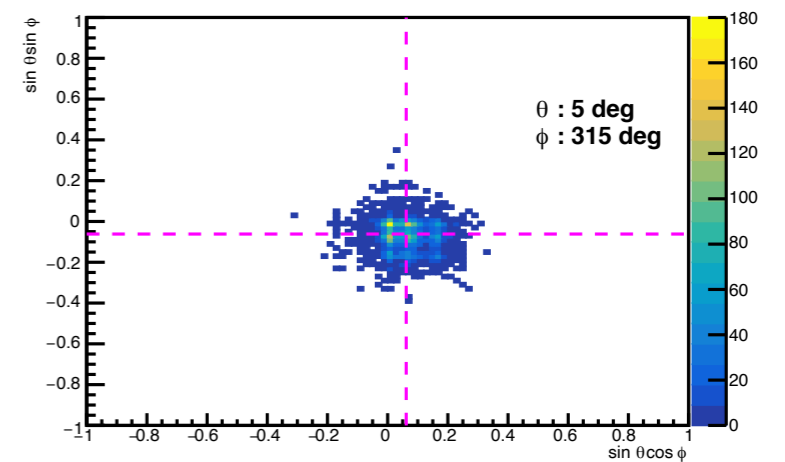
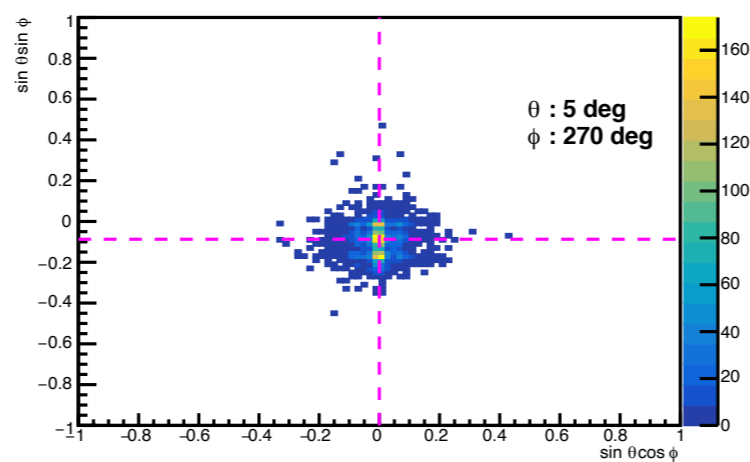
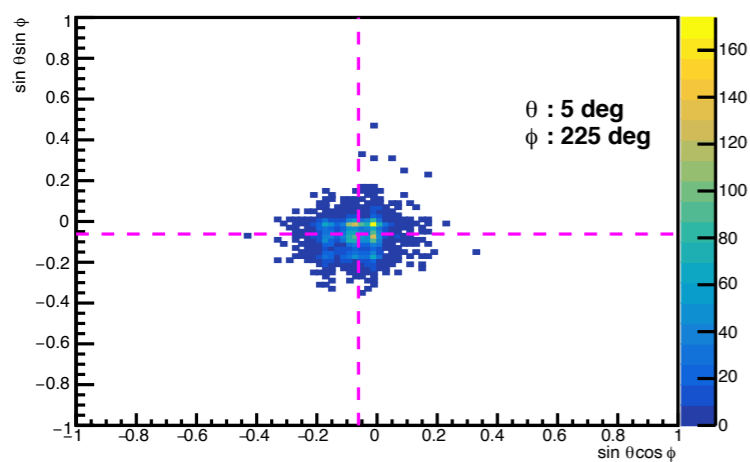
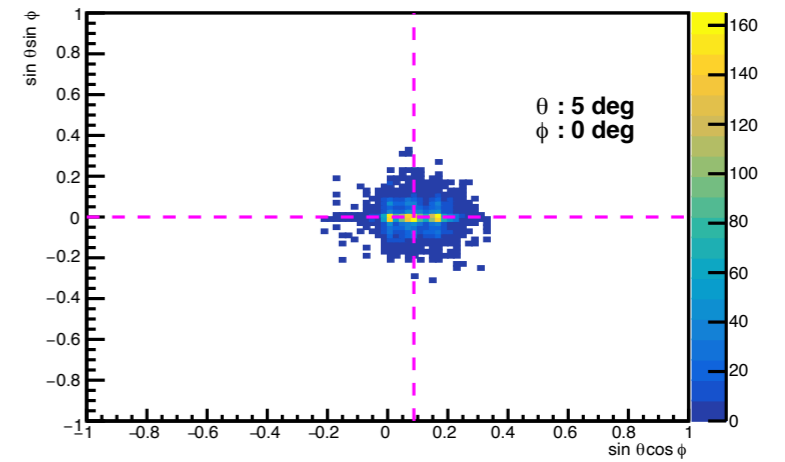
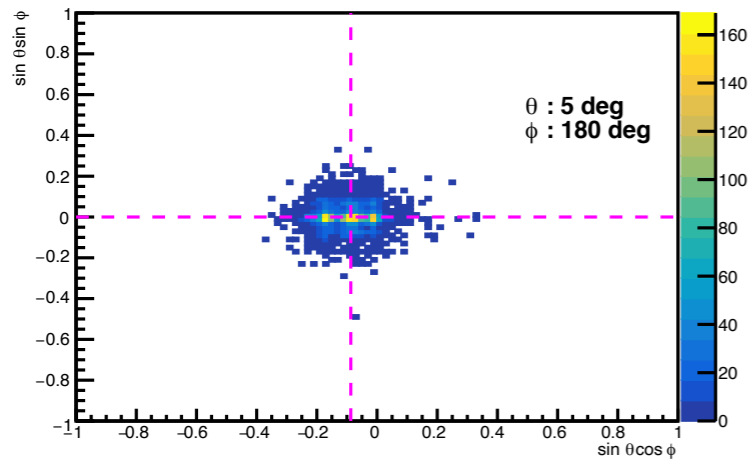
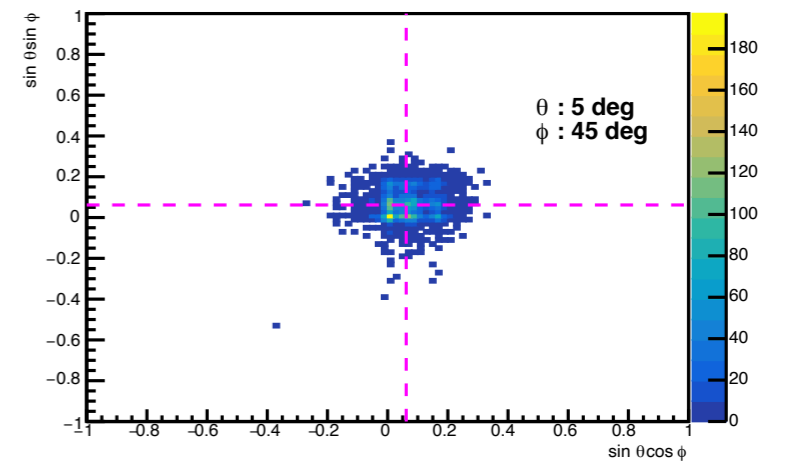
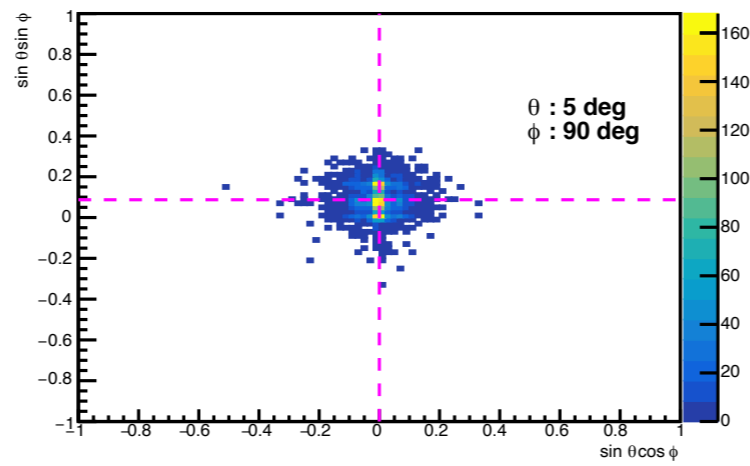
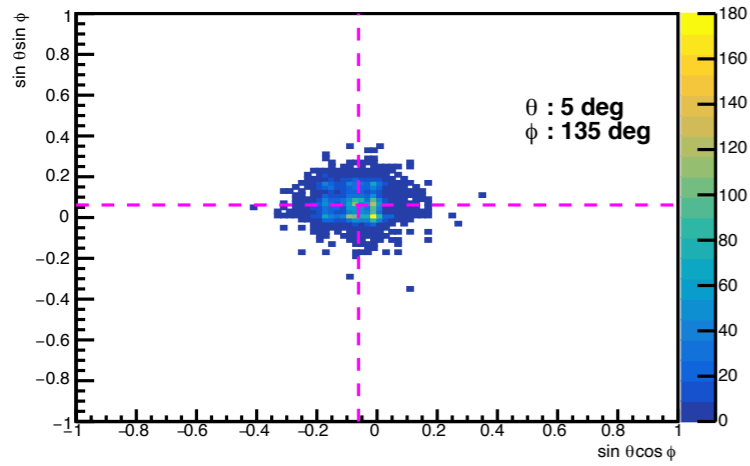


K-Koto Meeting

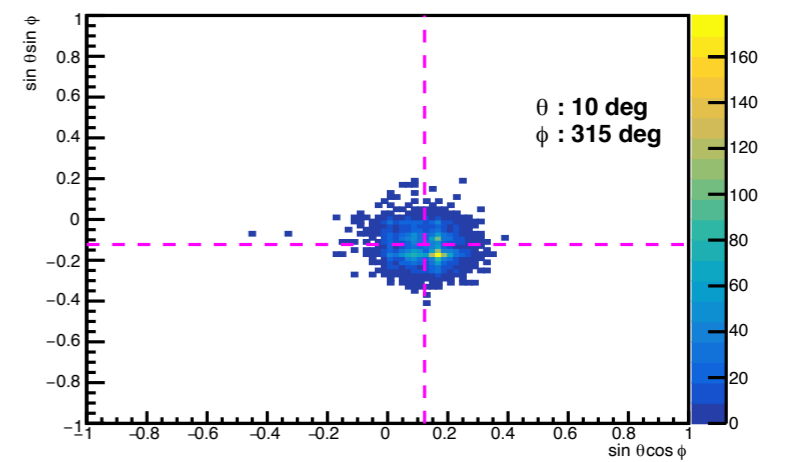
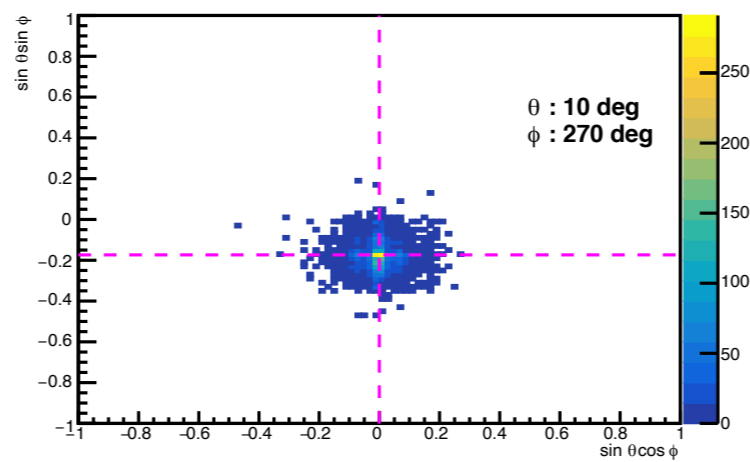
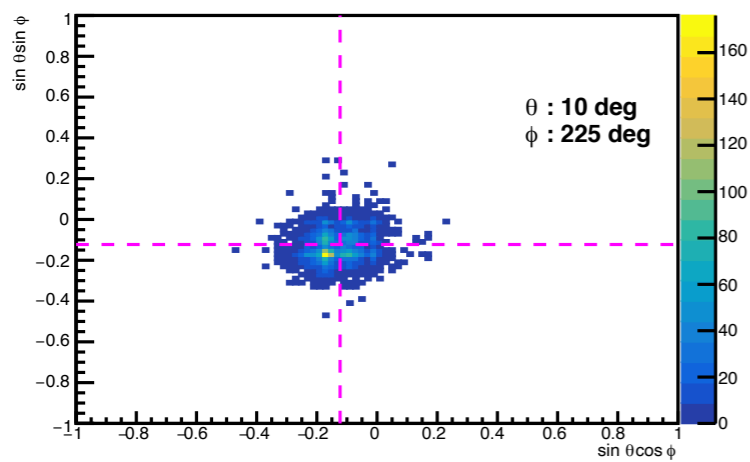
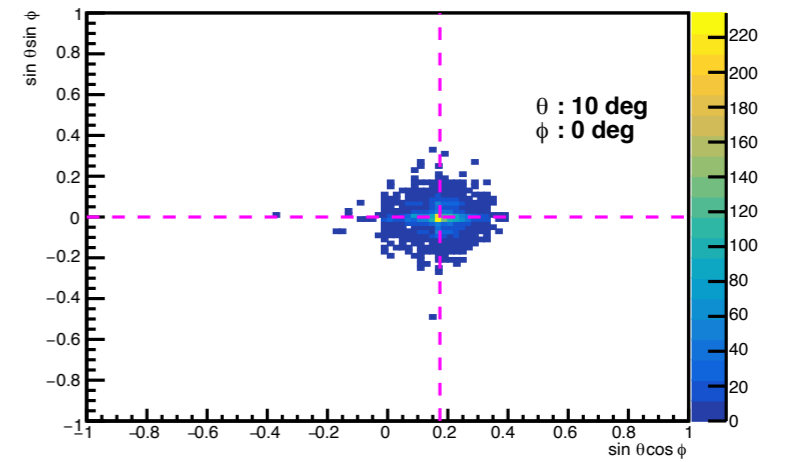
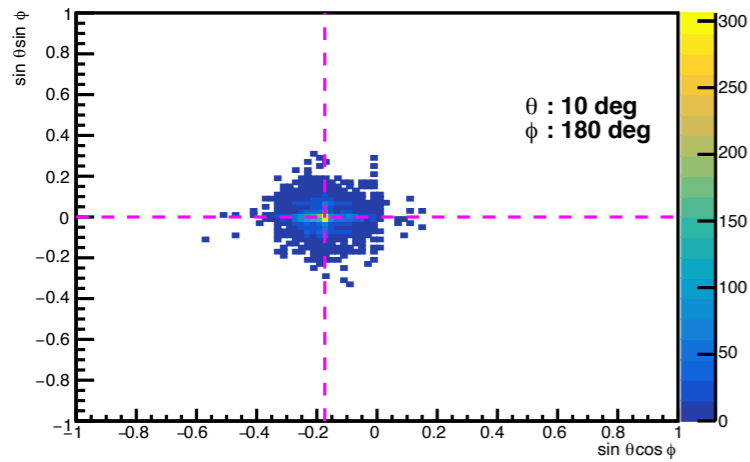
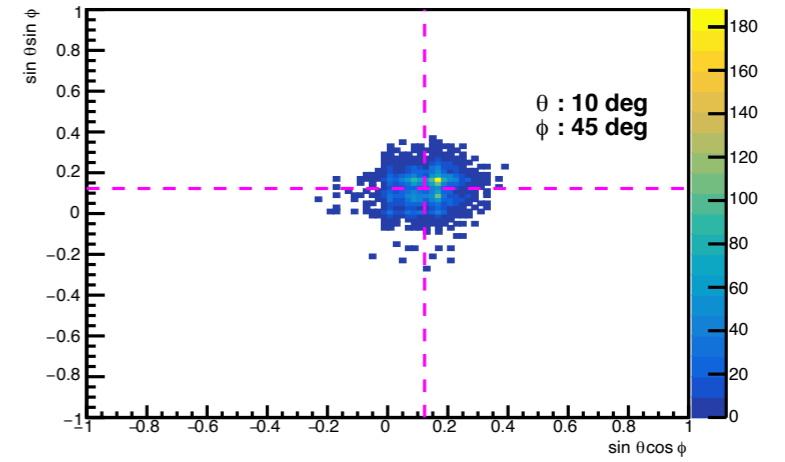
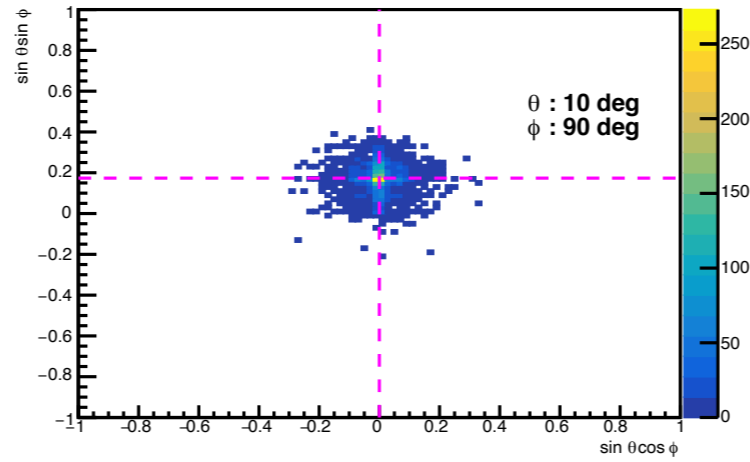
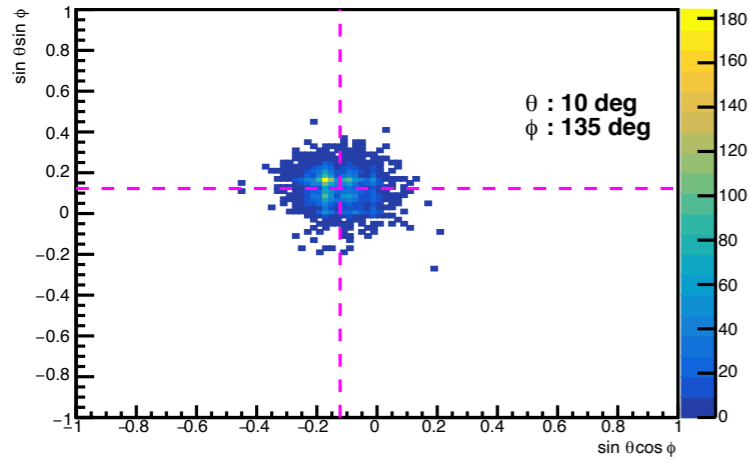
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YoungJun Kim

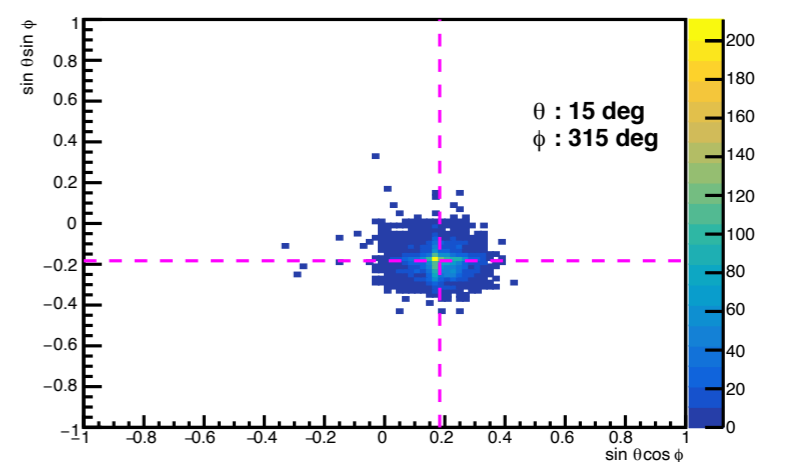
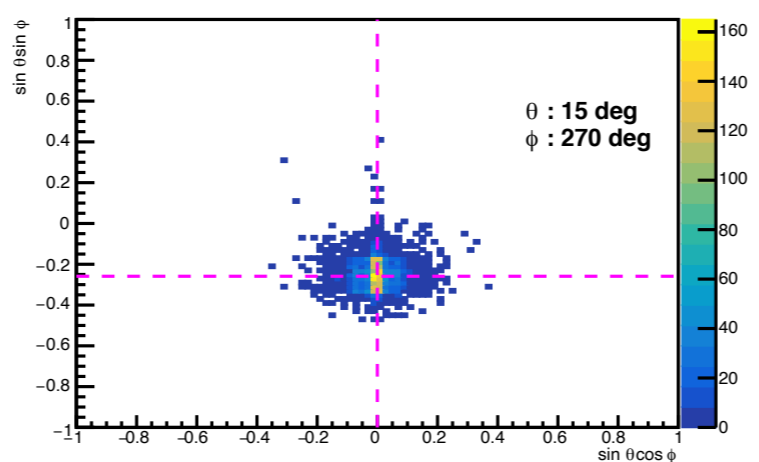
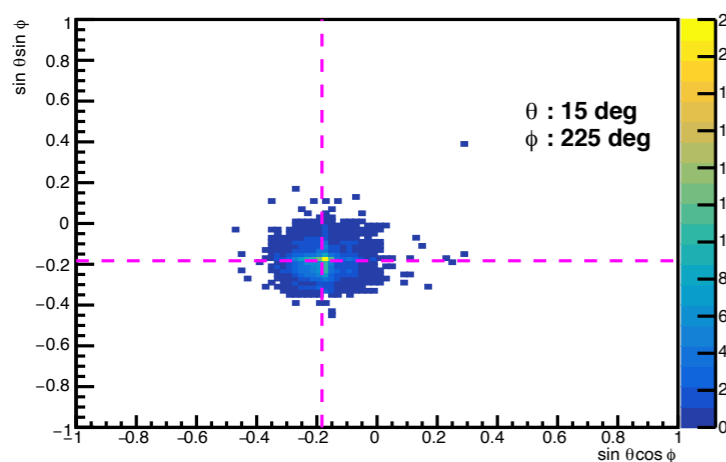
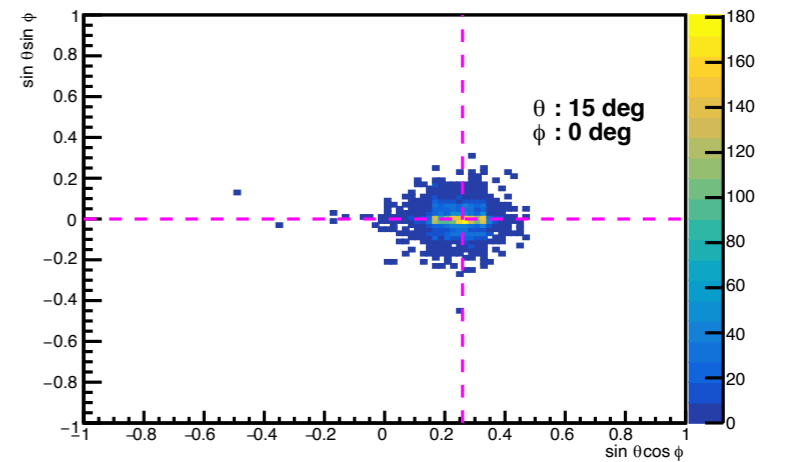
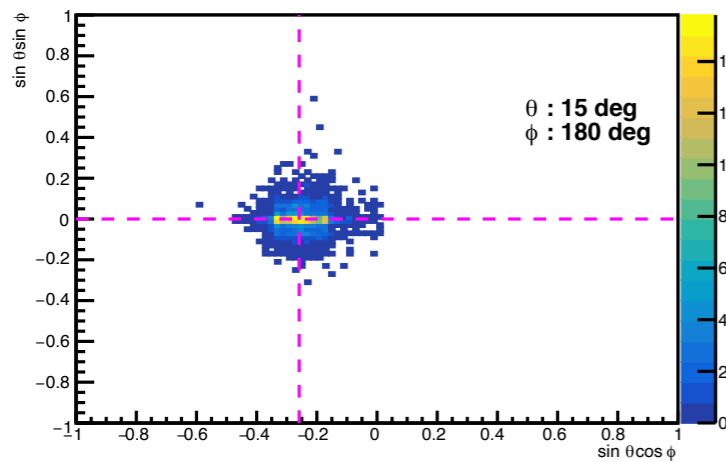
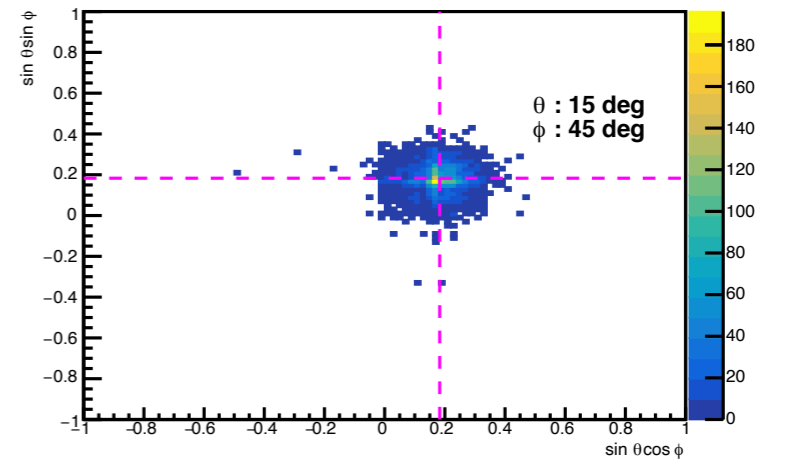
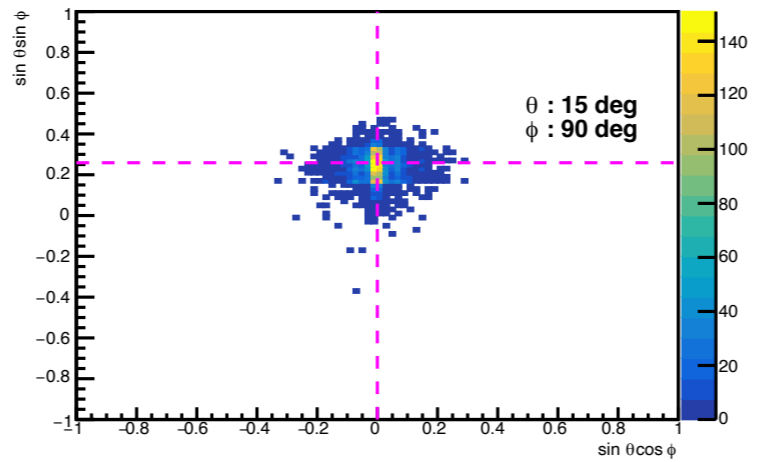
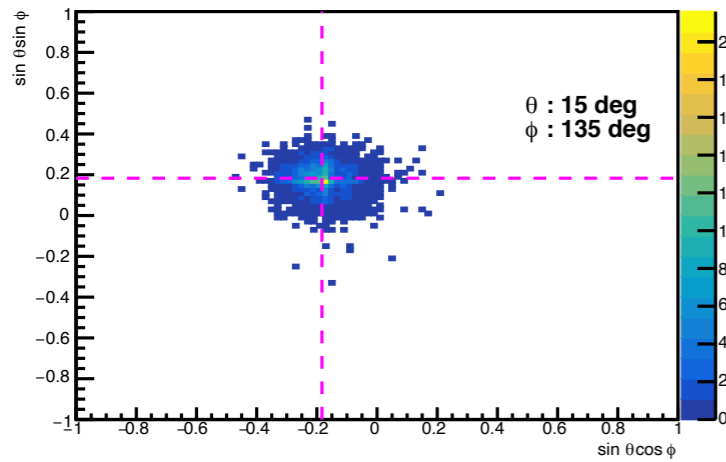
3x5 Clustering, 5 deg



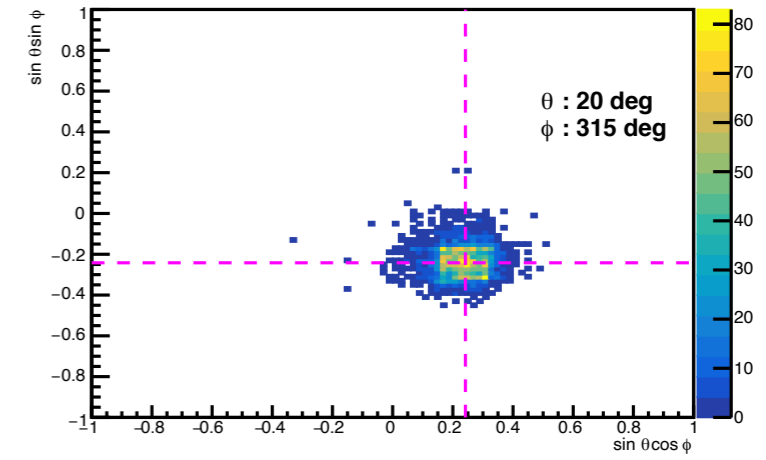
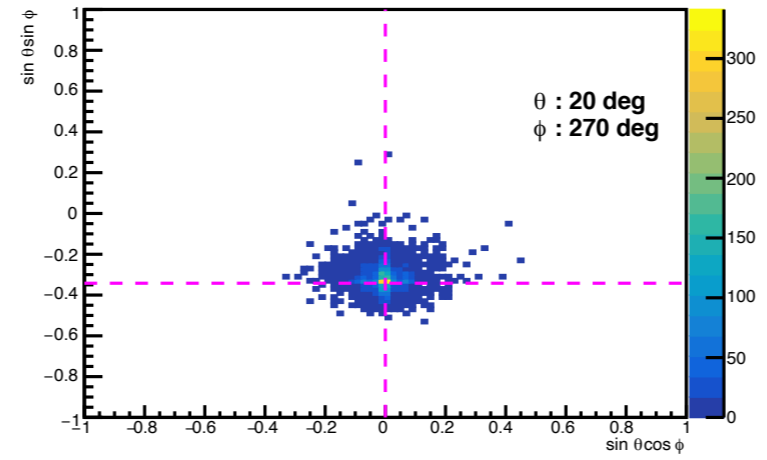
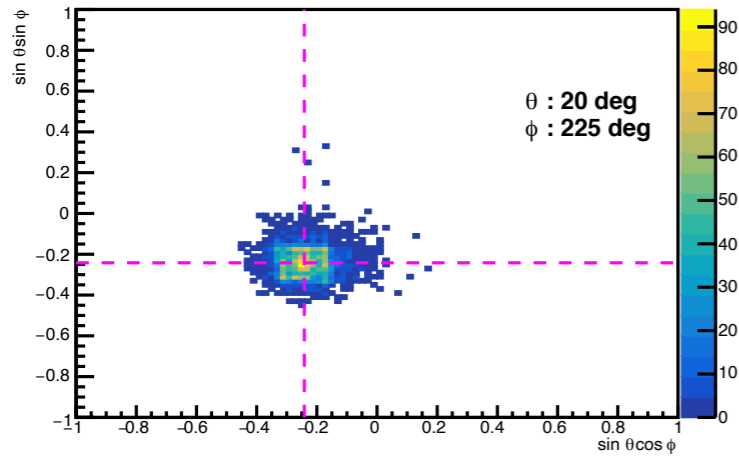
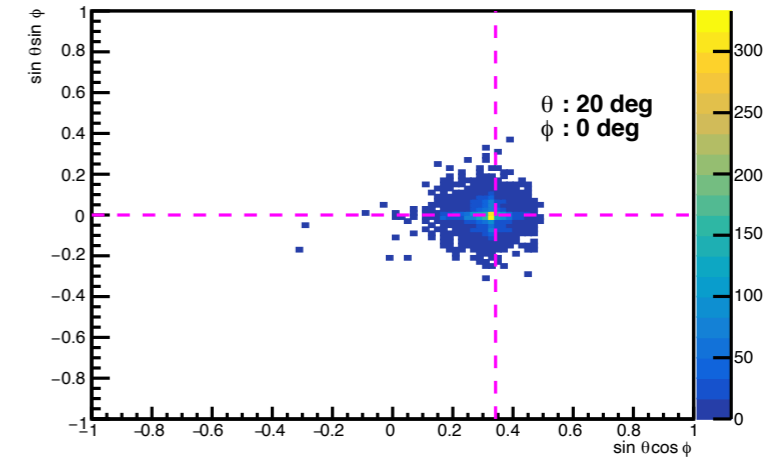
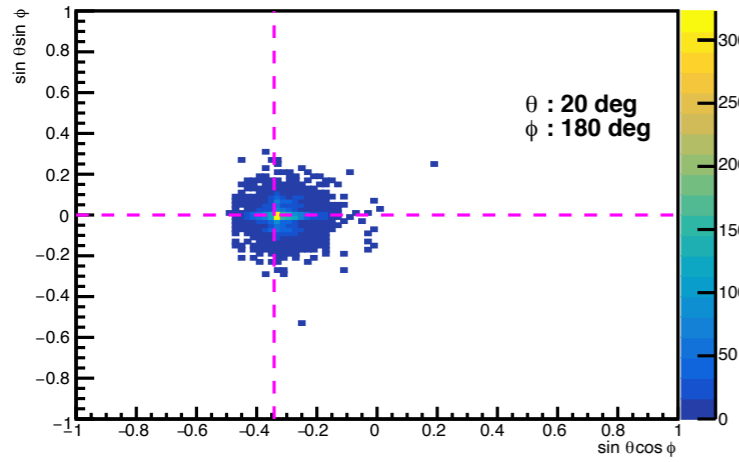
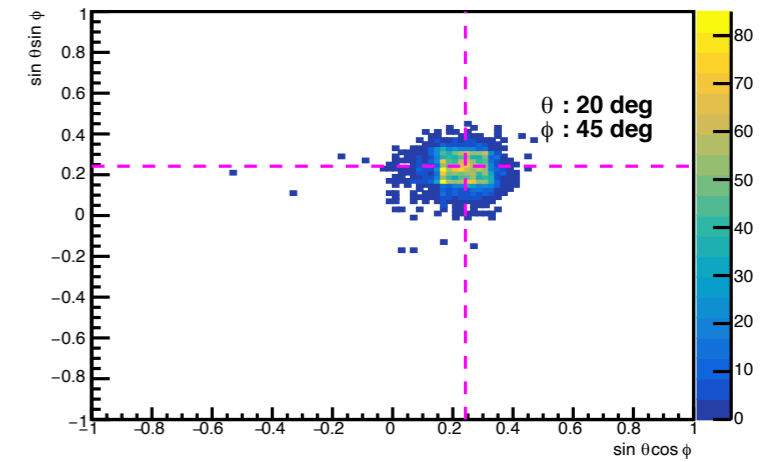
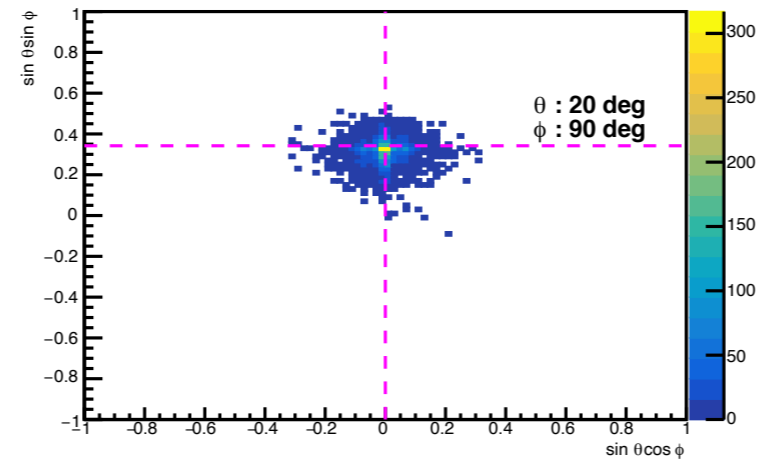
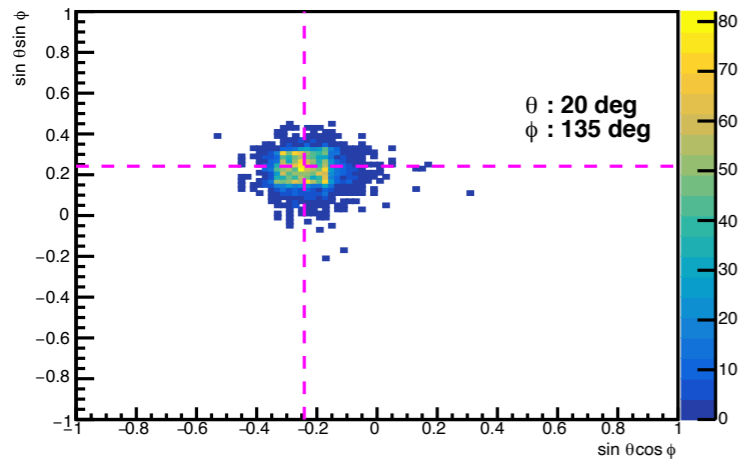
3x5 Clustering, 10 deg



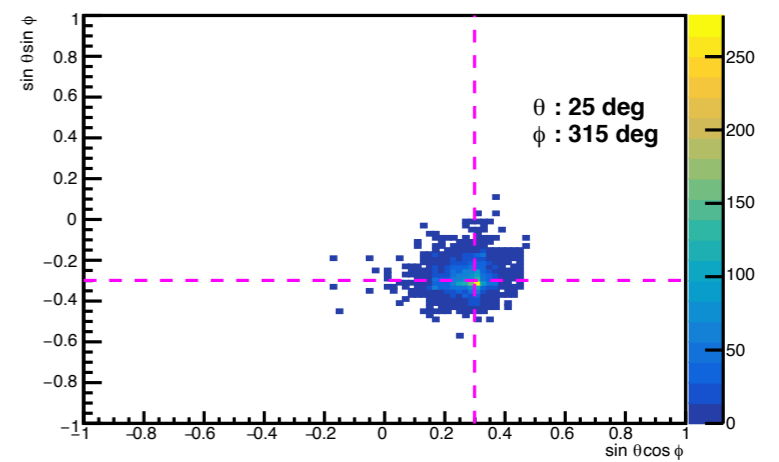
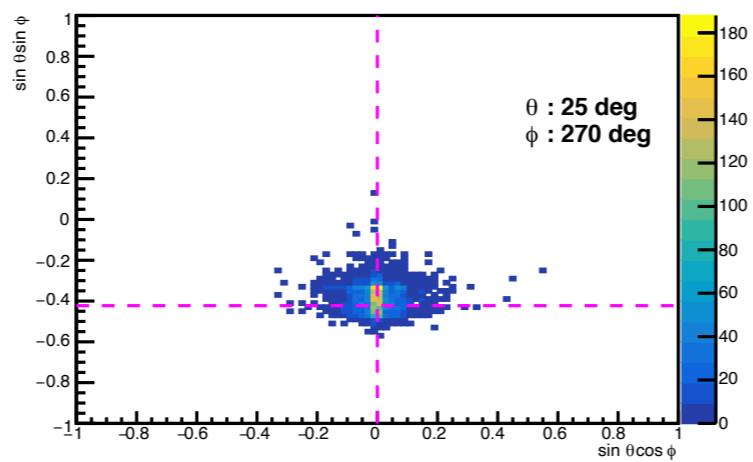
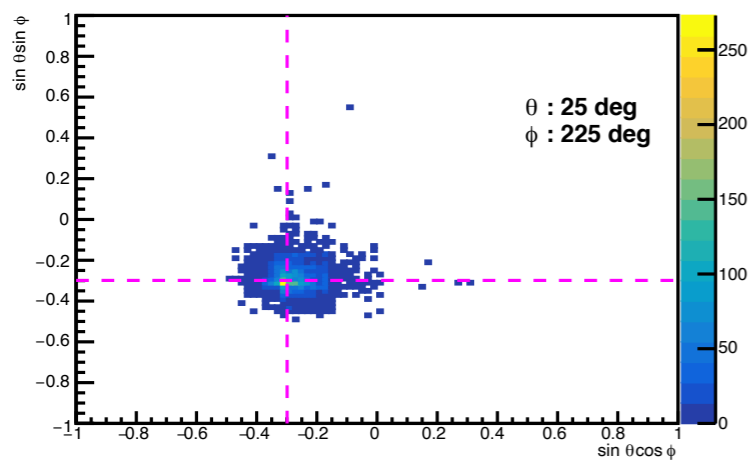
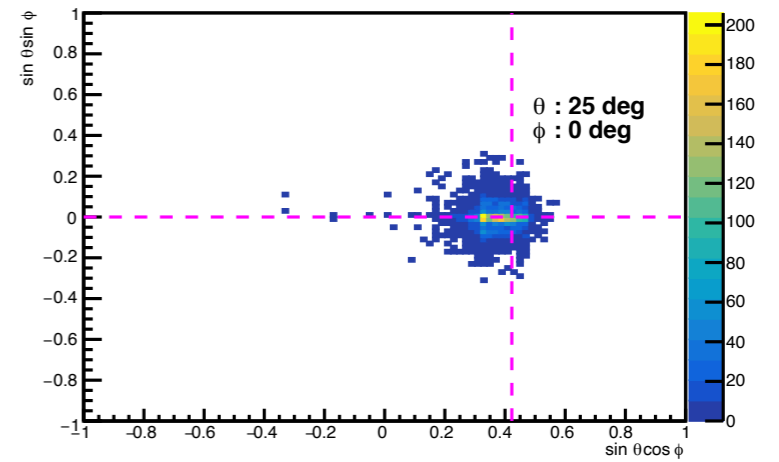
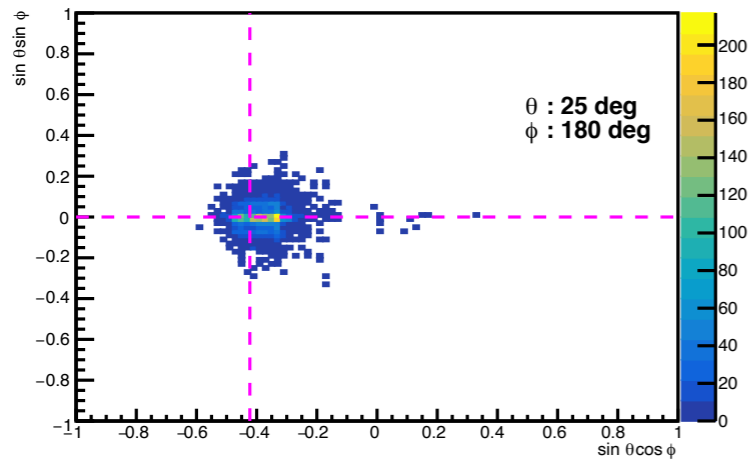
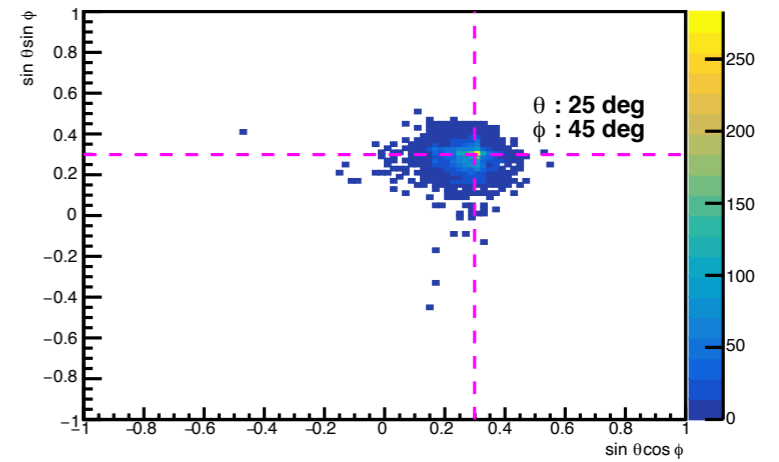
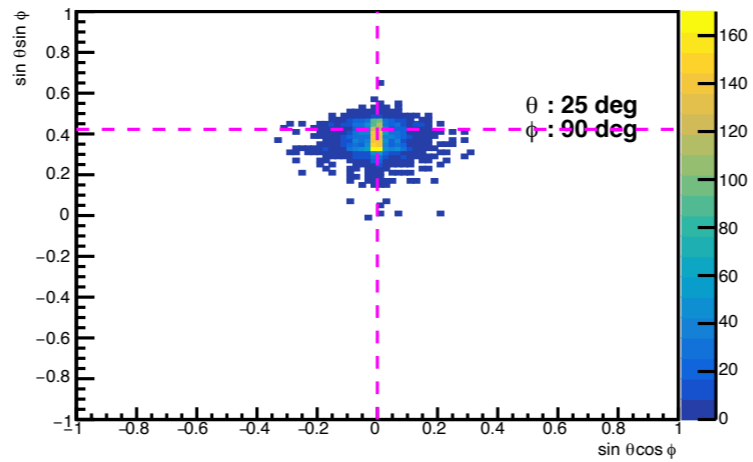
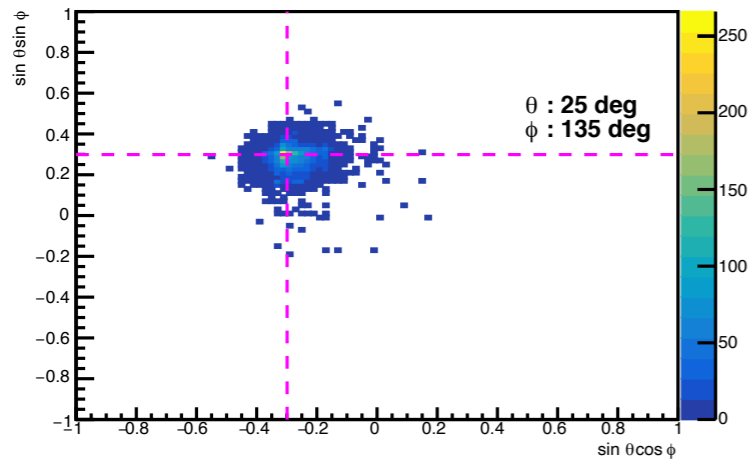
3x5 Clustering, 15 deg



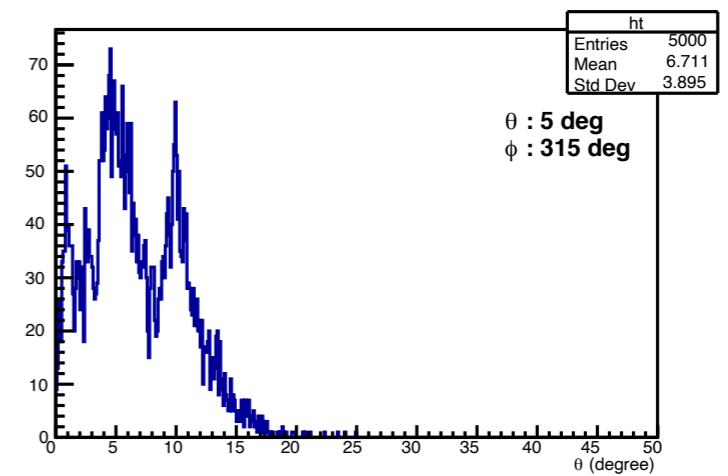
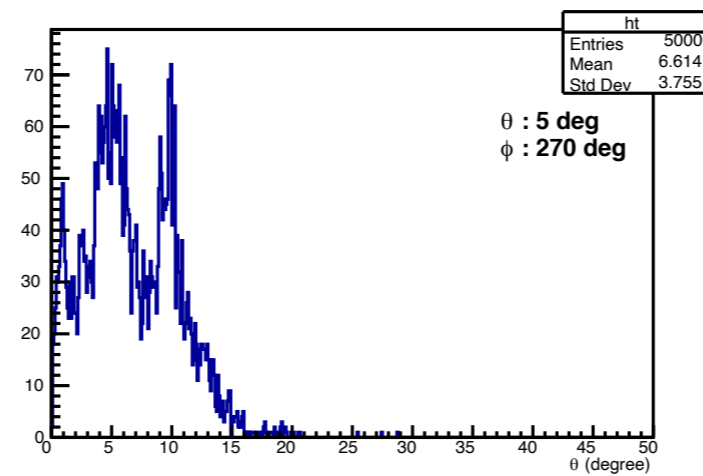
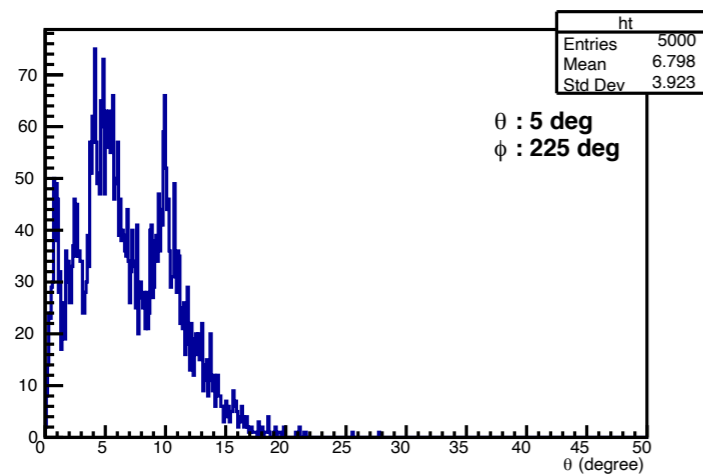
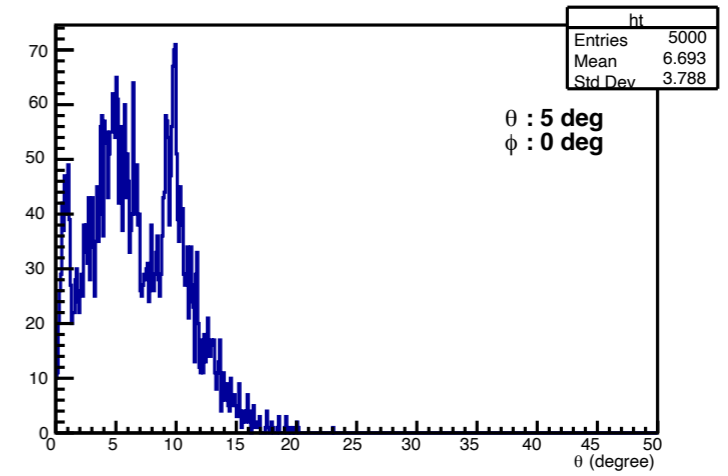
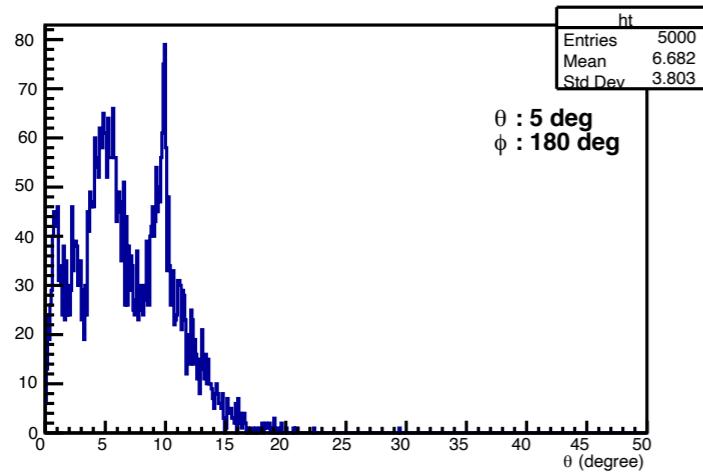
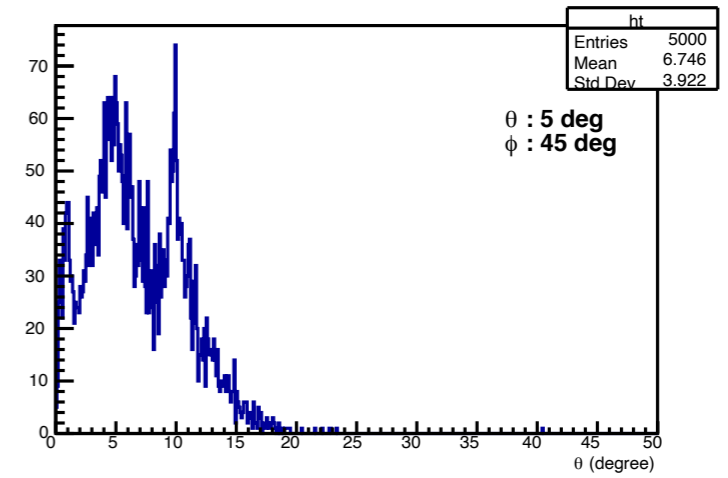
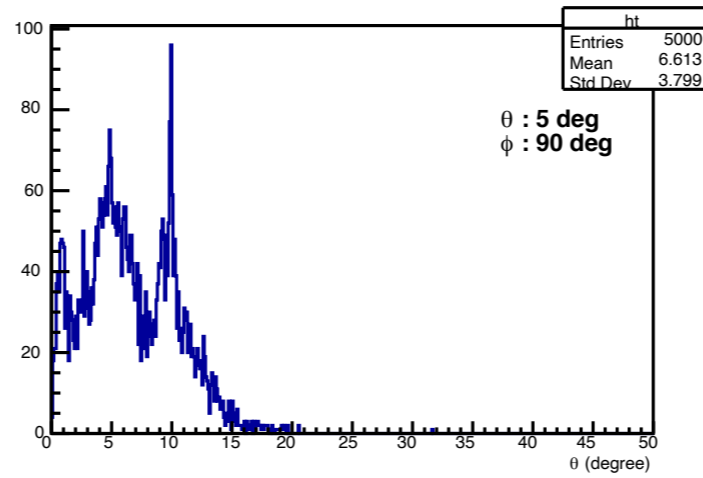
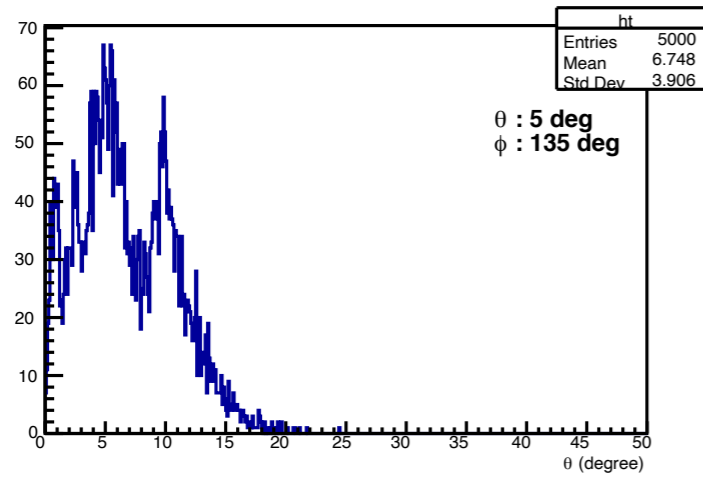
3x5 Clustering, 20 deg



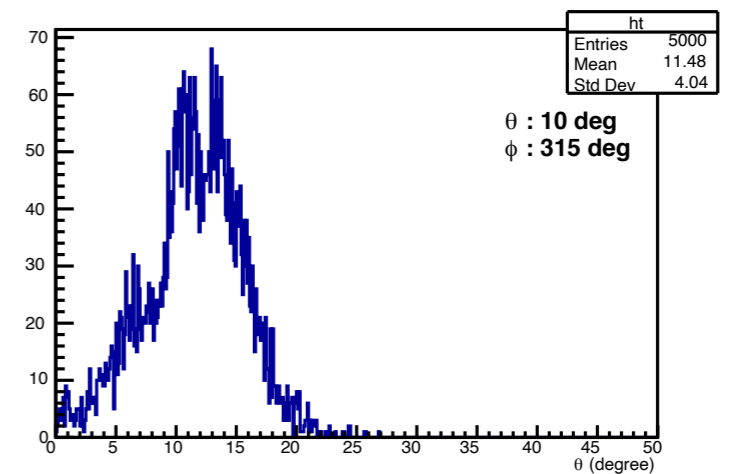
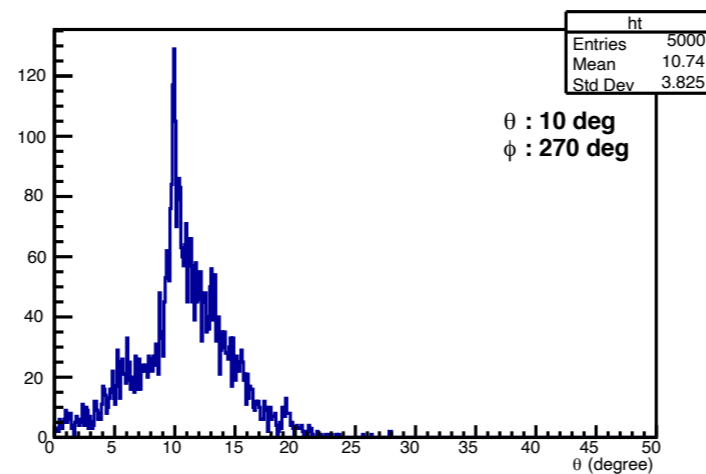
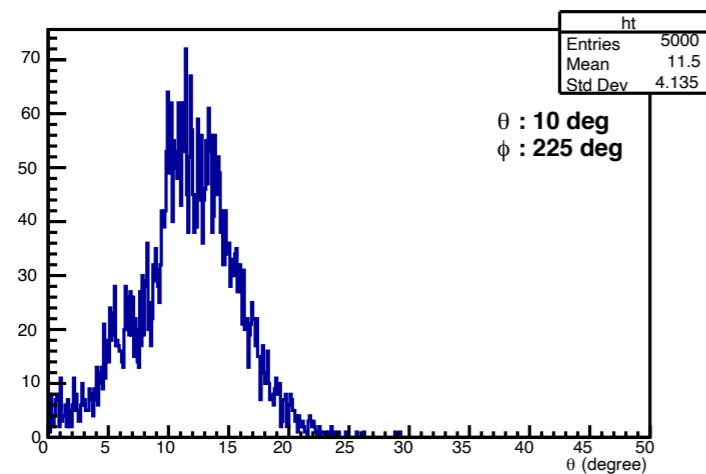
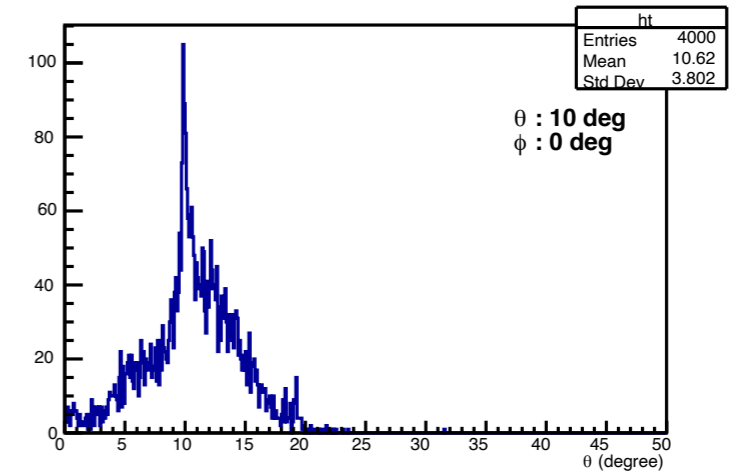
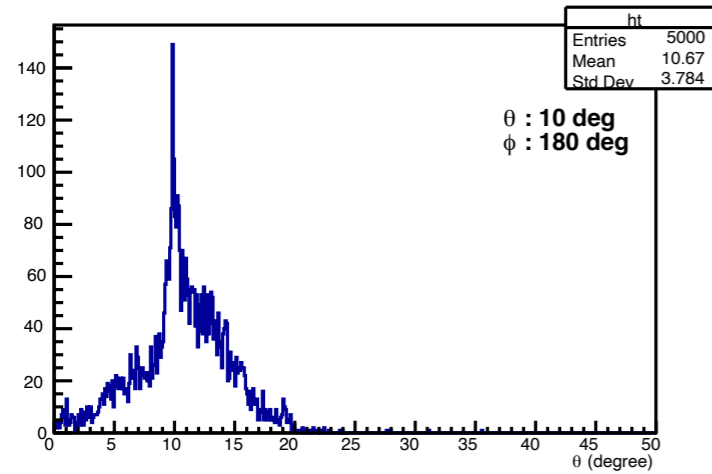
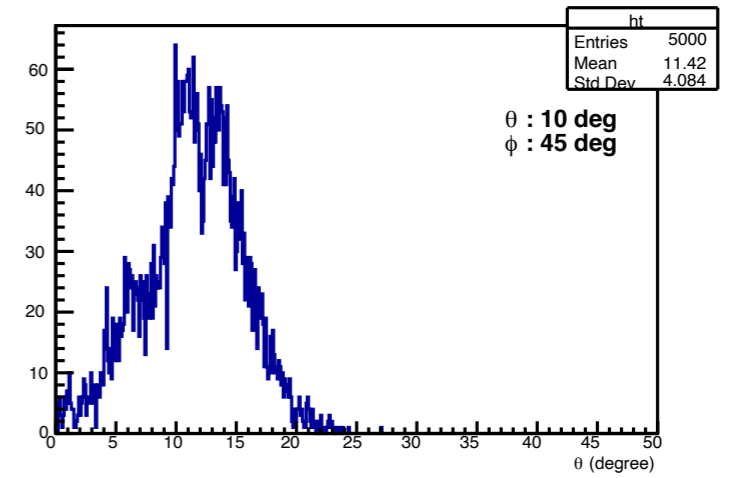
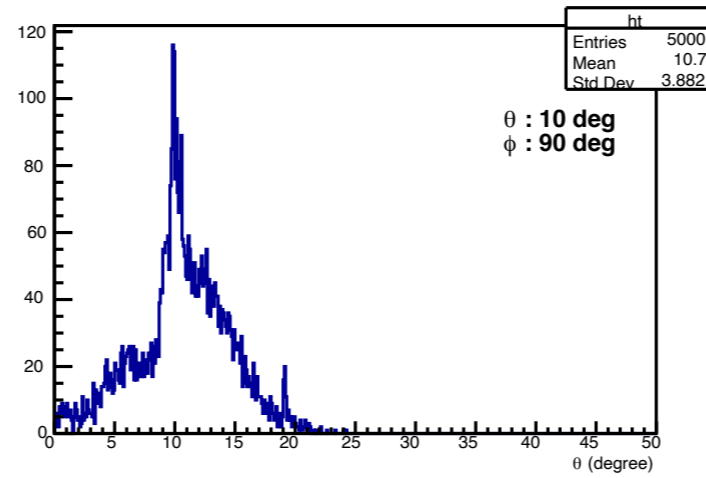
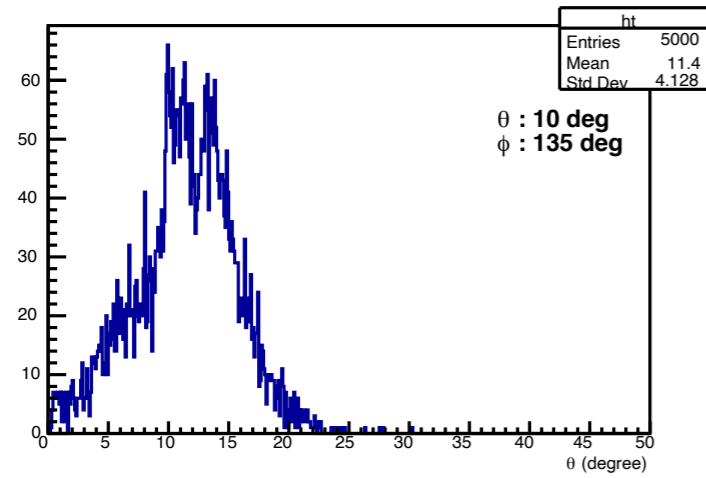
3x5 Clustering, 25 deg



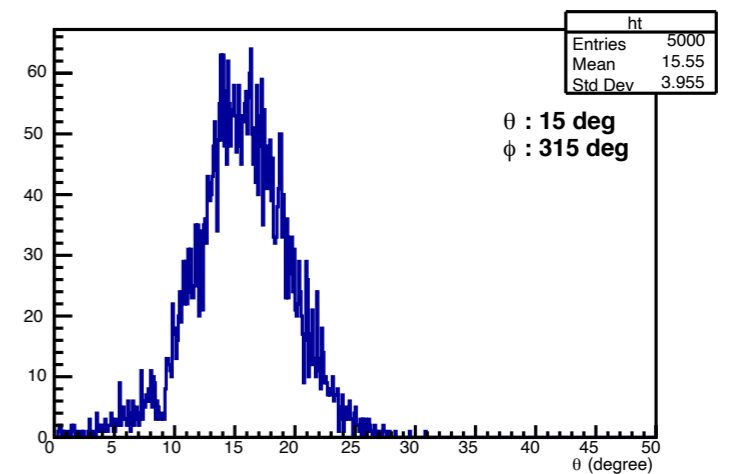
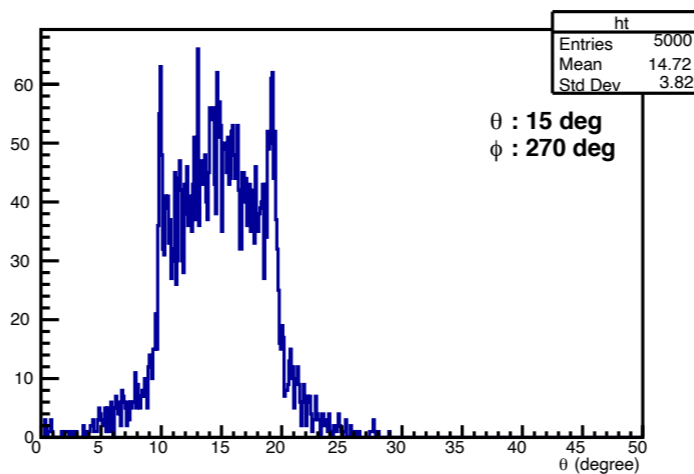
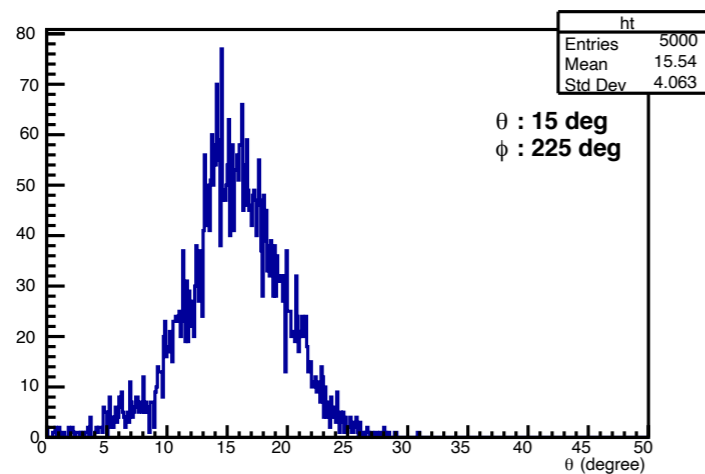
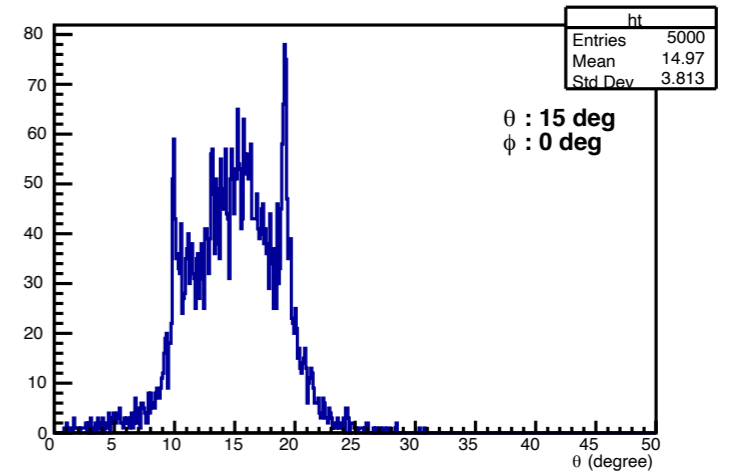
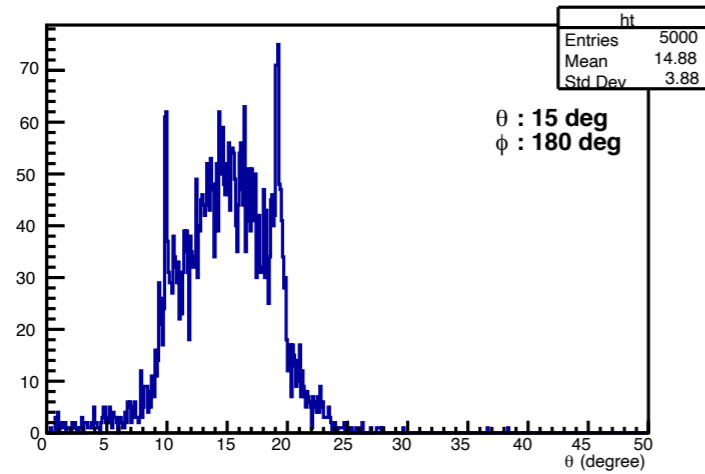
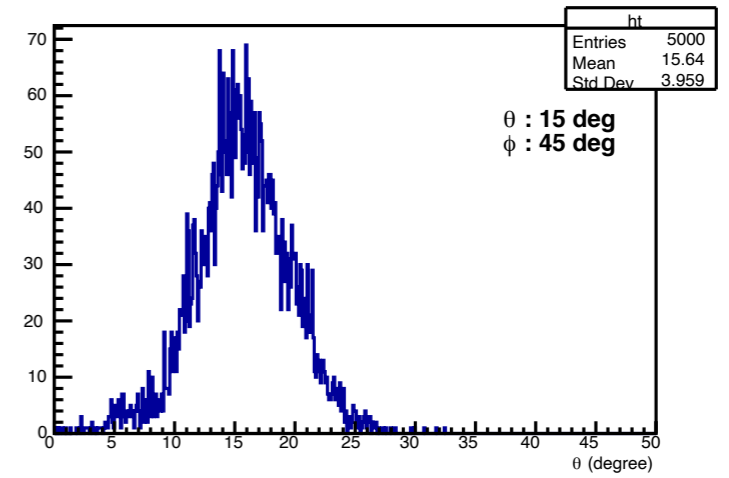
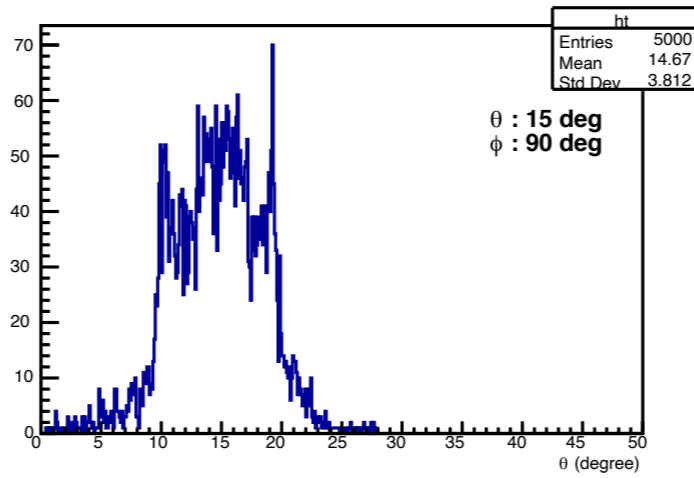
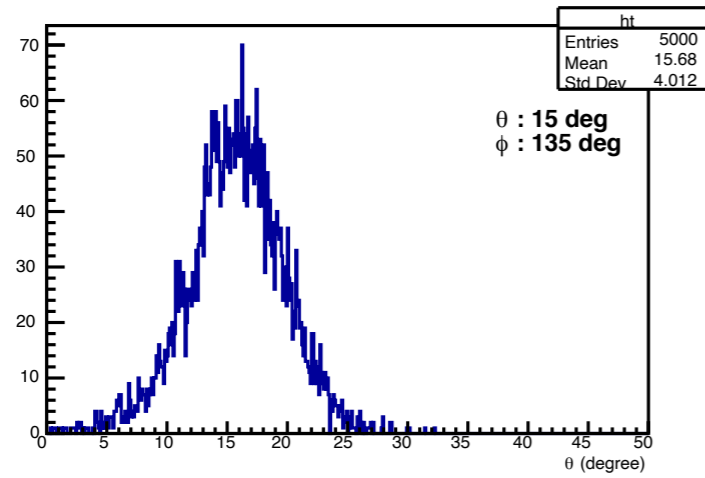
3x5 Clustering, 5 deg



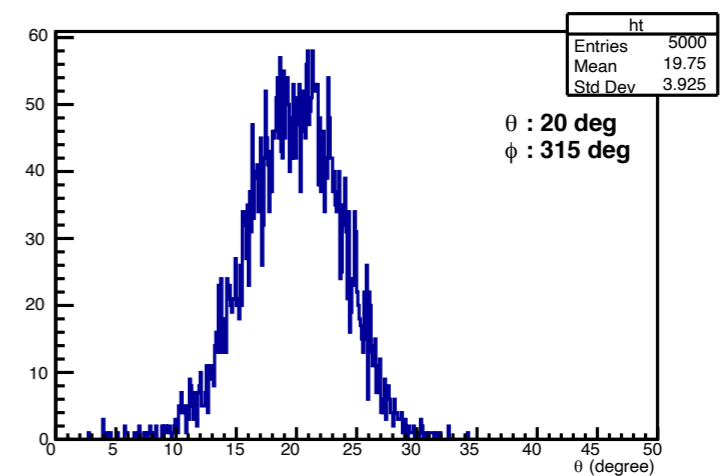
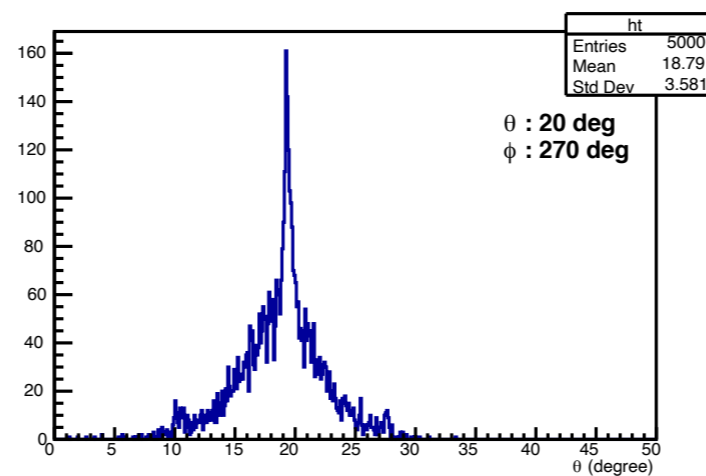
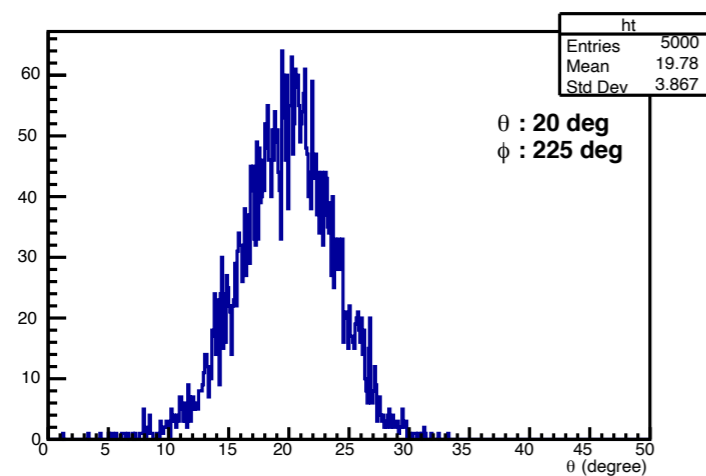
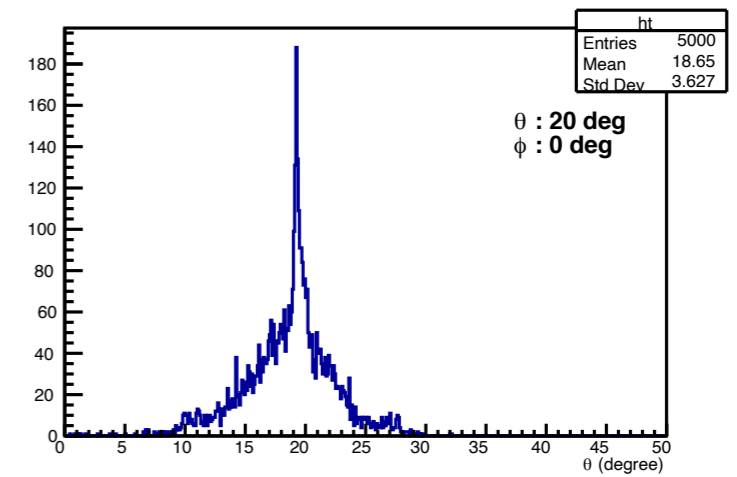
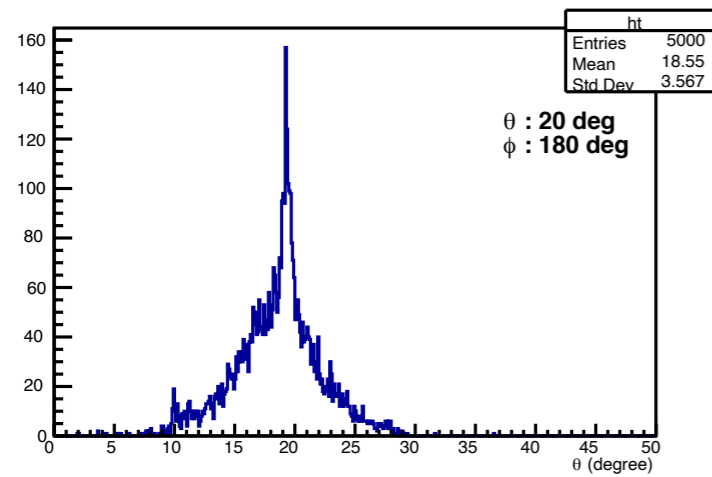
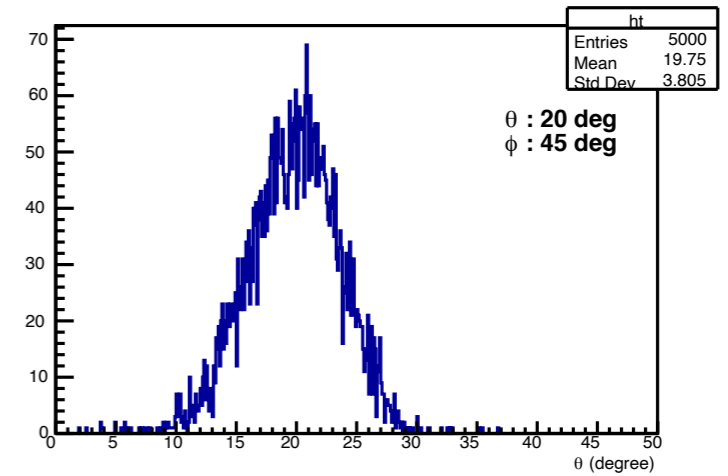
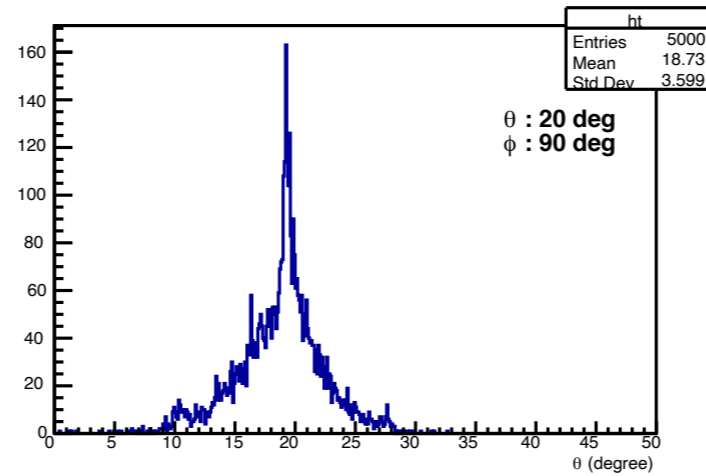
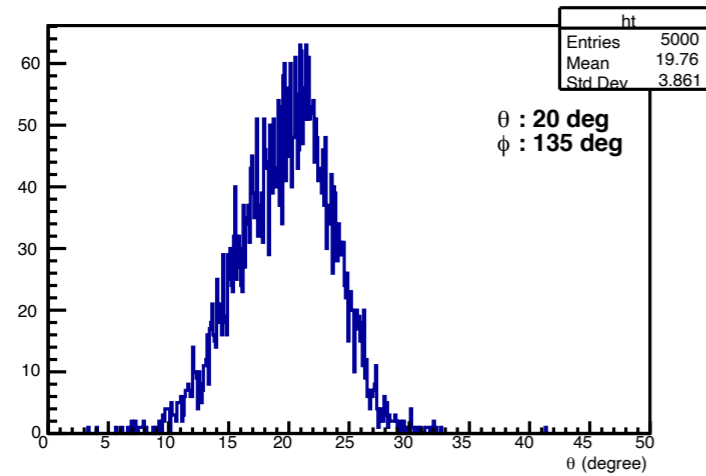
3x5 Clustering, 10 deg



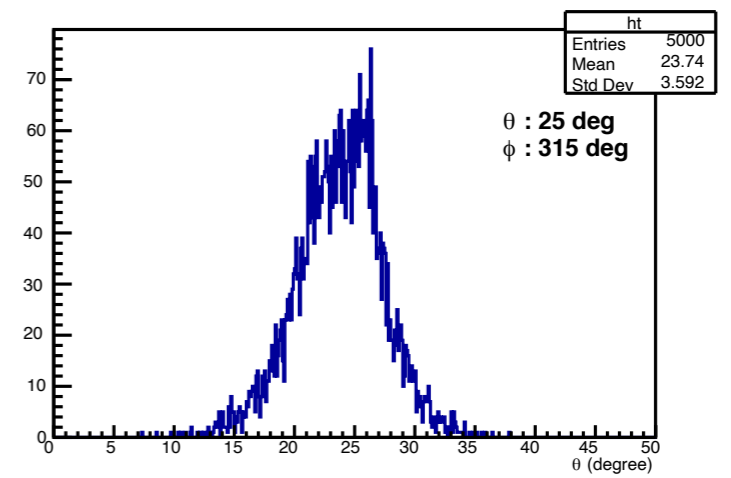
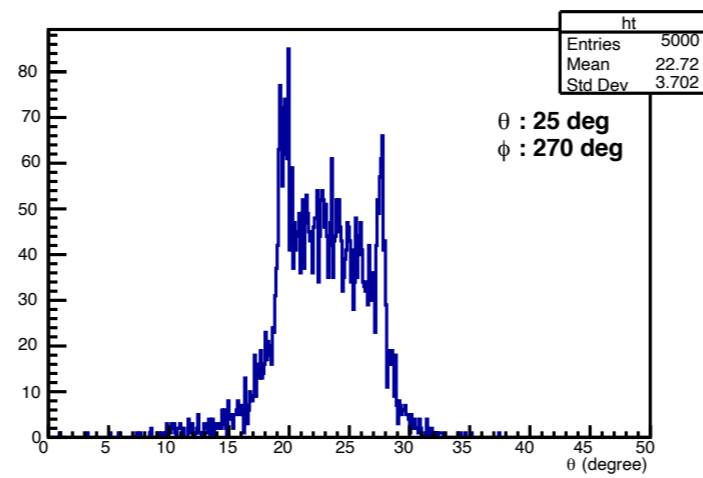
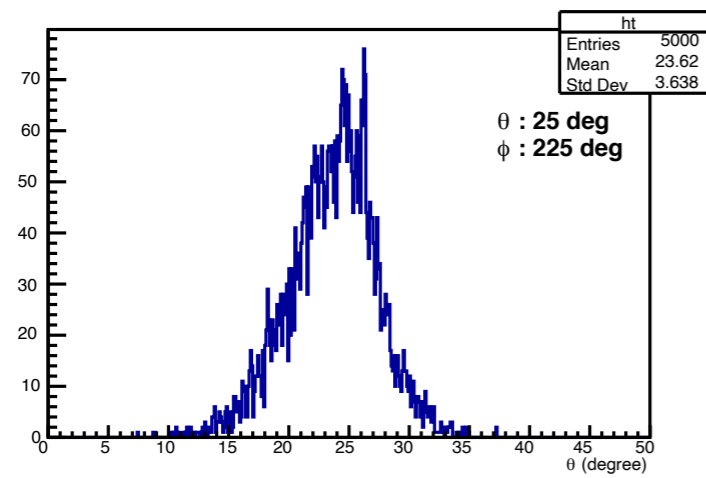
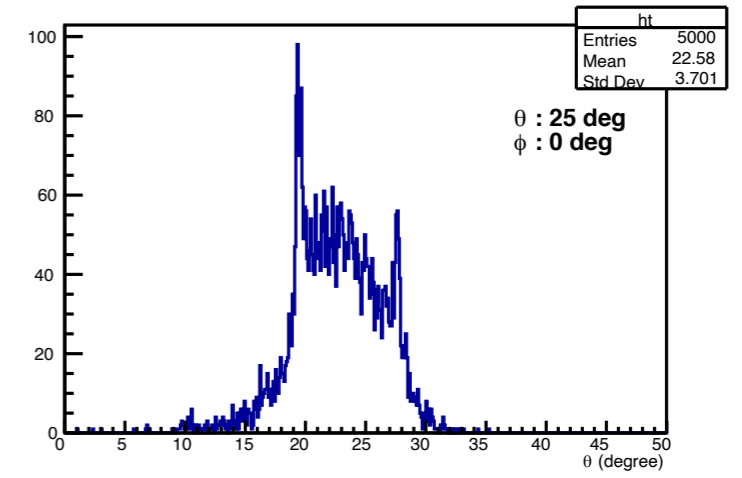
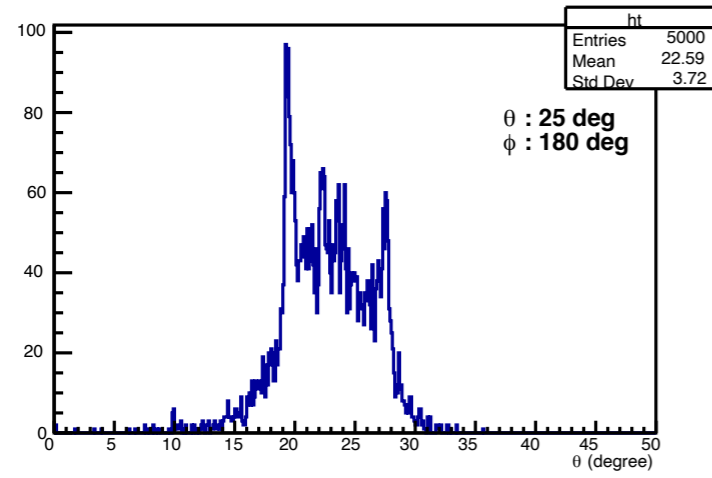
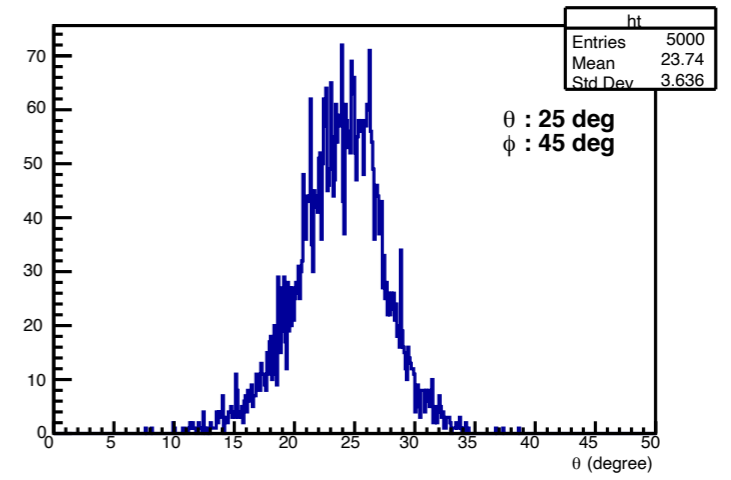
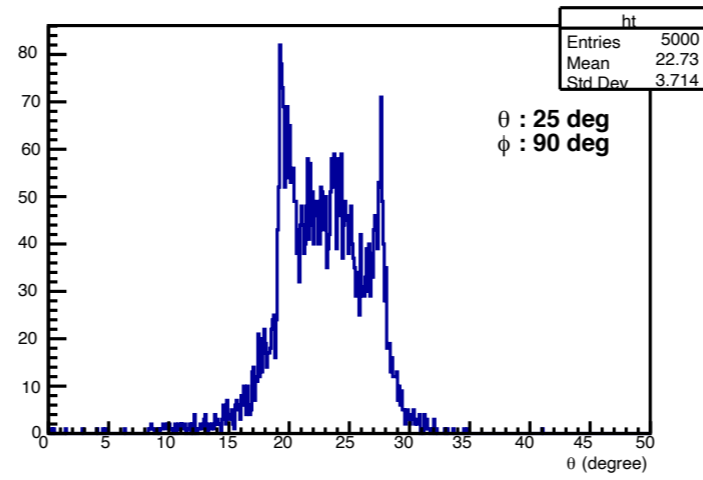
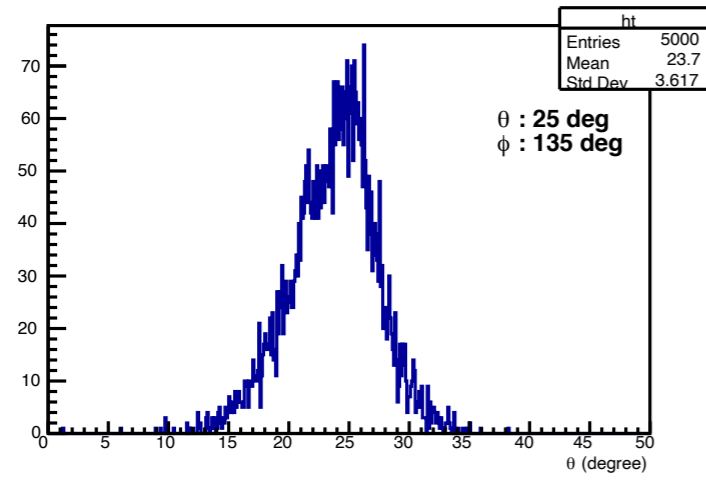
3x5 Clustering, 15 deg



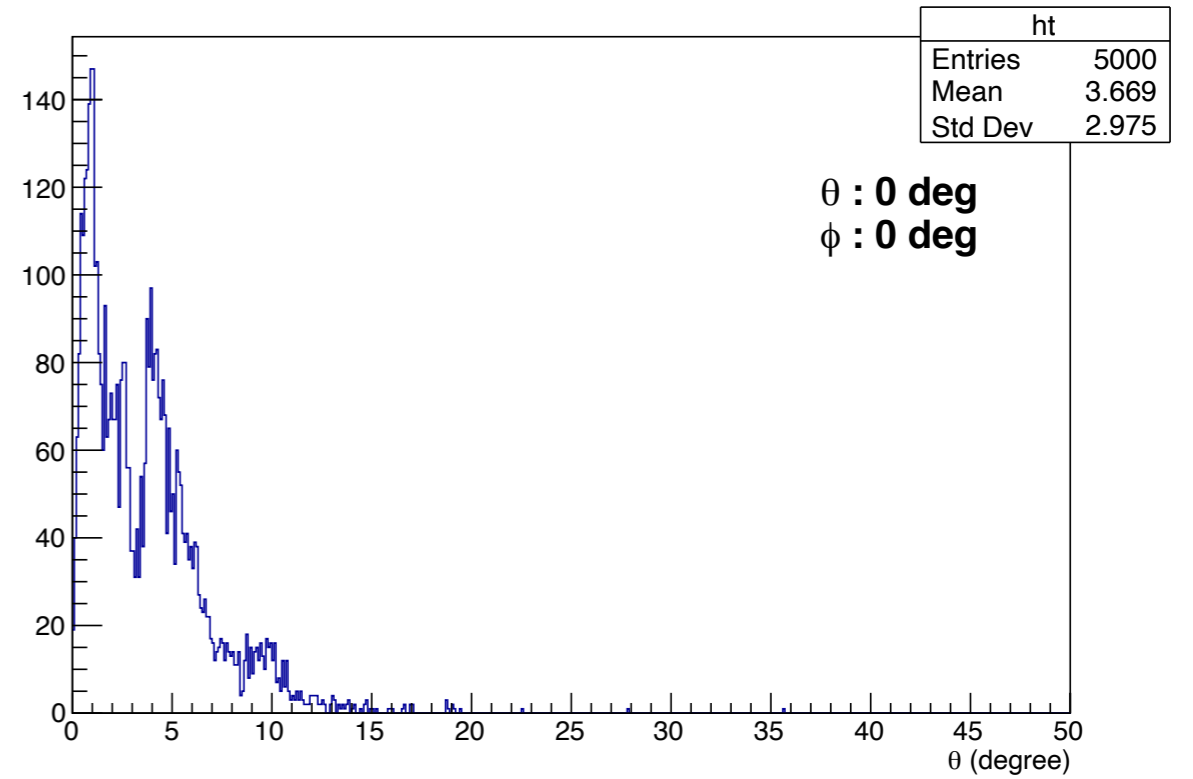
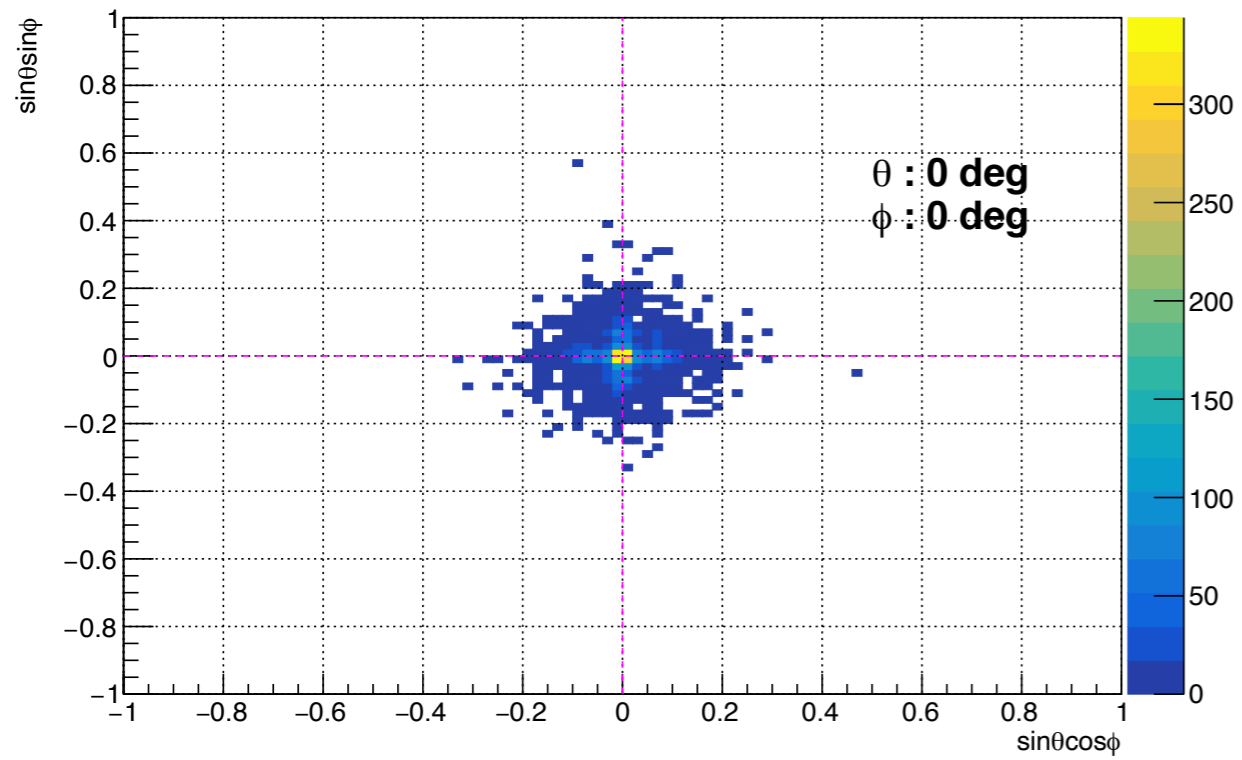
3x5 Clustering, 20 deg



3x5 Clustering, 25 deg



3x5 Clustering, 0 deg

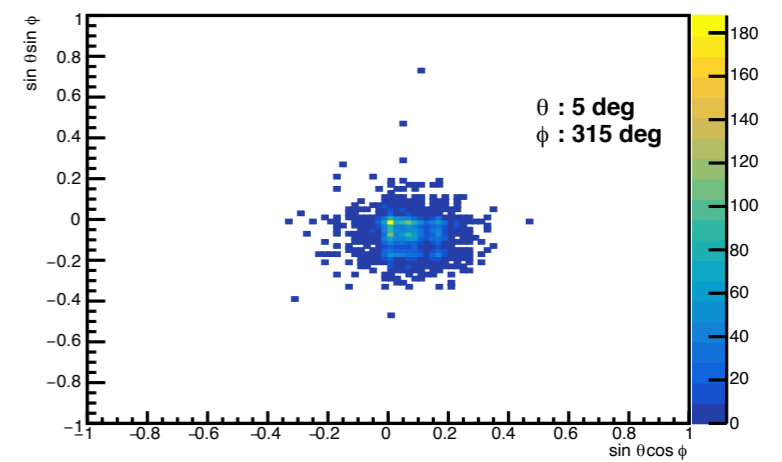
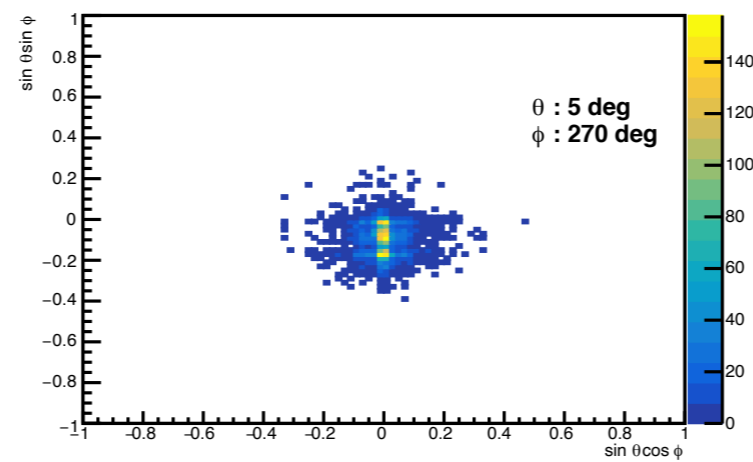
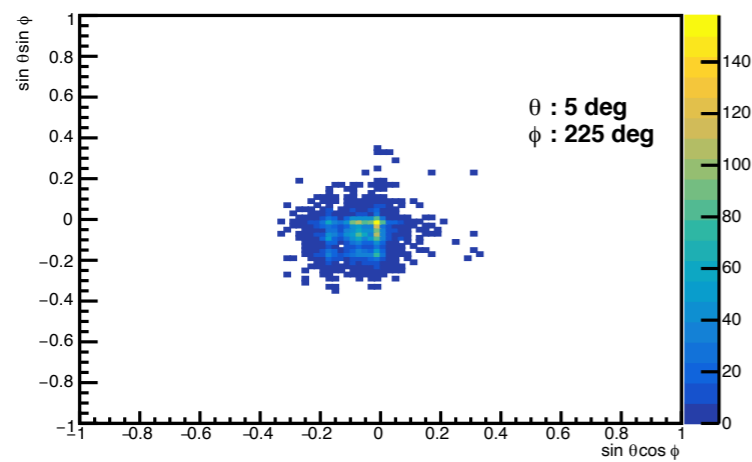
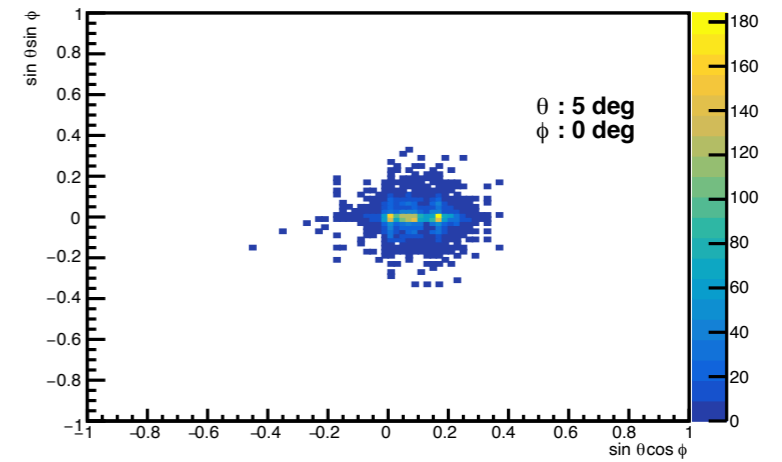
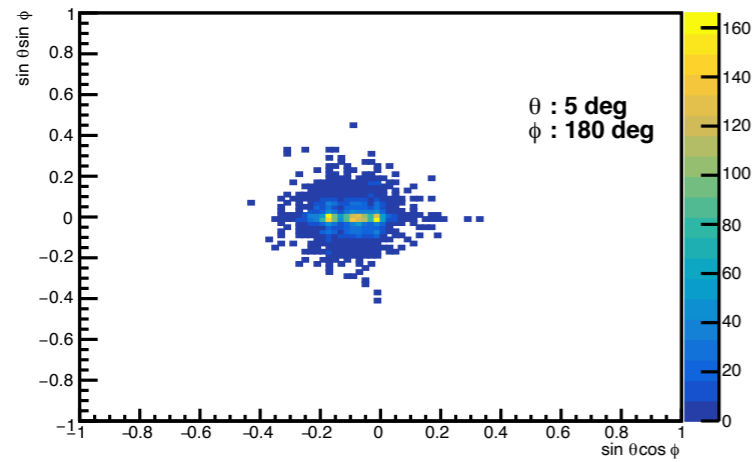
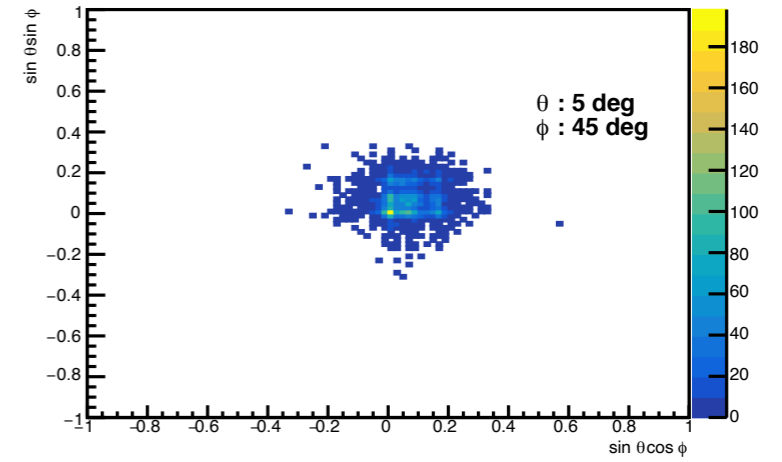
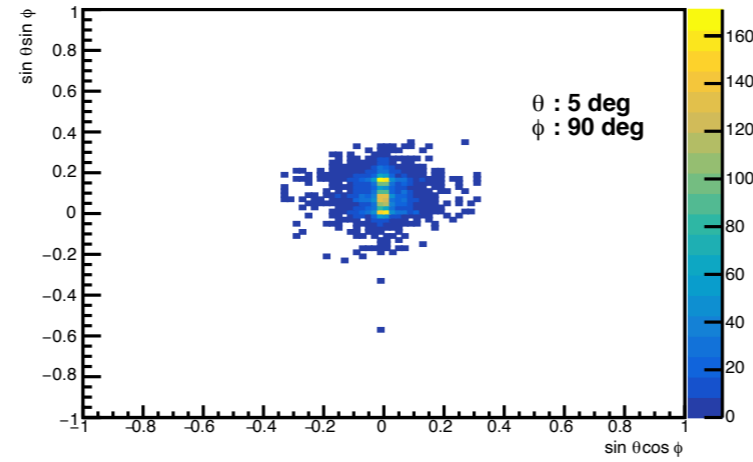
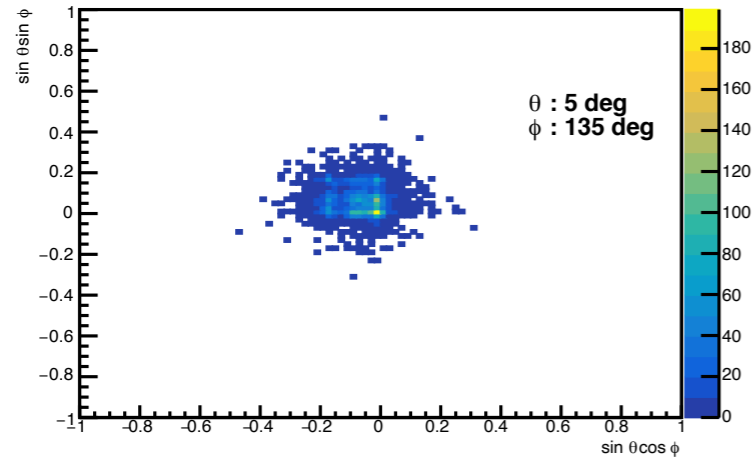


3x5 Clustering Angle estimation

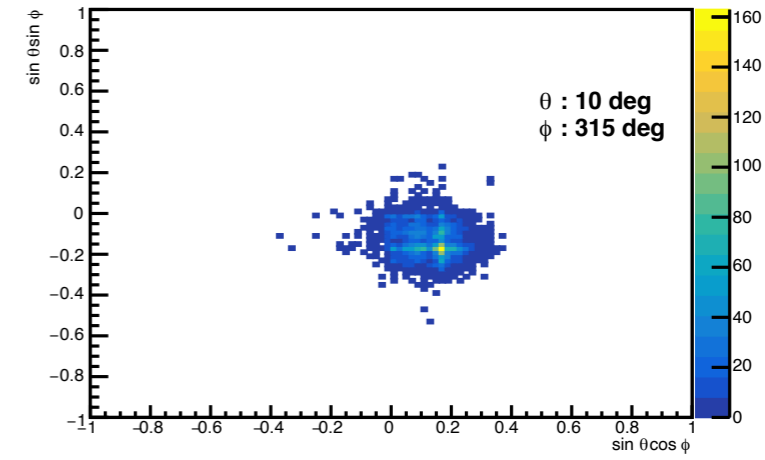
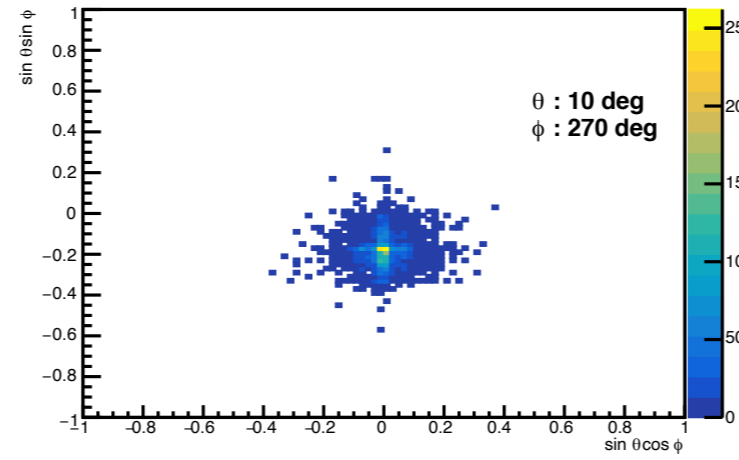
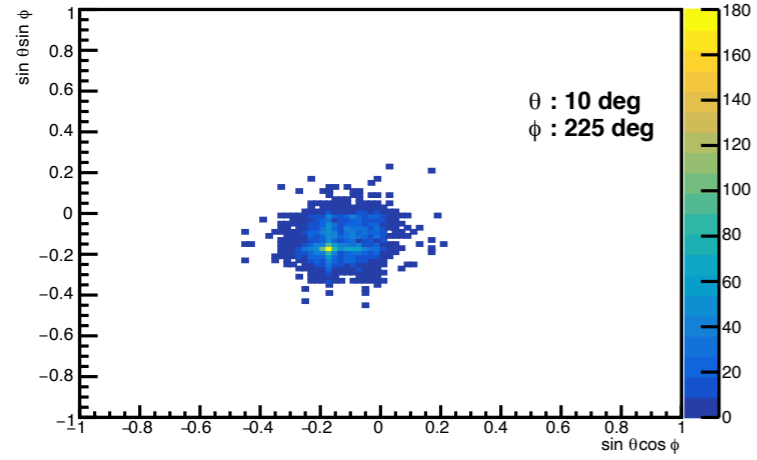
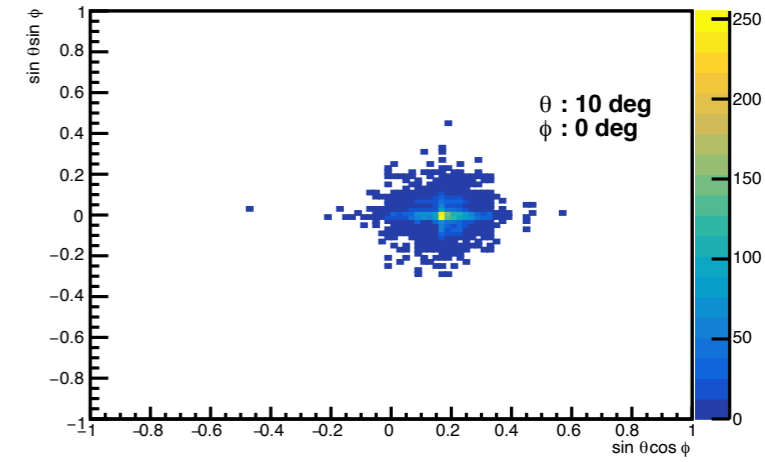
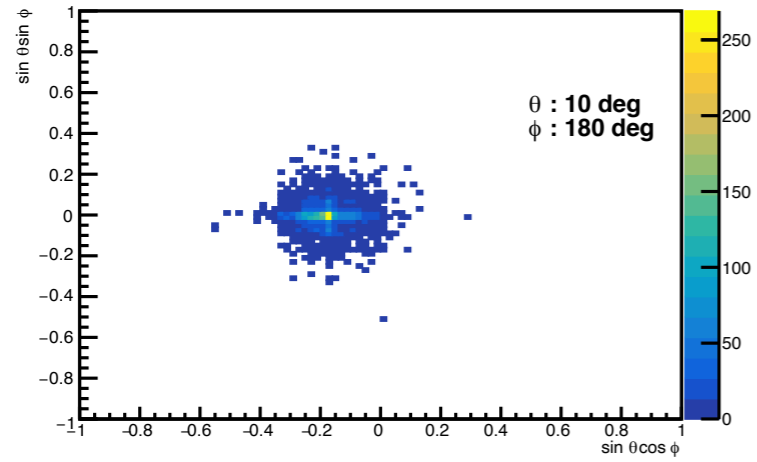
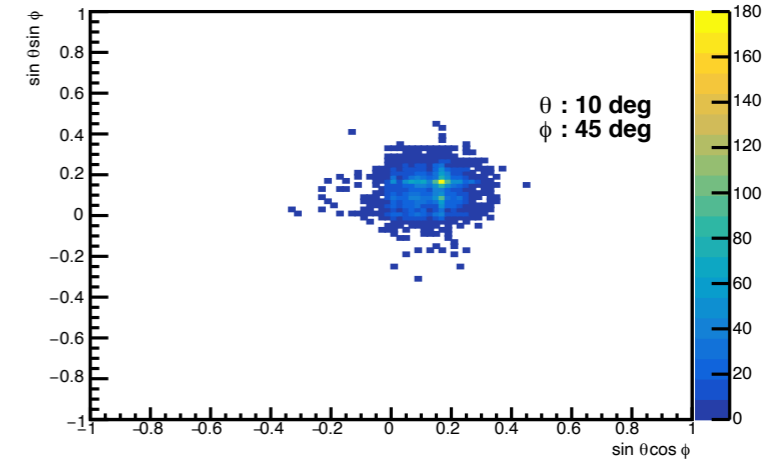
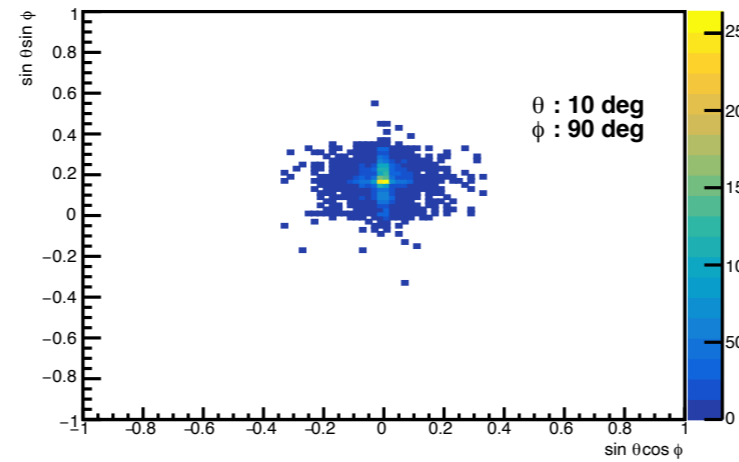
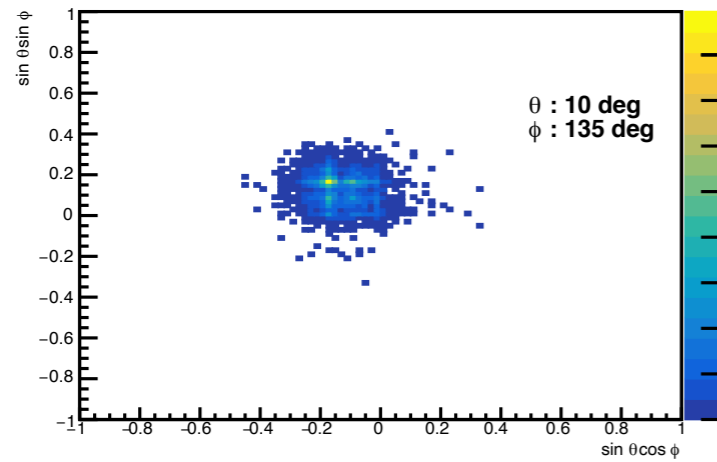
- 3.5~4 degree angular resolution (Std. Dev.)
- When we know exact starting point (~2 deg resolution)
- Next : Two gamma (π^0 reconstruction) ??

back up

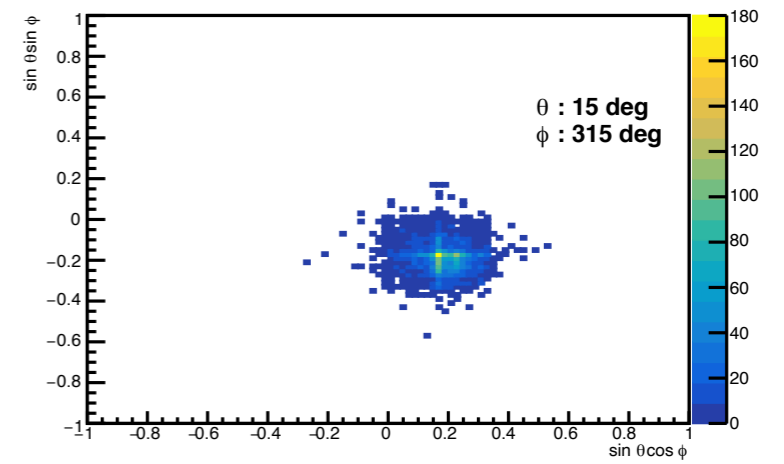
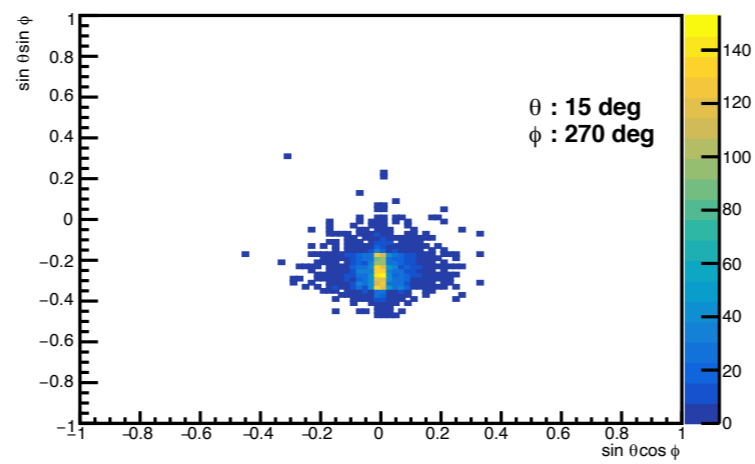
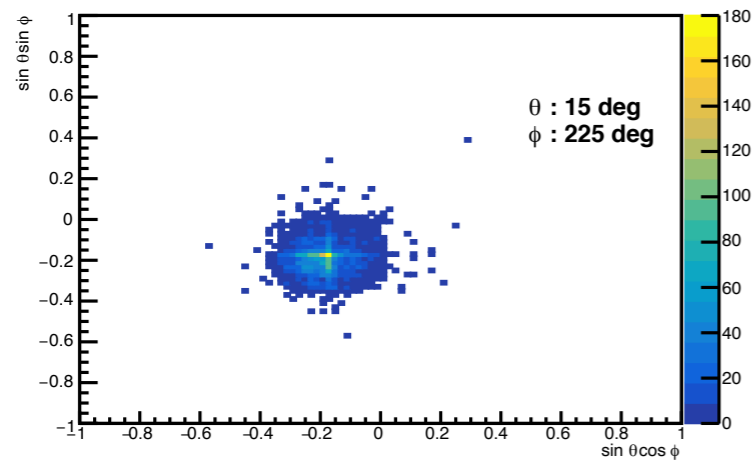
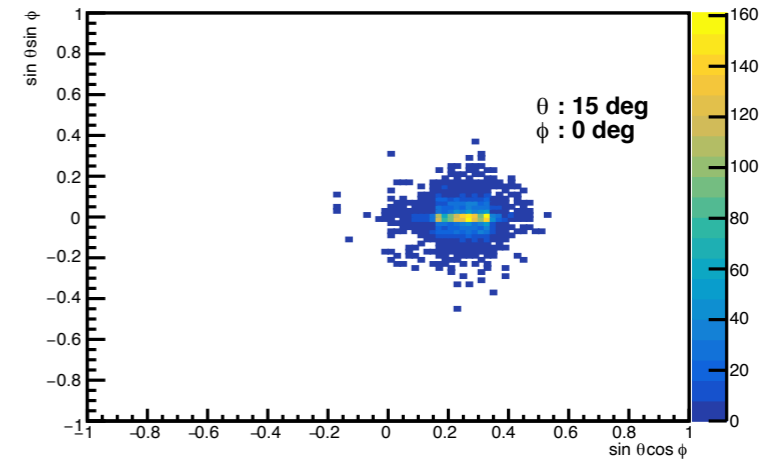
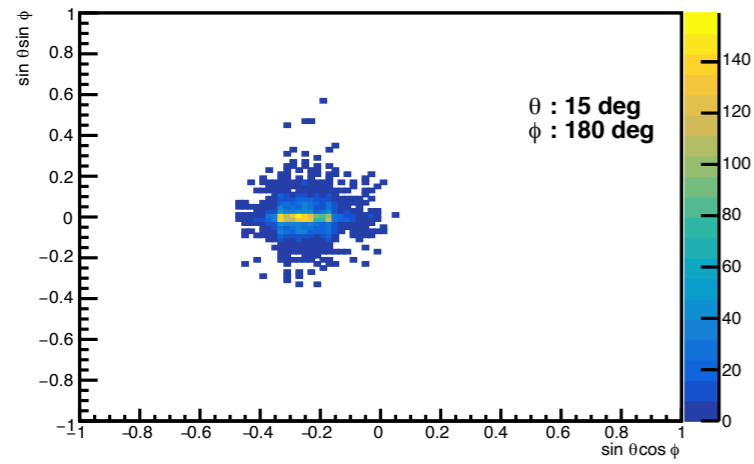
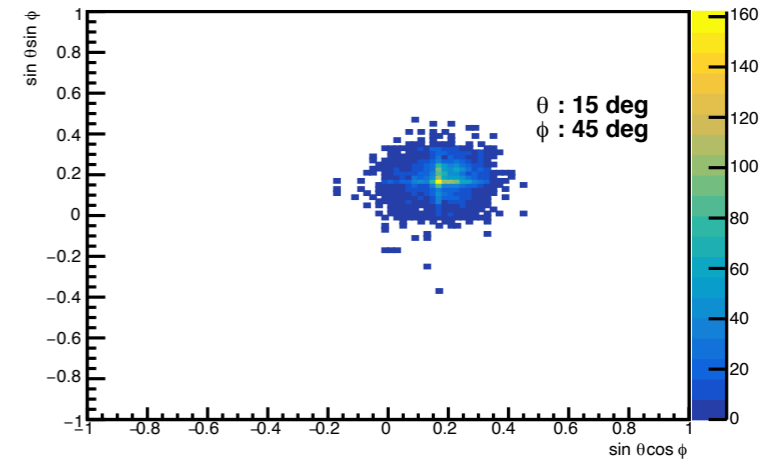
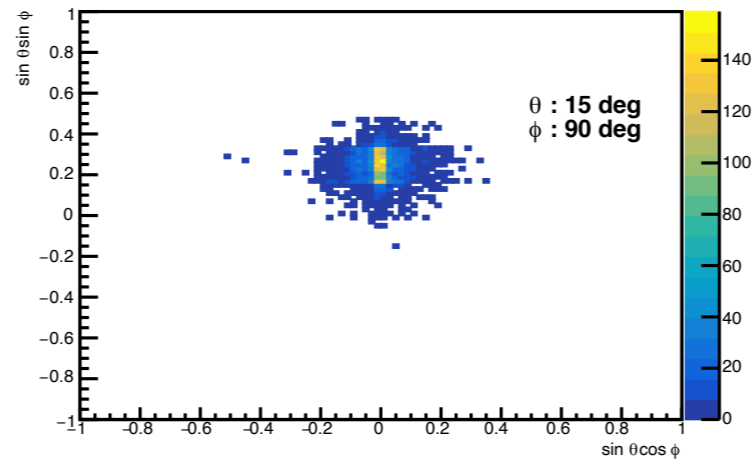
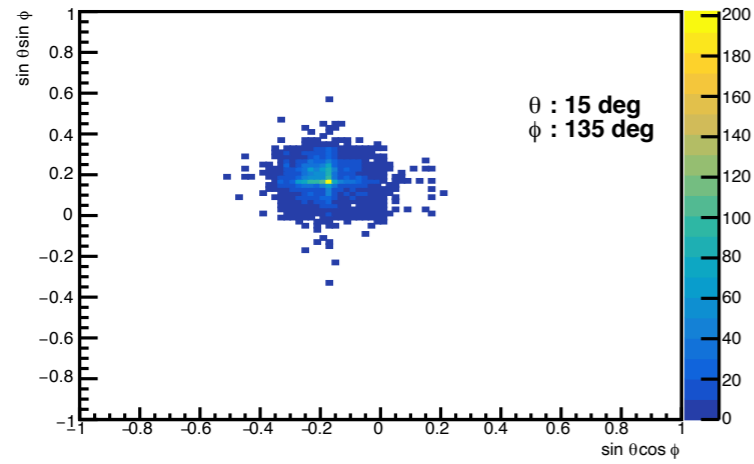
3x3 Clustering, 5 deg



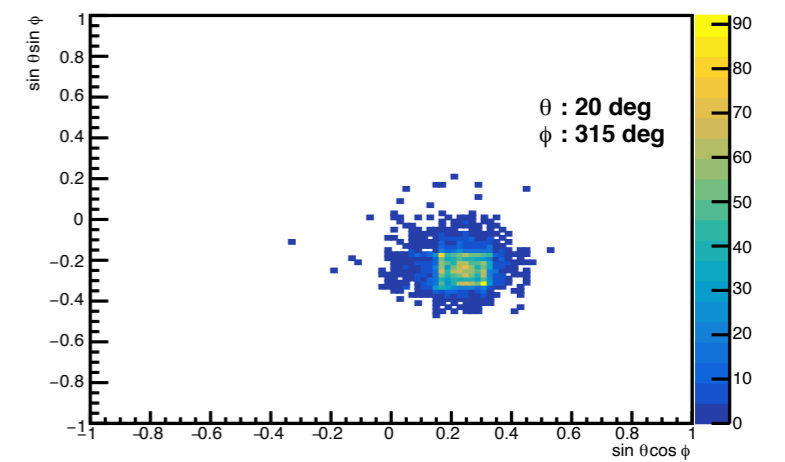
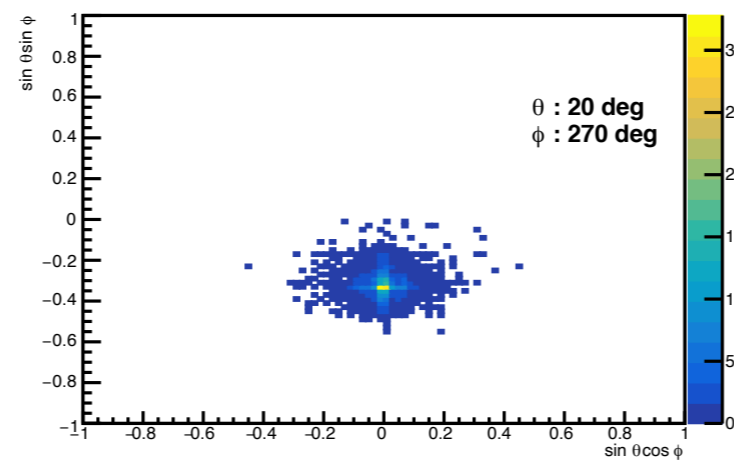
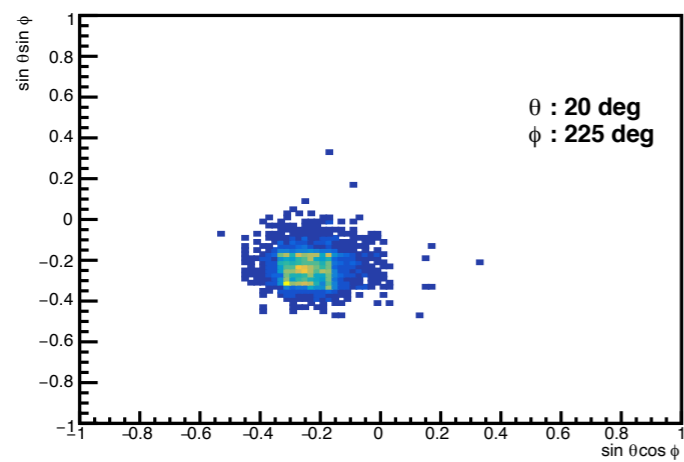
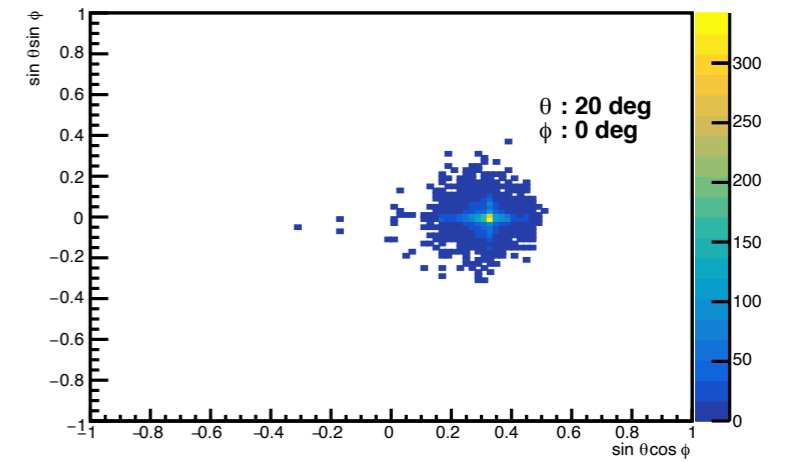
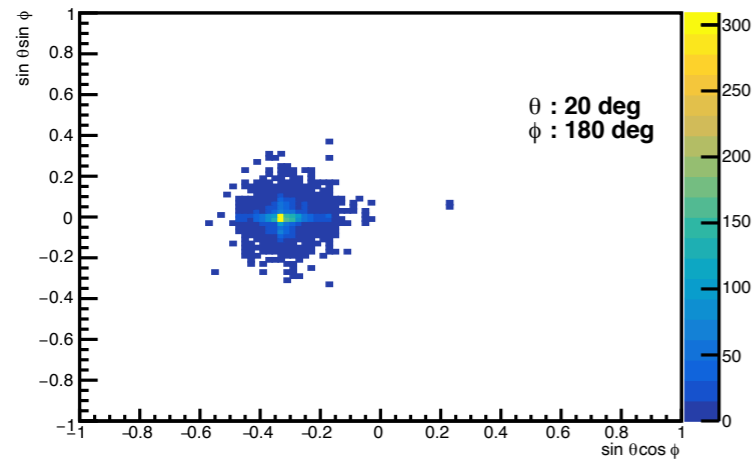
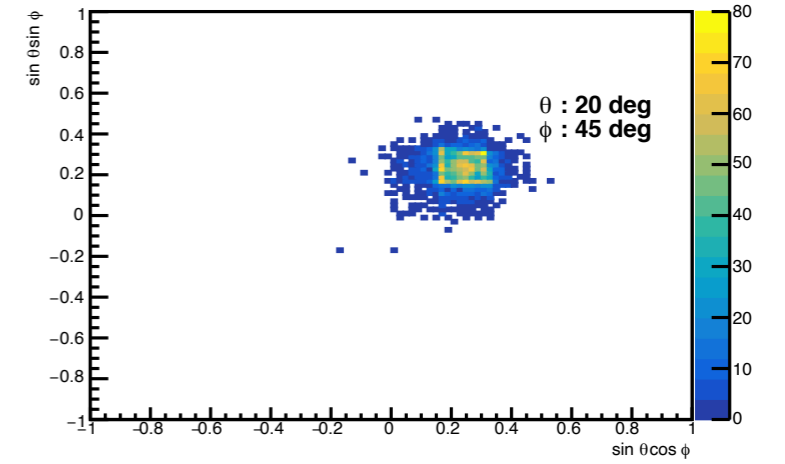
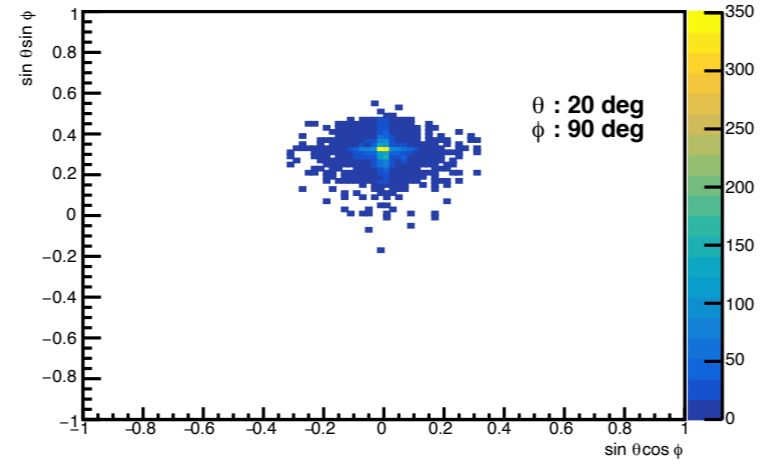
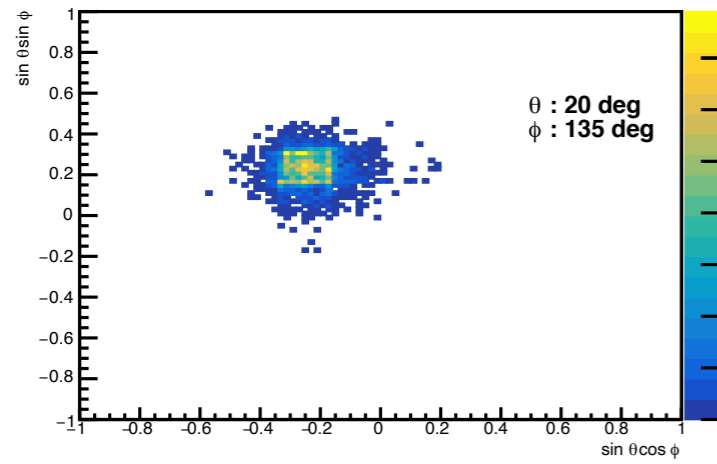
3x3 Clustering, 10 deg



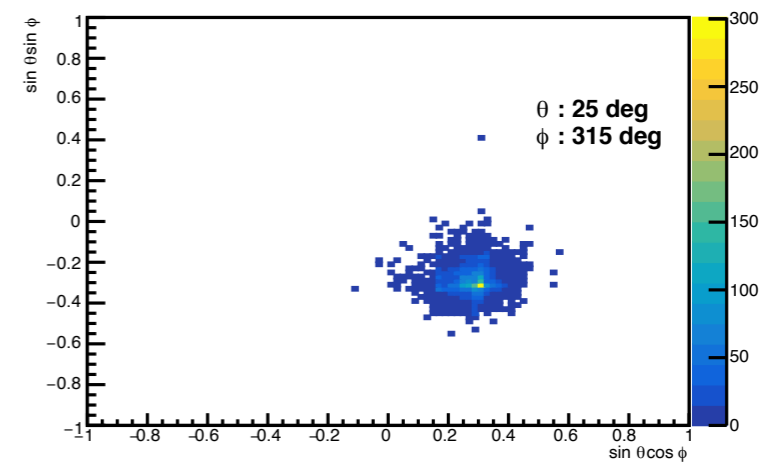
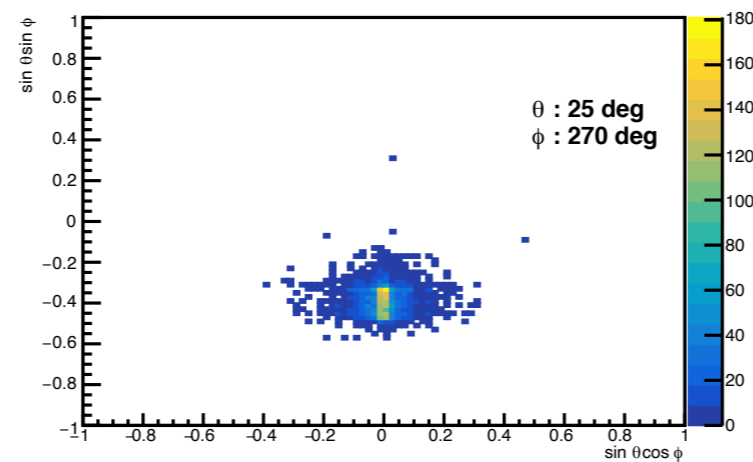
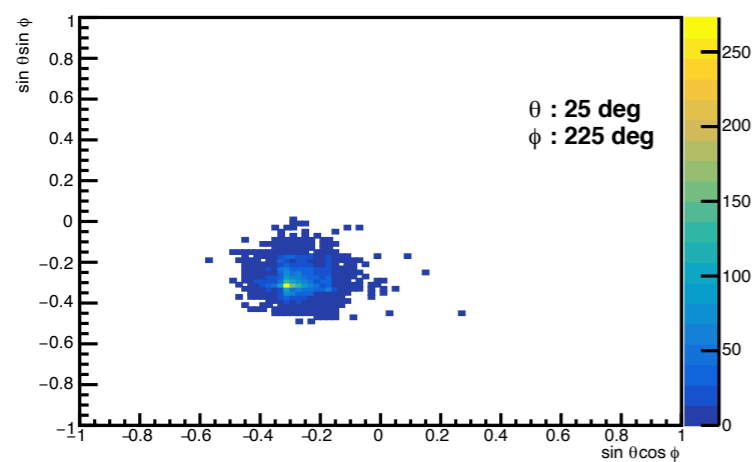
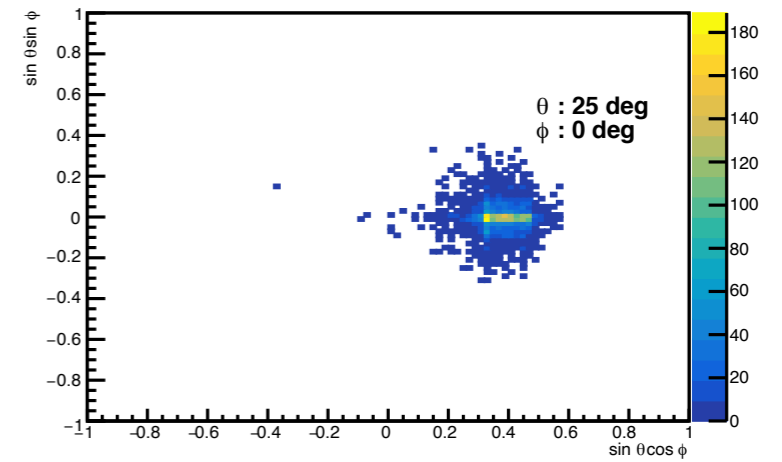
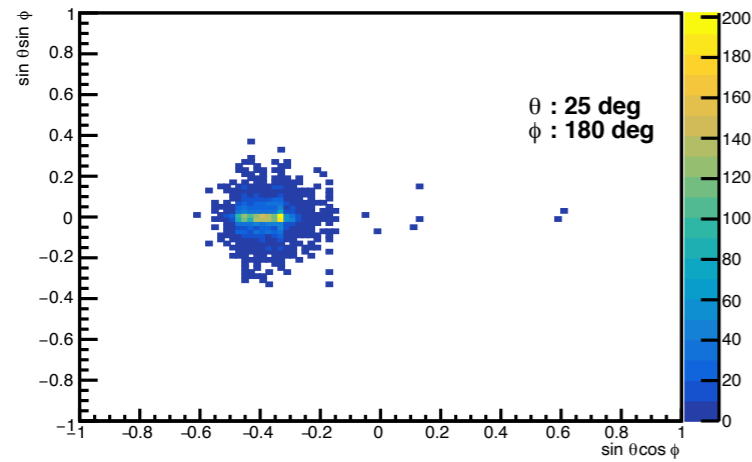
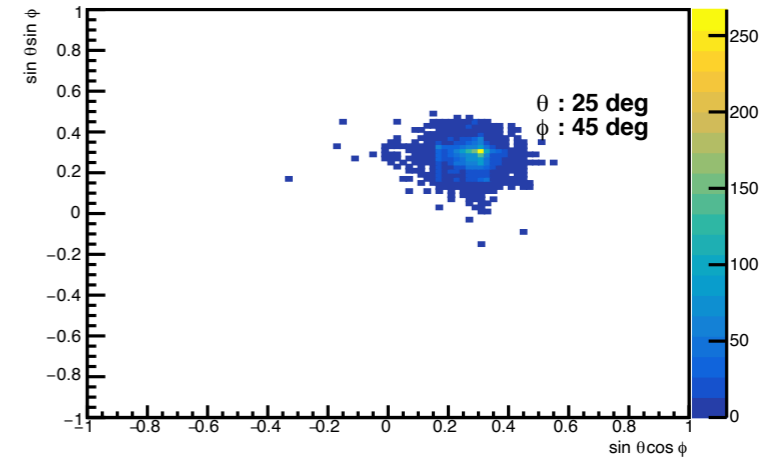
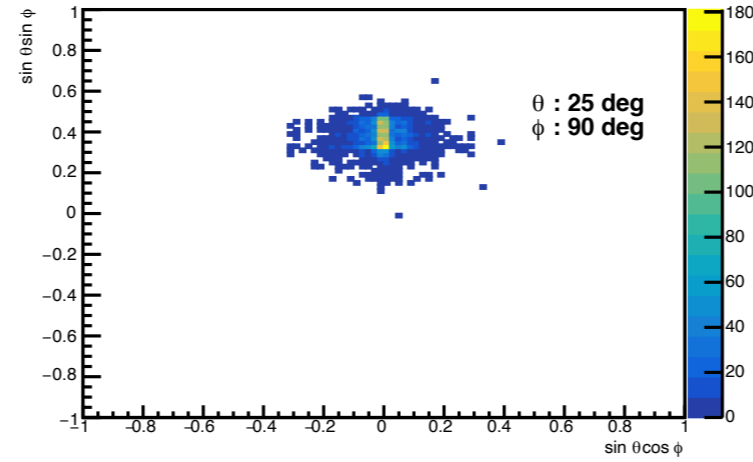
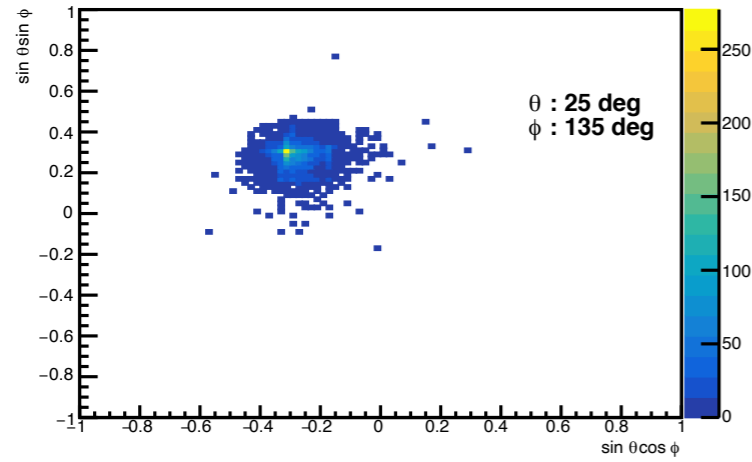
3x3 Clustering, 15 deg



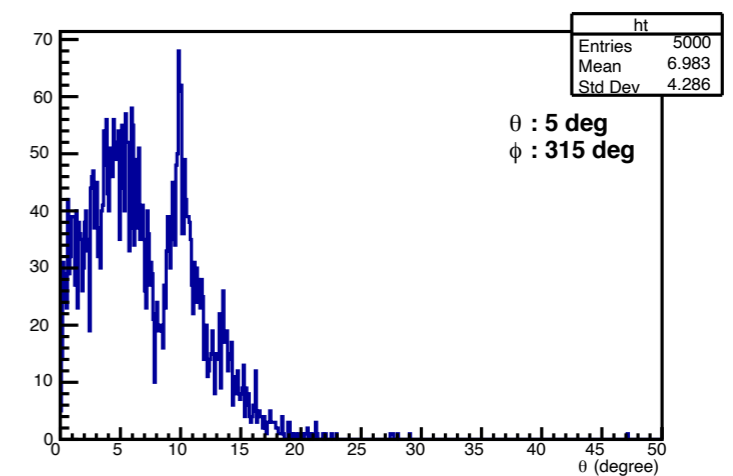
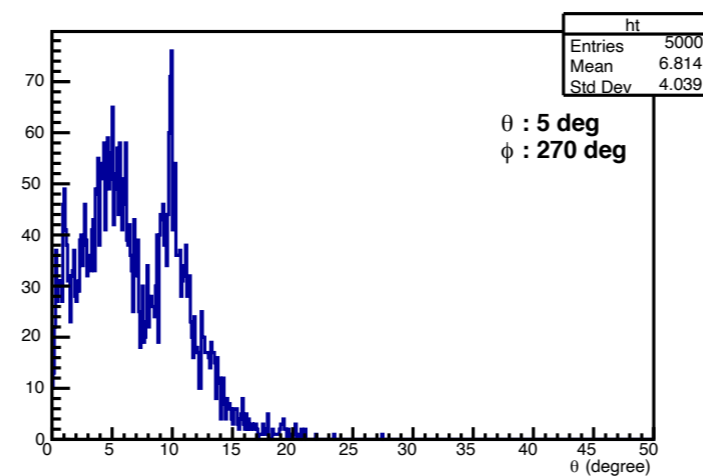
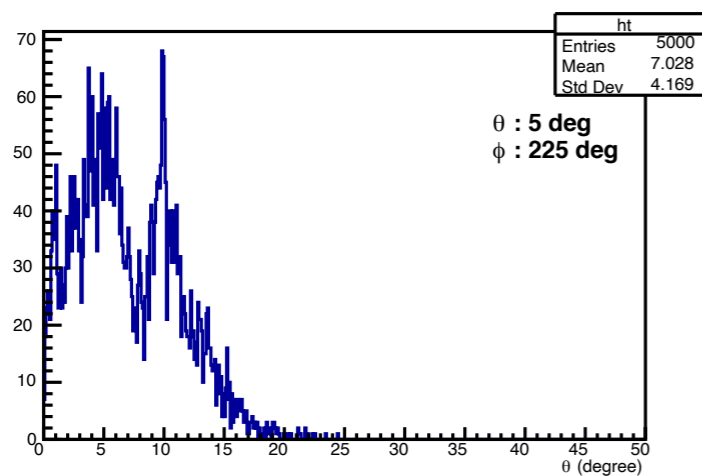
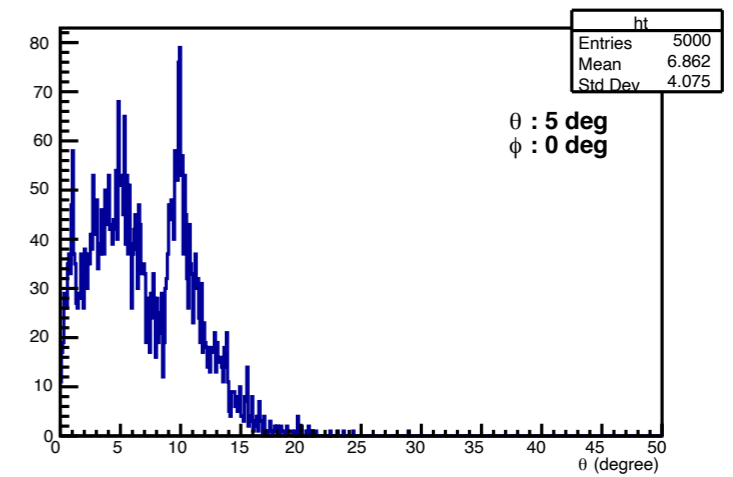
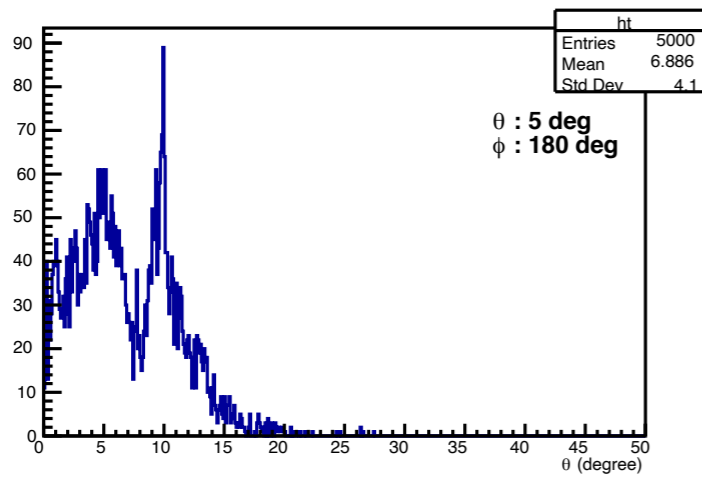
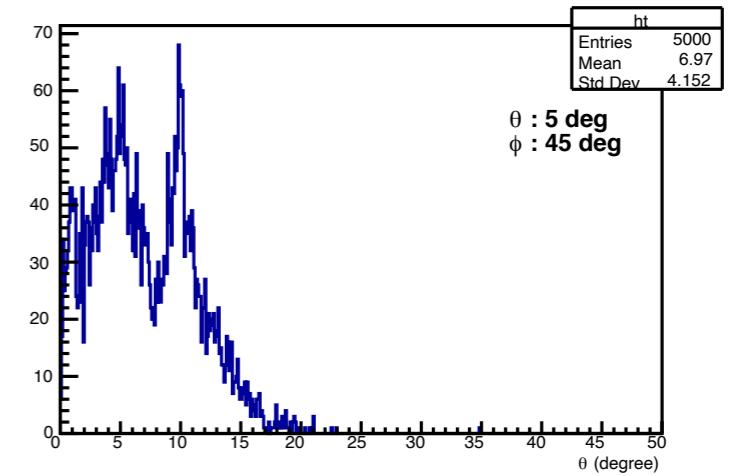
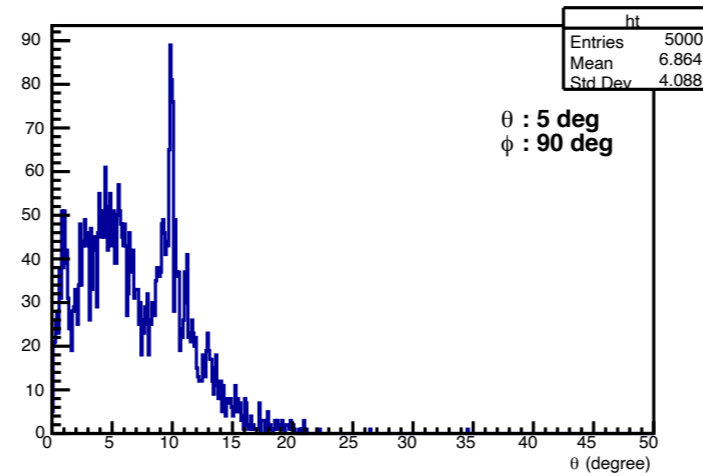
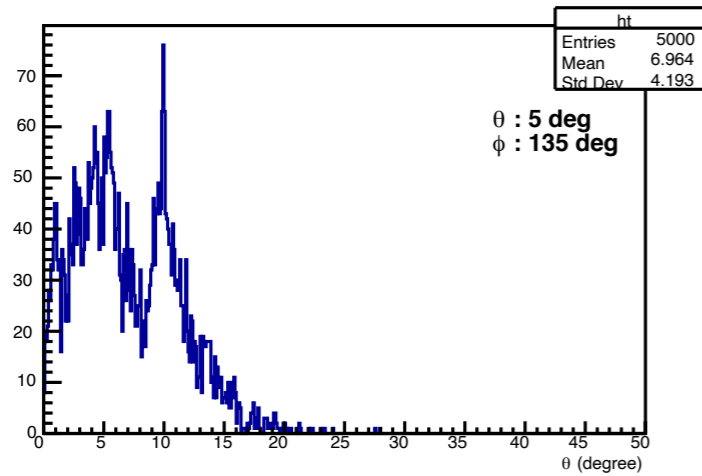
3x3 Clustering, 20 deg



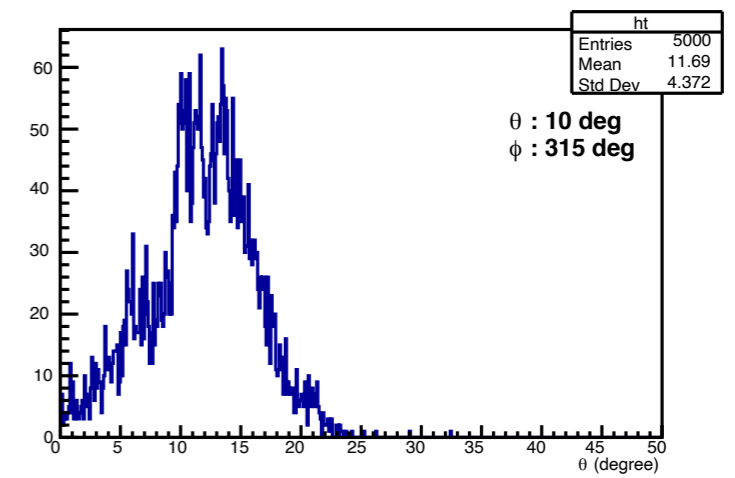
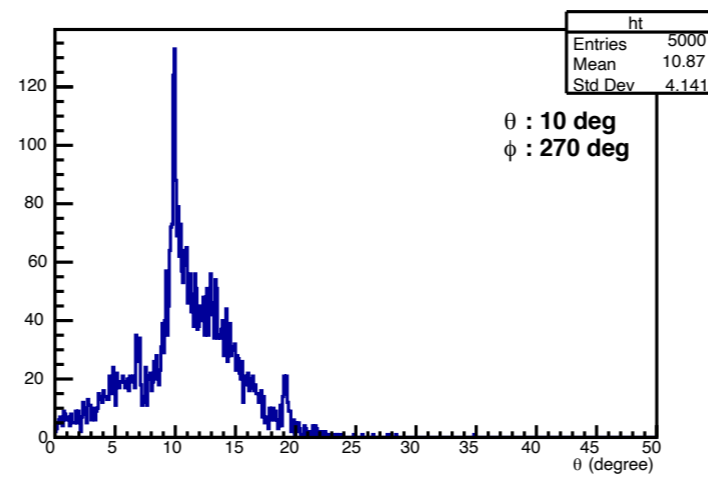
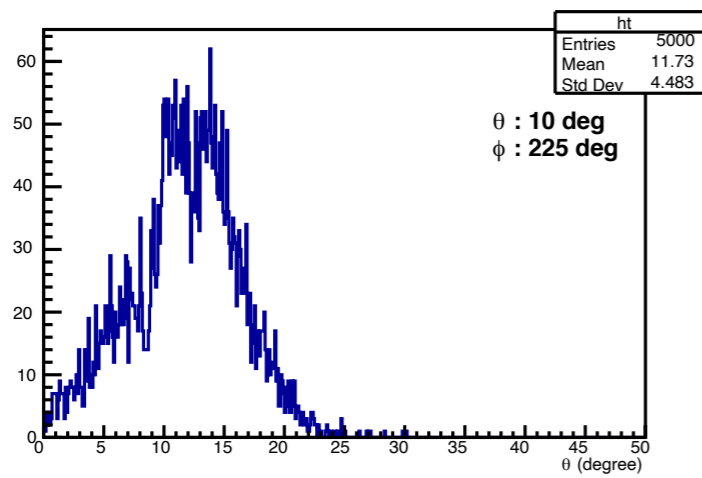
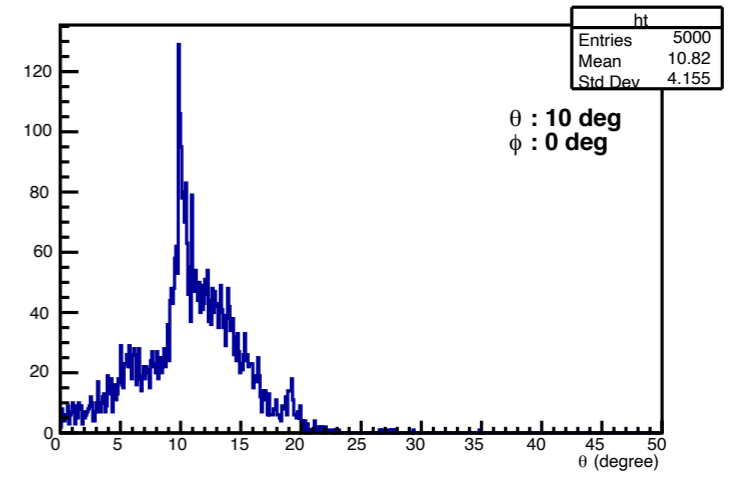
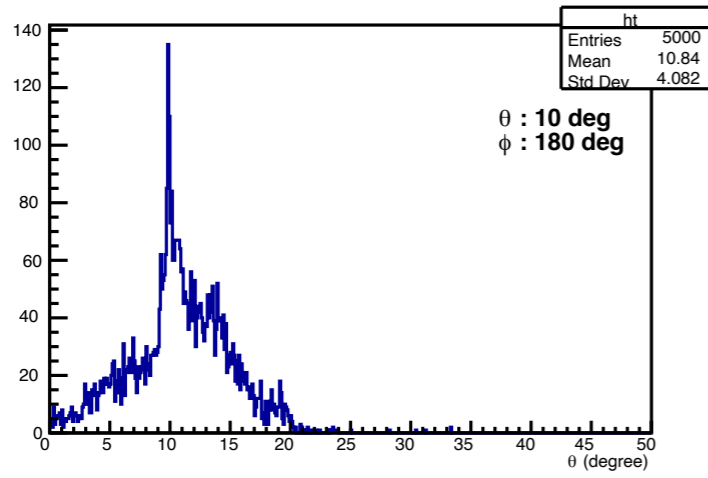
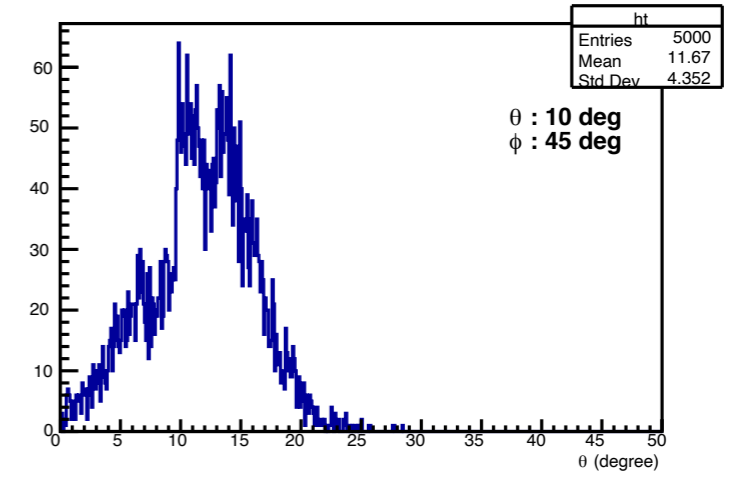
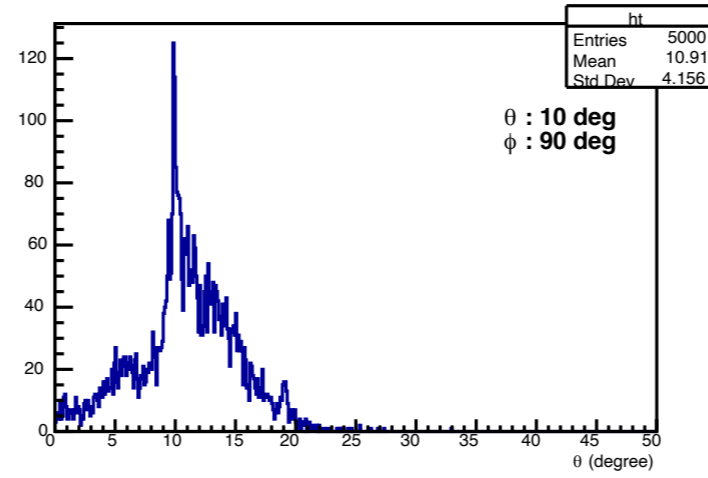
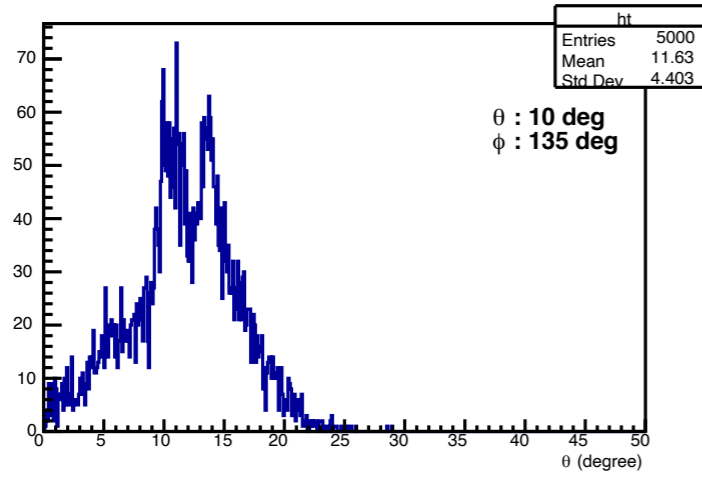
3x3 Clustering, 25 deg



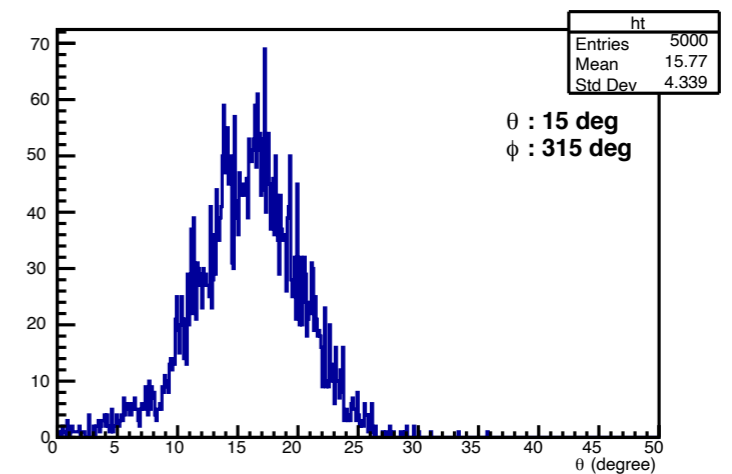
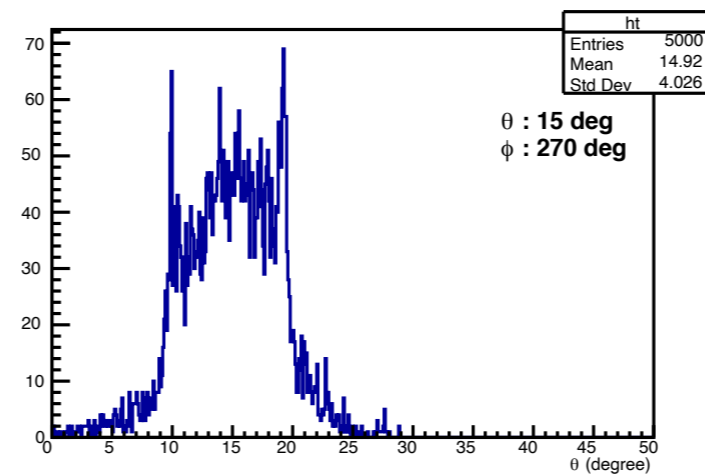
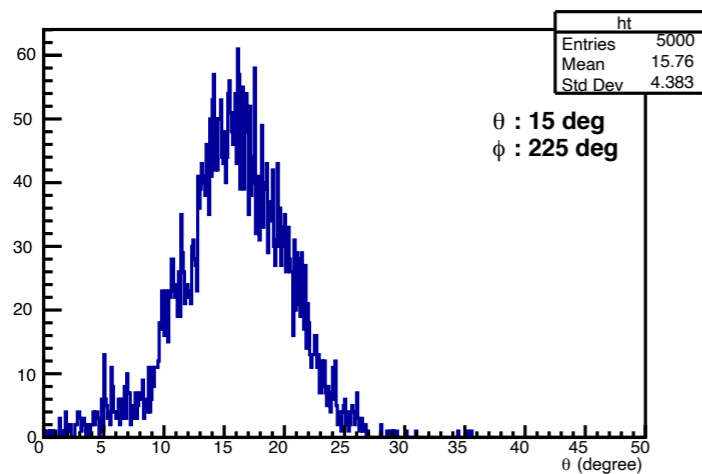
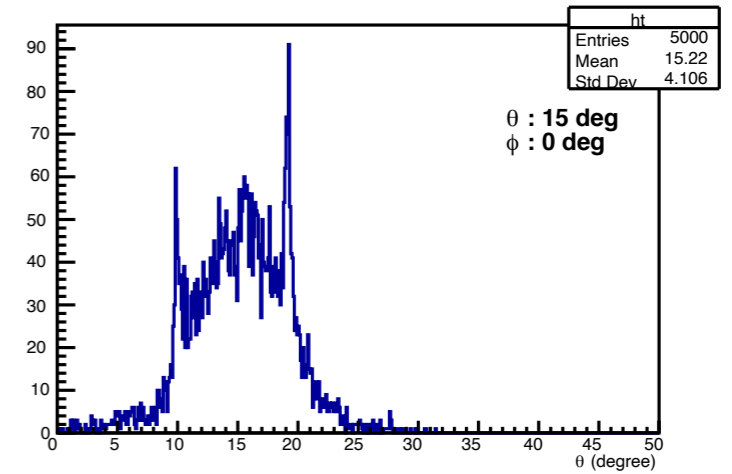
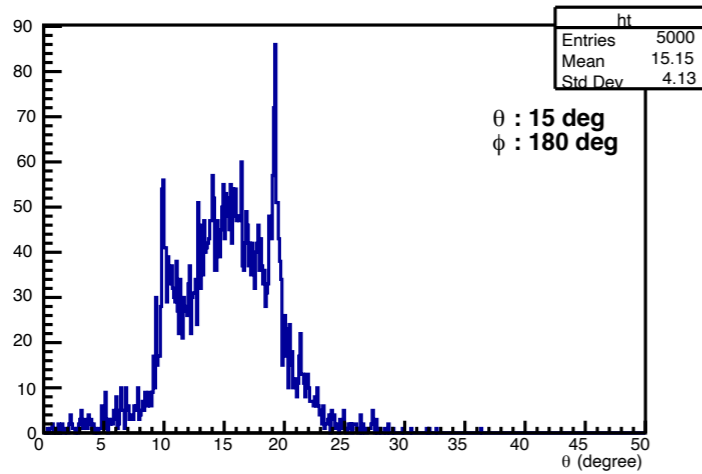
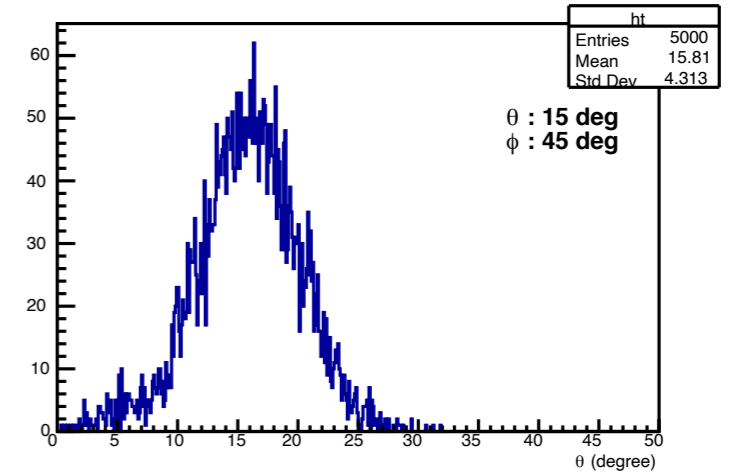
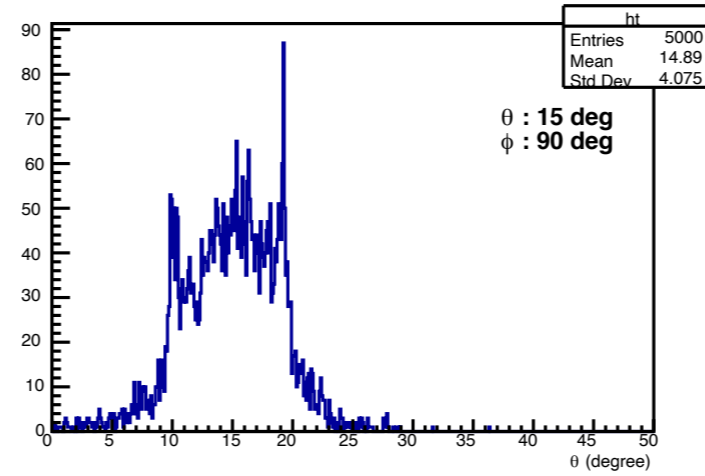
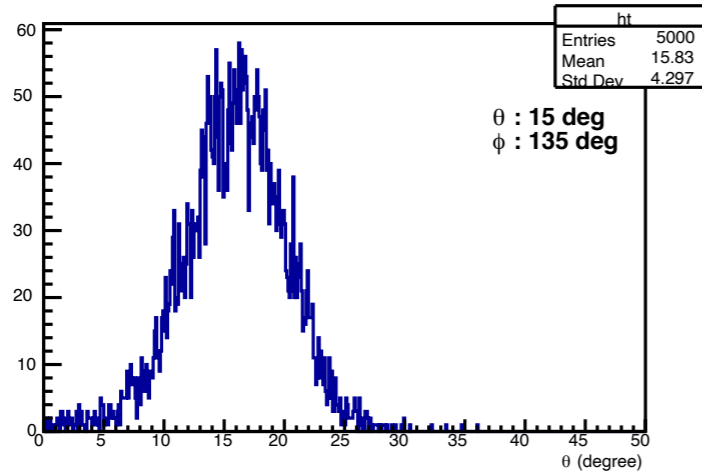
3x3 Clustering, 5 deg



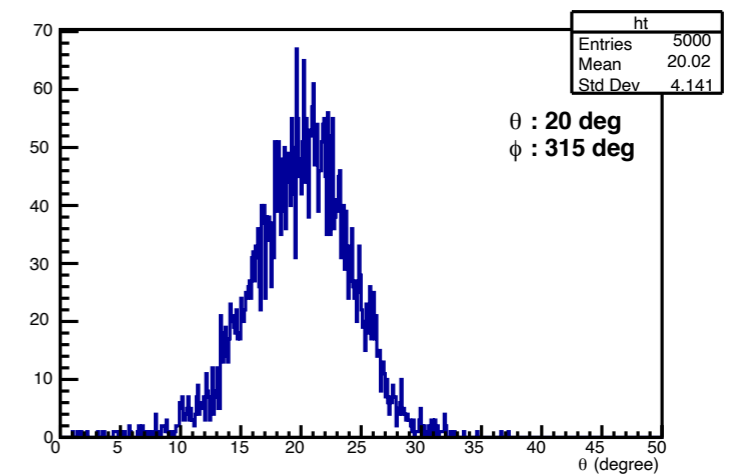
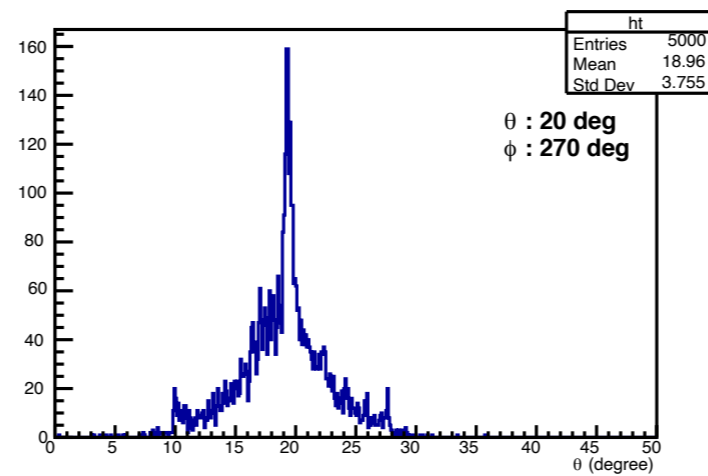
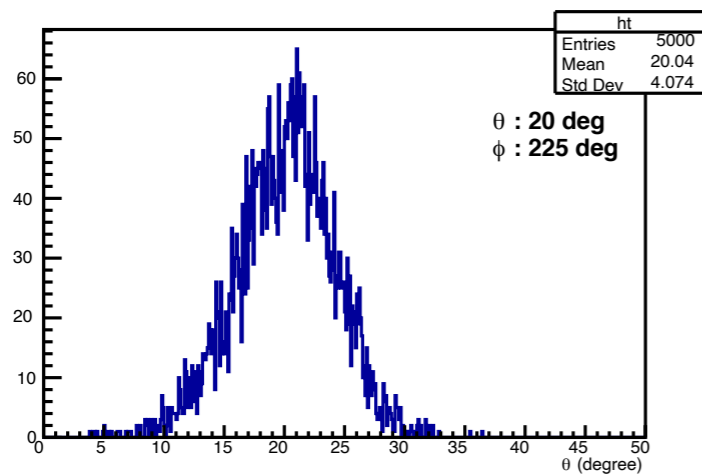
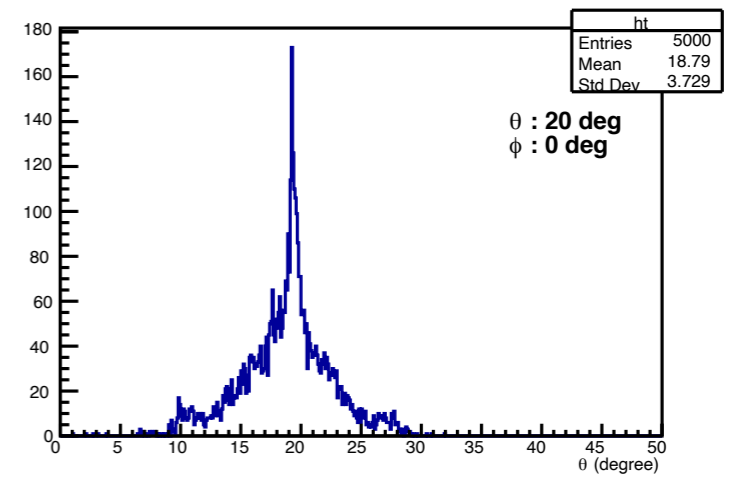
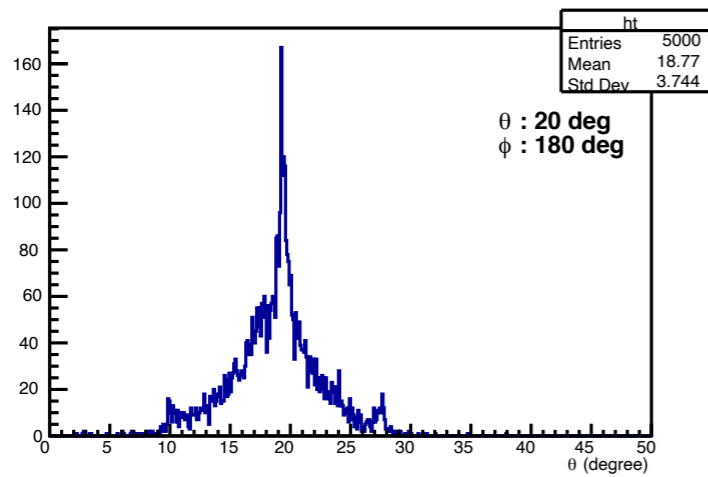
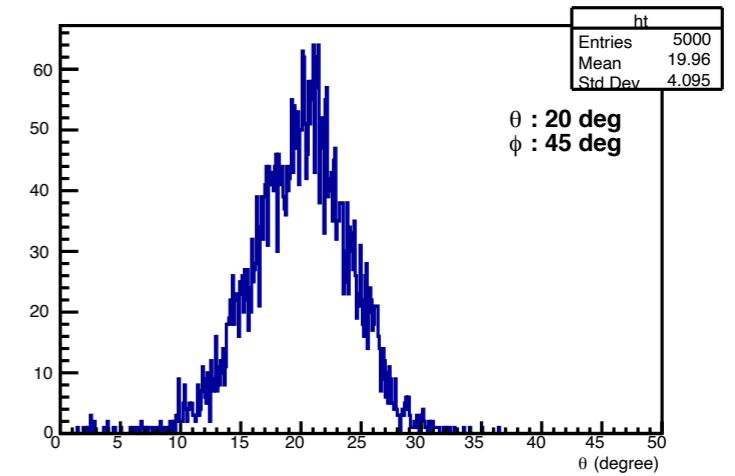
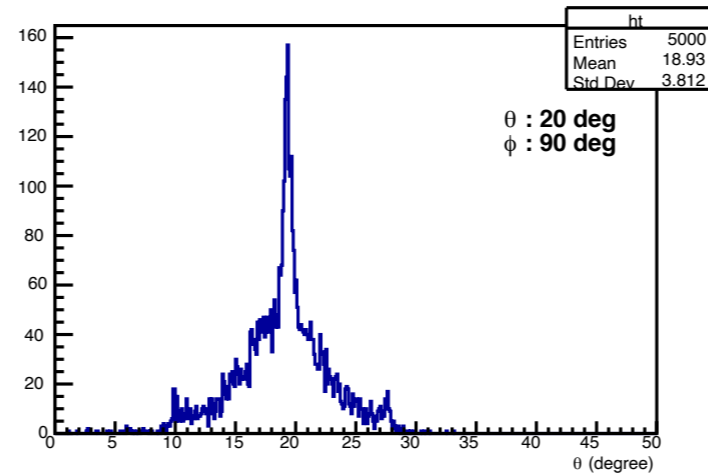
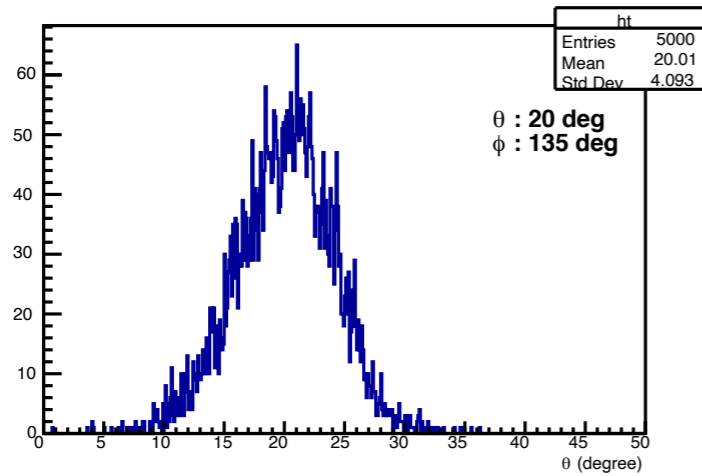
3x3 Clustering, 10 deg



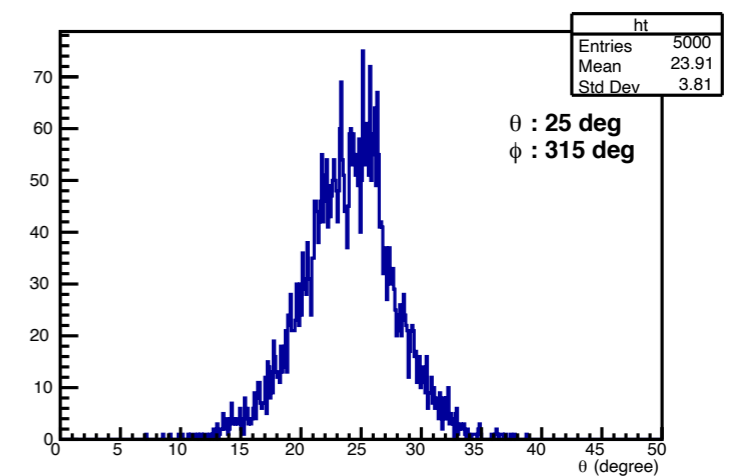
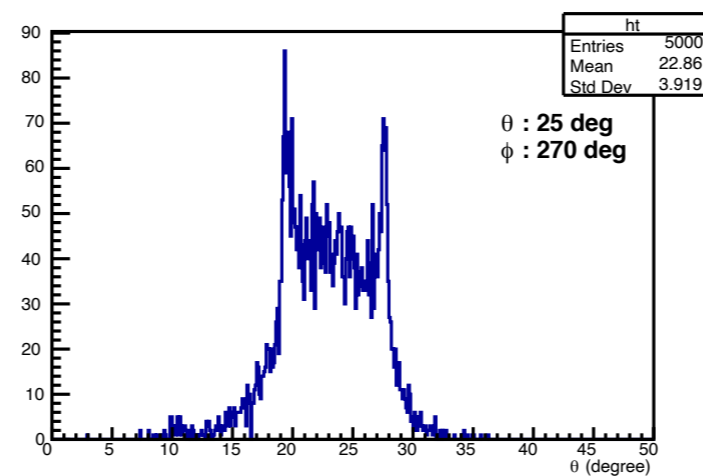
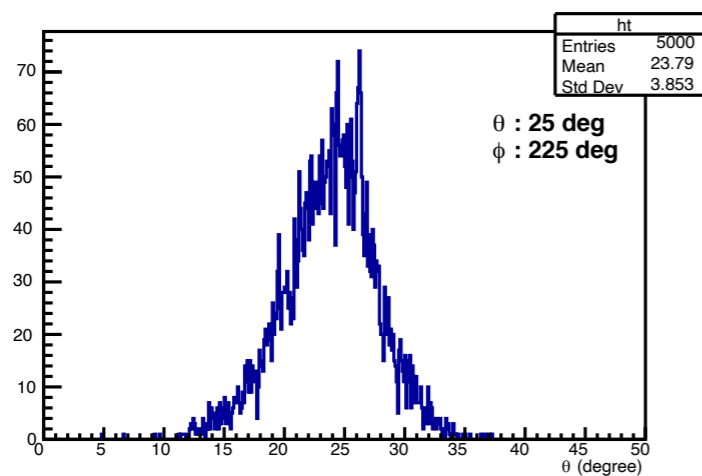
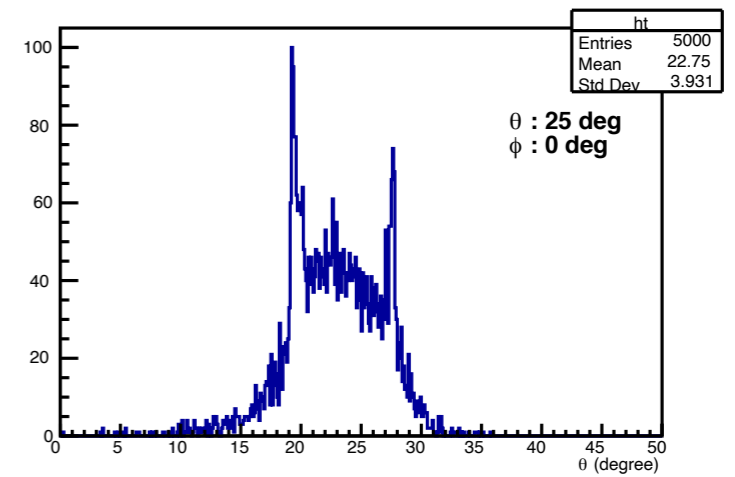
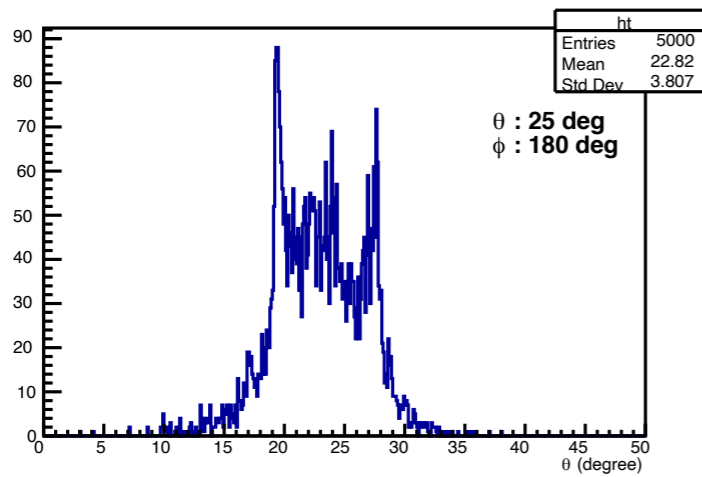
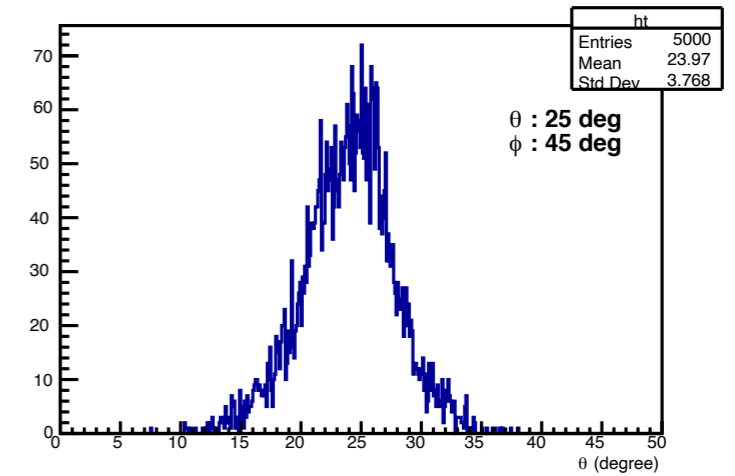
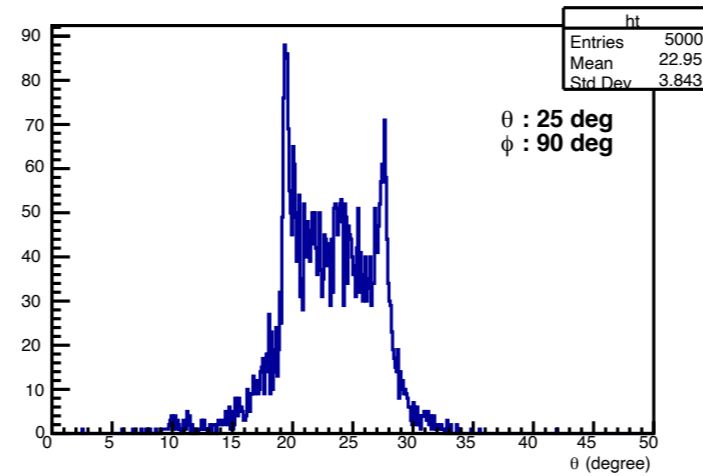
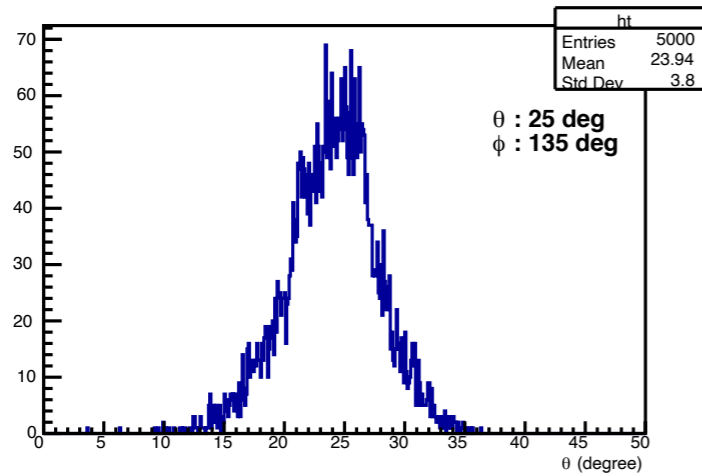
3x3 Clustering, 15 deg



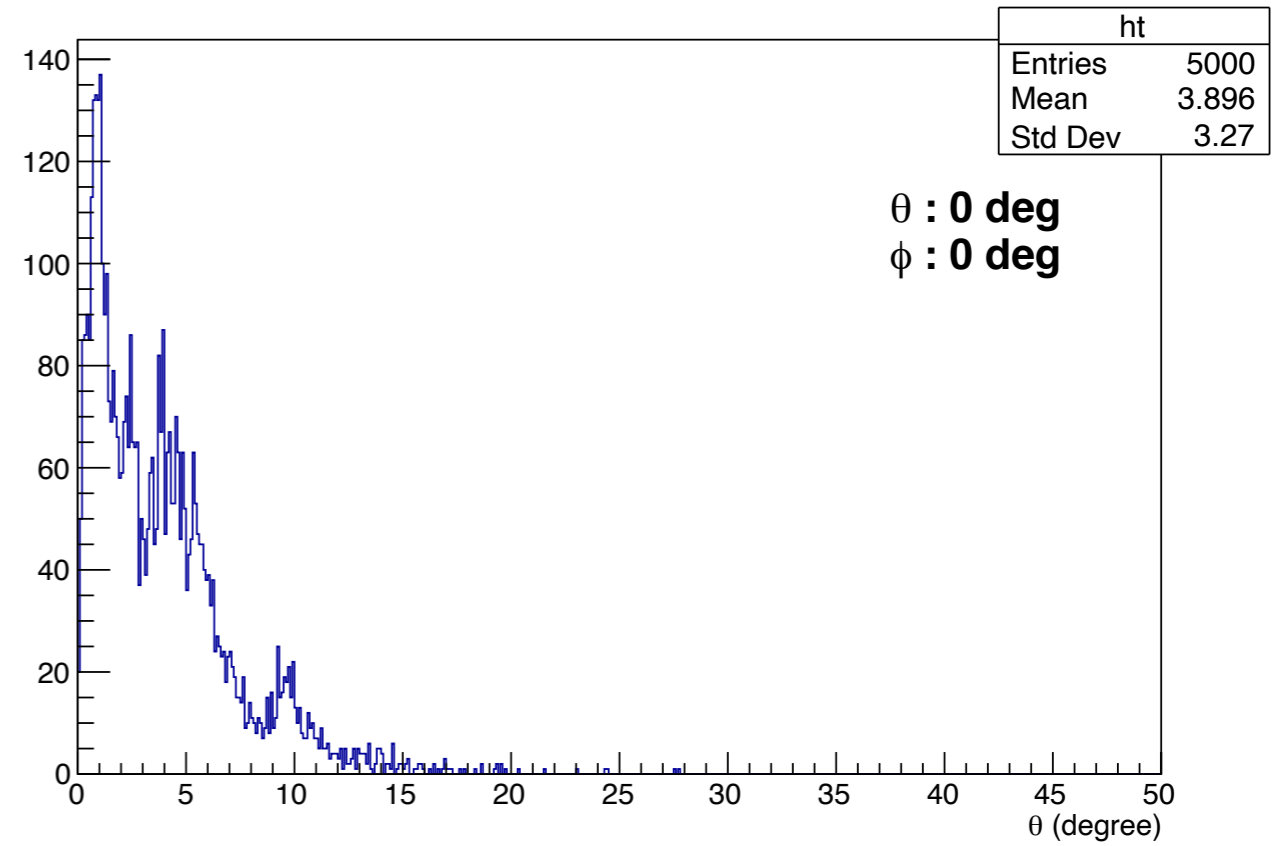
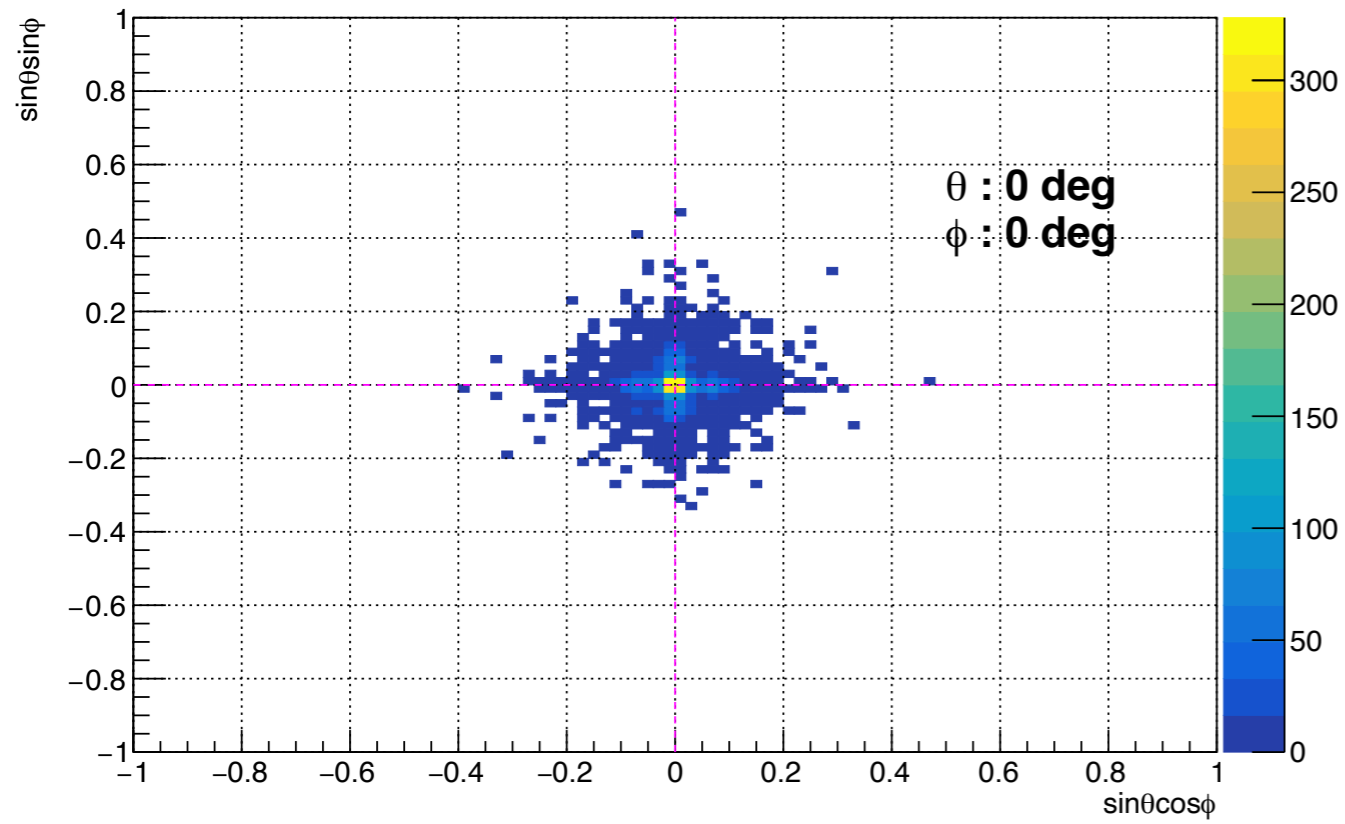
3x3 Clustering, 20 deg



3x3 Clustering, 25 deg

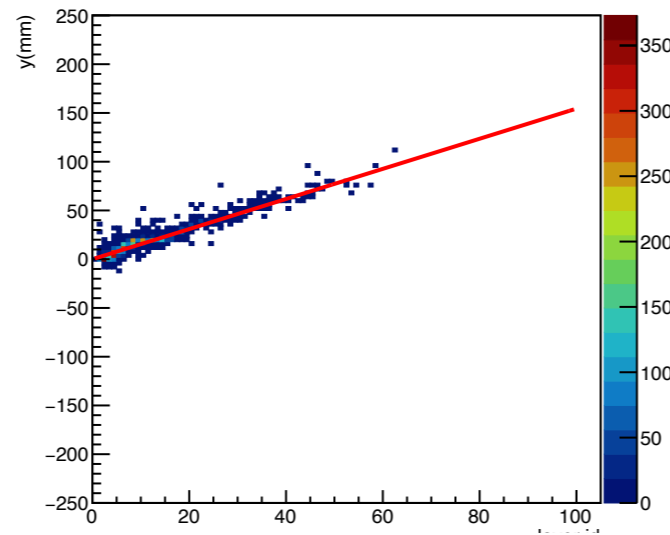
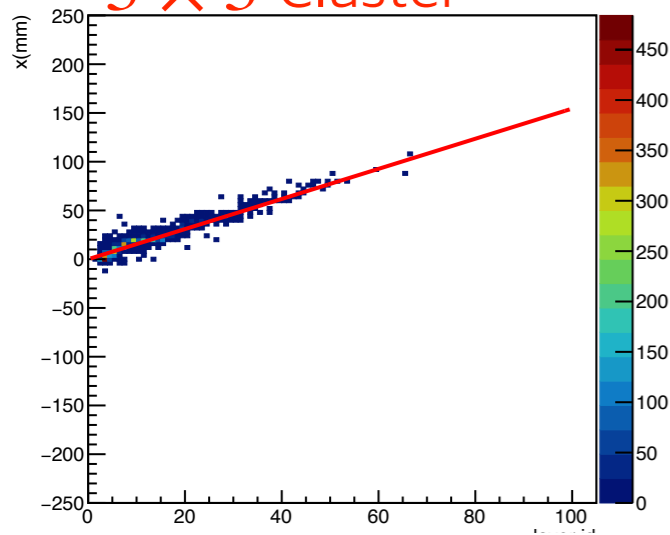


3x3 Clustering, 0 deg

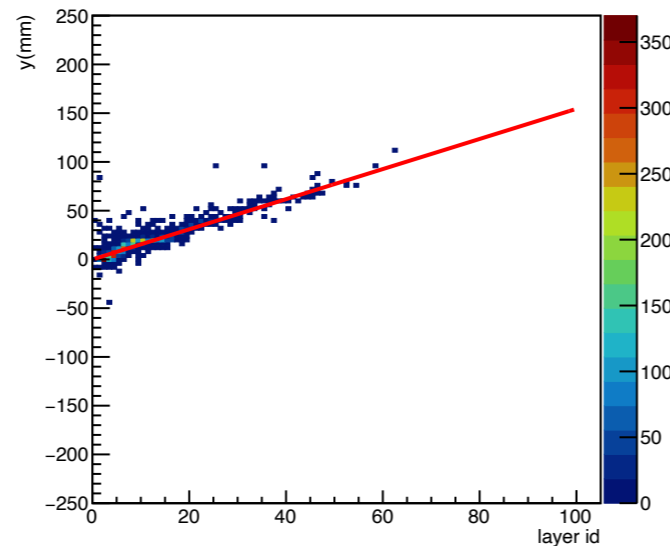
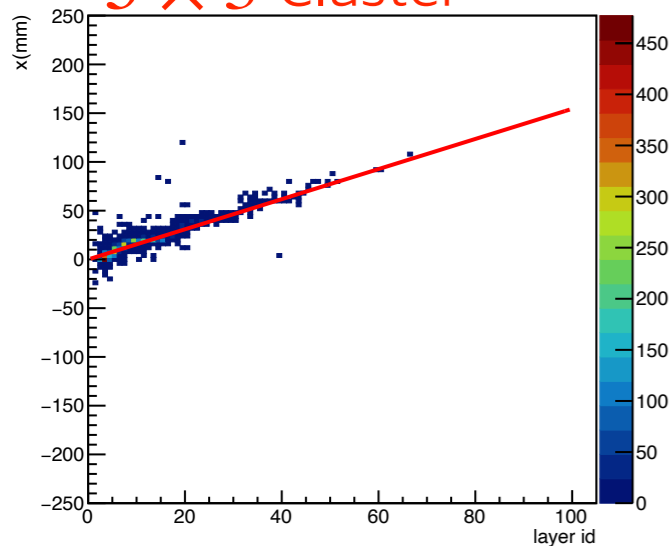


Find a front side x,y position distribution

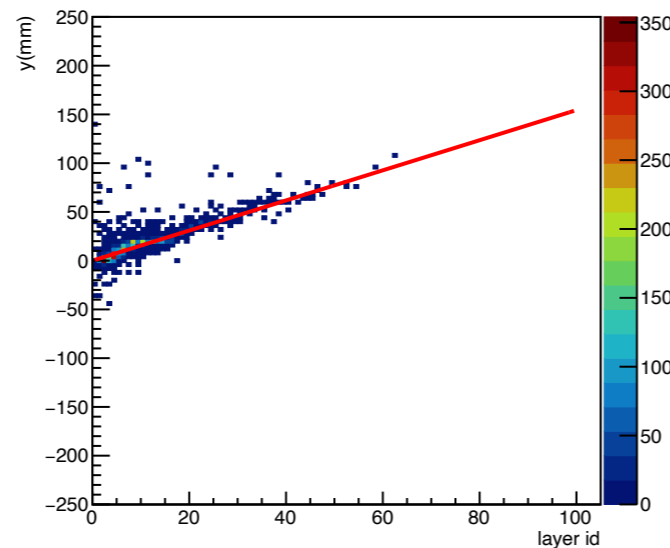
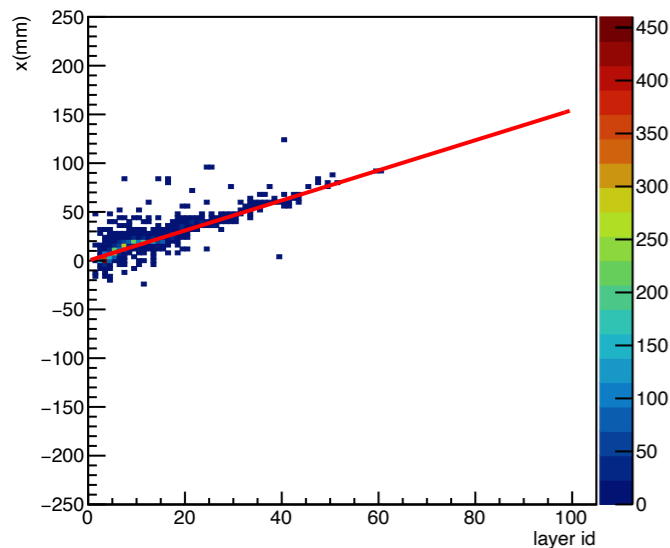
3 × 3 Cluster



5 × 3 Cluster



5 × 5 Cluster



$m \times n$ Clustering

m : Z direction

n : X or Y direction