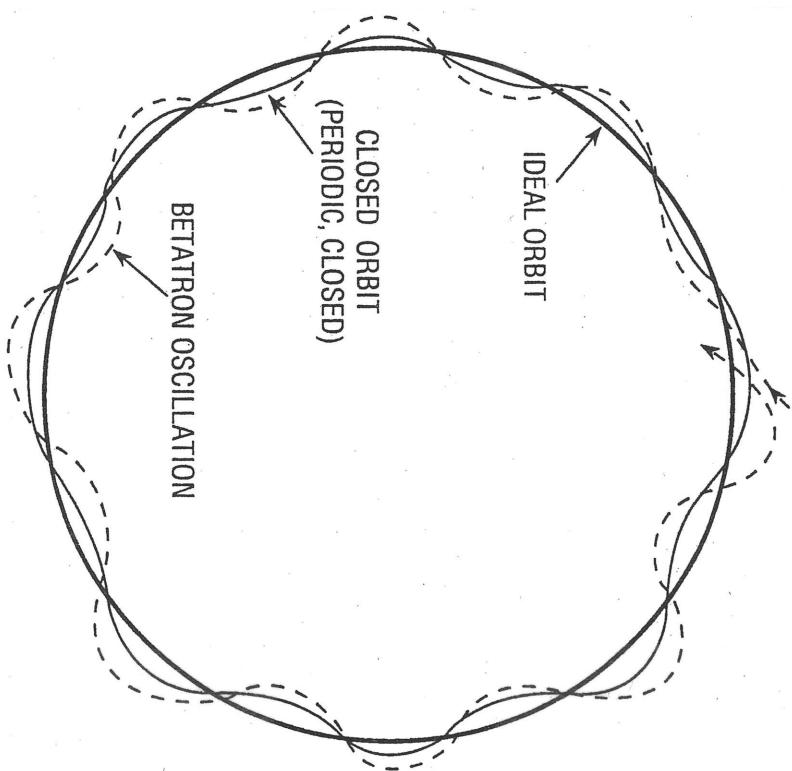


Accelerator Physics Lecture Modules

1. Introduction/Timing
2. Beam propagation basics
3. Simple Harmonic Oscillator
4. Betatron oscillations (transverse motion)
5. Dispersion
6. Closed Orbit Distortion
7. Synchrotron oscillations
8. Properties of synchrotron radiation
9. Radiation damping
10. Equilibrium emittance

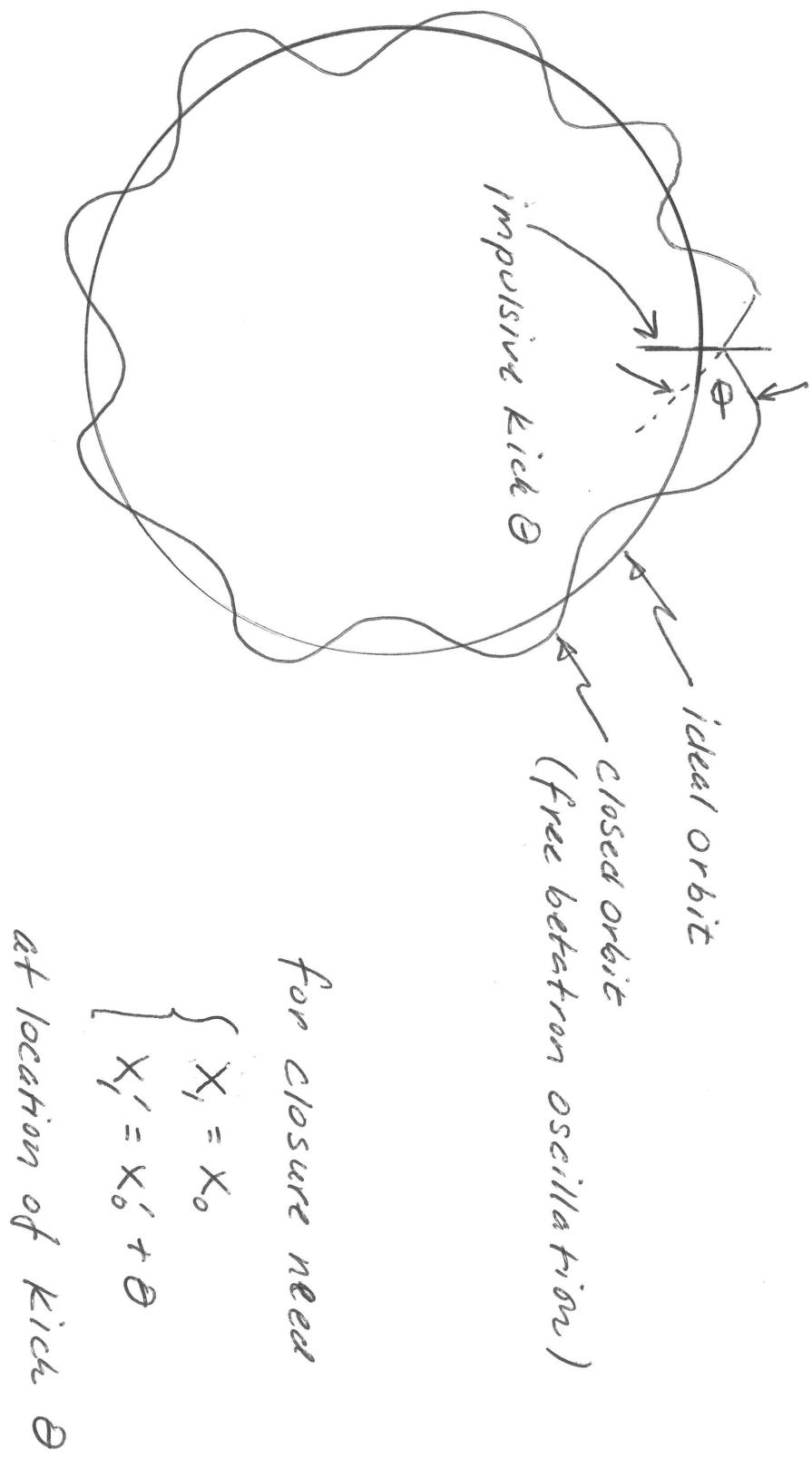
Closed Orbit Distortions

- Betatron oscillations do not 'close'
- The betatron function does 'close'
 - Twiss parameters (α, β, δ) repeat because focusing function $K(s)$ repeats
- The Dispersion function also 'repeats'
 - boundary conditions on $D(s), D'(s)$
- What about the 'Closed Orbit'
 - Closed Orbit also repeats (by definition)



Closed Orbit Distortions (COD)

- Dipole errors distort the closed orbit - 'kick'



Closed Orbit Distortion Formula

From Dispersion (closed orbit) calculation

$$D(s) = \frac{x(s)}{\Delta p} = \frac{\sqrt{\beta(s)}}{2\sin\pi Q} \int \frac{\sqrt{\beta(\tilde{s})}}{R(\tilde{s})} \cos(\phi(s) - \phi(\tilde{s}) + \pi Q) d\tilde{s}$$

Re-arrange $\frac{\Delta p}{p}$ normalization

$$x(s) = \frac{1}{2\sin\pi Q} \int \left[\frac{\frac{\Delta p}{p}}{R(\tilde{s})} \right] \sqrt{\beta(s)\beta(\tilde{s})} \cos(\phi(s) - \phi(\tilde{s}) + \pi Q) d\tilde{s}$$

\uparrow
kick
distribution observation point s
 perturbation points $\tilde{s} \rightarrow$ integrate

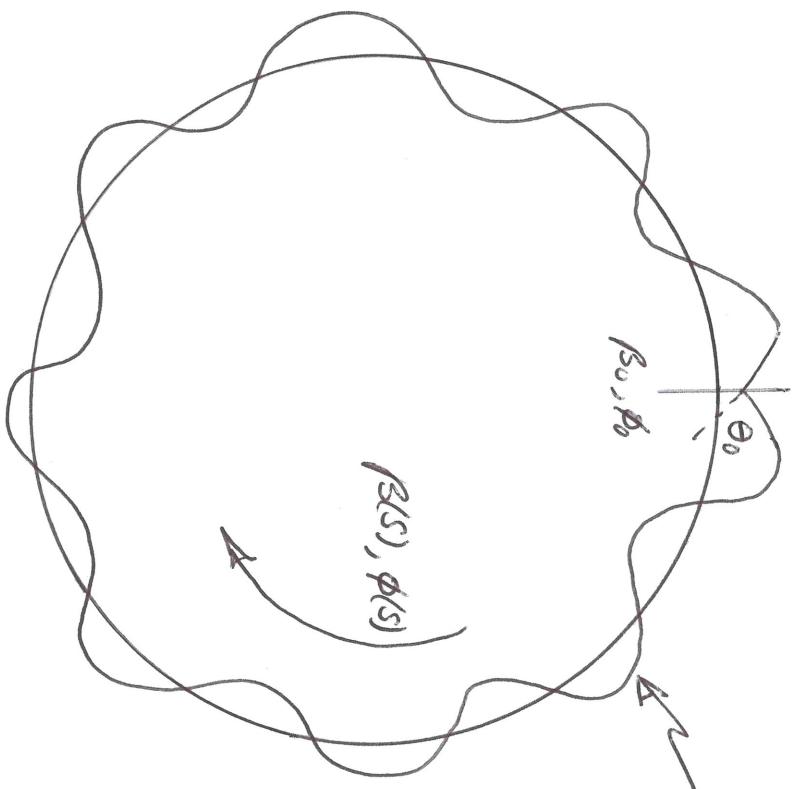
Replace the kick distribution with impulse: $\frac{\Delta p}{R(s)} \rightarrow \theta(s)$

$$x_1 = \frac{1}{2\sin\pi Q} \cdot \theta_0 \cdot \sqrt{\beta_1 \beta_0} \cos(\phi_1 - \phi_0 + \pi Q)$$

\downarrow
 \downarrow
kick
observation kick
 location

COD formula

Closed Orbit from a Kick

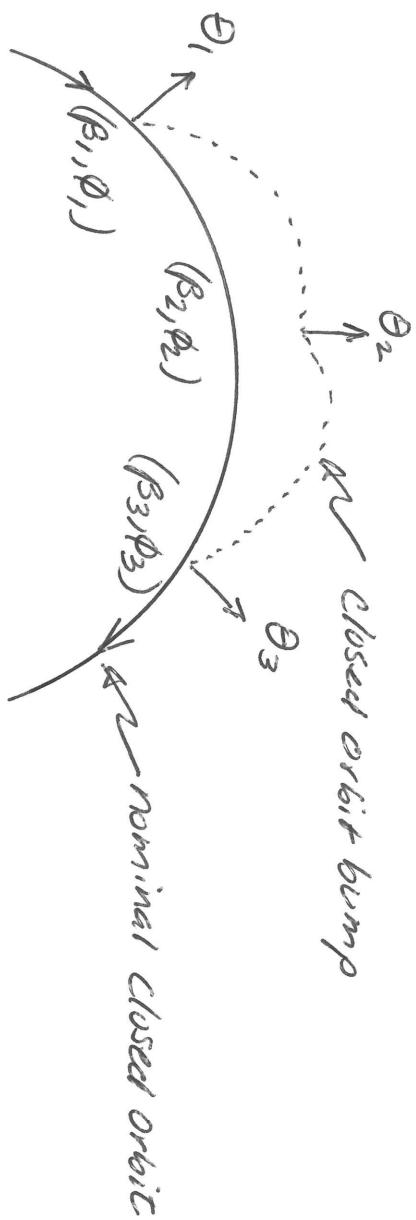


$$x_{\text{cod}}(s) = \sqrt{\beta_0 / \beta(s)} \cos(\lvert \phi(s) - \phi_0 \rvert + \pi Q)$$

↑
integer resonance
↑
note abs bars

$(\beta(s), \phi(s))$

Closed Orbit 'Bumps'



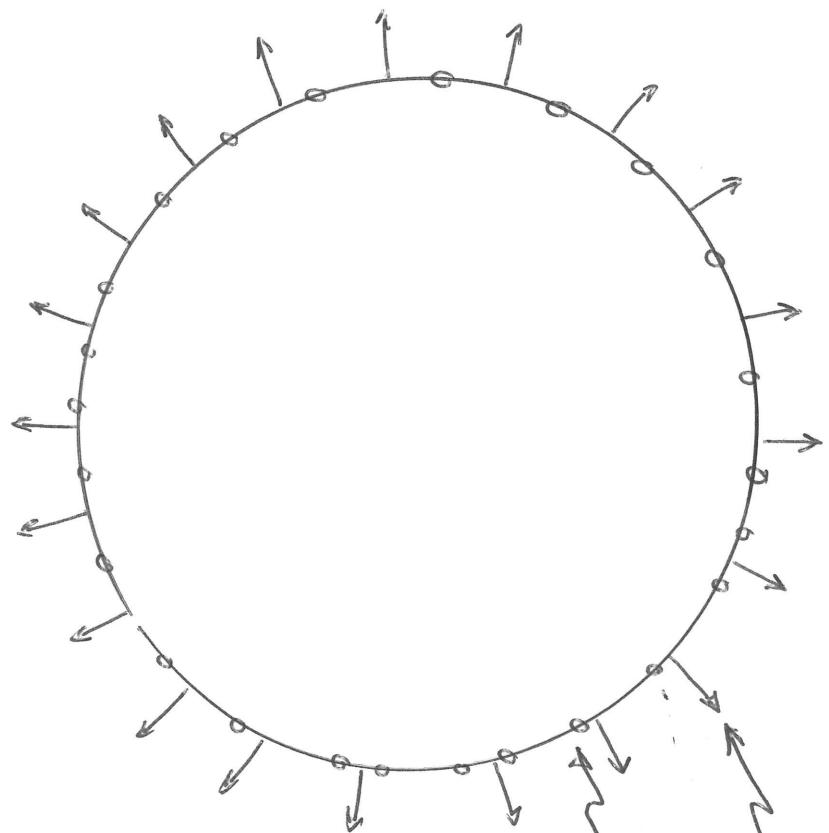
3 equations with 3 variables $(\theta_1, \theta_2, \theta_3)$

- Steer or 'point' a photon beam
- Steer counter-propagating beams into collision

- 3 bumps
- 4 bumps
- 5 bumps

⋮
closed orbit control (feedback)

The Orbit Response Matrix



orbit correctors/striking dipoles
~100ea

beam position monitors
~100ea

$$\text{kick}_i \dots \text{kick}_{100}$$

$$= \begin{pmatrix} \frac{\Delta X_1}{\Delta \theta_1} & \dots & \frac{\Delta X_1}{\Delta \theta_{100}} \\ \vdots & \ddots & \vdots \\ \frac{\Delta X_i}{\Delta \theta_1} & \dots & \frac{\Delta X_i}{\Delta \theta_{100}} \\ \vdots & \ddots & \vdots \\ \frac{\Delta X_{100}}{\Delta \theta_1} & \dots & \frac{\Delta X_{100}}{\Delta \theta_{100}} \end{pmatrix} \begin{pmatrix} \Delta \theta_1 \\ \vdots \\ \Delta \theta_{100} \end{pmatrix}$$

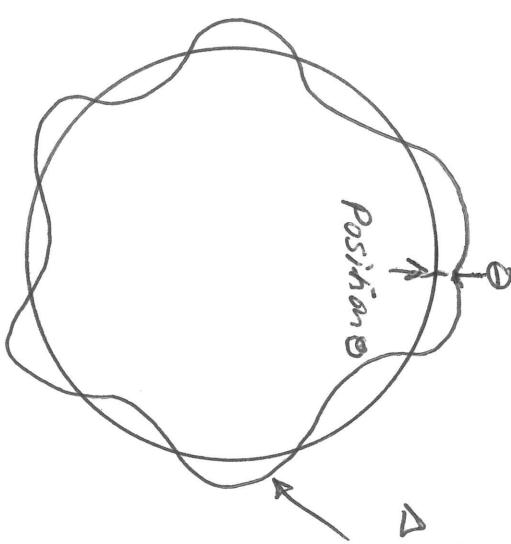
$$\boxed{\begin{aligned} \overrightarrow{\Delta X} &= R \overrightarrow{\Delta \theta} \\ \overrightarrow{\Delta \theta} &= R^{-1} \overrightarrow{\Delta X} \end{aligned}}$$

↑
inverse
response
matrix

$$\underbrace{\begin{pmatrix} \Delta X_1 \\ \vdots \\ \Delta X_{100} \end{pmatrix}}_{\text{BPMs}} = \underbrace{\begin{pmatrix} \frac{\Delta X_1}{\Delta \theta_1} & \dots & \frac{\Delta X_1}{\Delta \theta_{100}} \\ \vdots & \ddots & \vdots \\ \frac{\Delta X_i}{\Delta \theta_1} & \dots & \frac{\Delta X_i}{\Delta \theta_{100}} \\ \vdots & \ddots & \vdots \\ \frac{\Delta X_{100}}{\Delta \theta_1} & \dots & \frac{\Delta X_{100}}{\Delta \theta_{100}} \end{pmatrix}}_{\text{Response Matrix}} \underbrace{\begin{pmatrix} \Delta \theta_1 \\ \vdots \\ \Delta \theta_{100} \end{pmatrix}}_{\text{Correctors}}$$

Review I

- Dipole kicks generate Closed Orbit Distortions (COD)

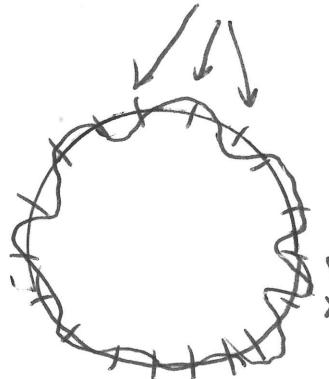


$$\Delta x_i = \frac{l}{2\sin\theta_0} \cdot \theta_0 \cdot \sqrt{\beta_i \epsilon_i} \cos((\phi_i - \phi_0) + \pi\alpha)$$

- Use corrector magnets to steer the beam (closed bump)
 - photon beams
 - beams in collision

Review II

- If a quadrupole moves it makes a 'kick' $B = \frac{\partial B}{\partial x} \cdot \Delta x$
- Many quads moving makes many kicks
each has an amplification factor
- Use orbit response matrix for feedback correction



$$\begin{pmatrix} \Delta x_1 \\ \vdots \\ \Delta x_n \end{pmatrix} = \begin{pmatrix} \text{Response Matrix} \\ \vdots \\ \text{Response Matrix} \end{pmatrix} \begin{pmatrix} \Delta \theta_1 \\ \vdots \\ \Delta \theta_m \end{pmatrix}$$

$$\vec{\Delta X} = \vec{R} \vec{\Delta \Theta}$$

$$\vec{\Delta \Theta} = \vec{R}' \vec{\Delta X}$$

- slow feedback (creep, lunar, 10's)
- fast feedback (vibration compensation)