RHIC Polarimeter Target Scans

(*Refer to Diagrams on attached page*)

1. Open Pet/Polarized Protons/Polarimeter/Control and note the orientation and name of the target

2. Change the **Mode** to “Test Run”

3. Once the **Status** is “Running” you can note the **Count Rate** for the target

4. Open Pet/Polarized Protons/Target/Yellow and scroll to either the vertical or horizontal section of the page as appropriate

5. Increase the **Y(rotary)** target position by 3 to 5 counts

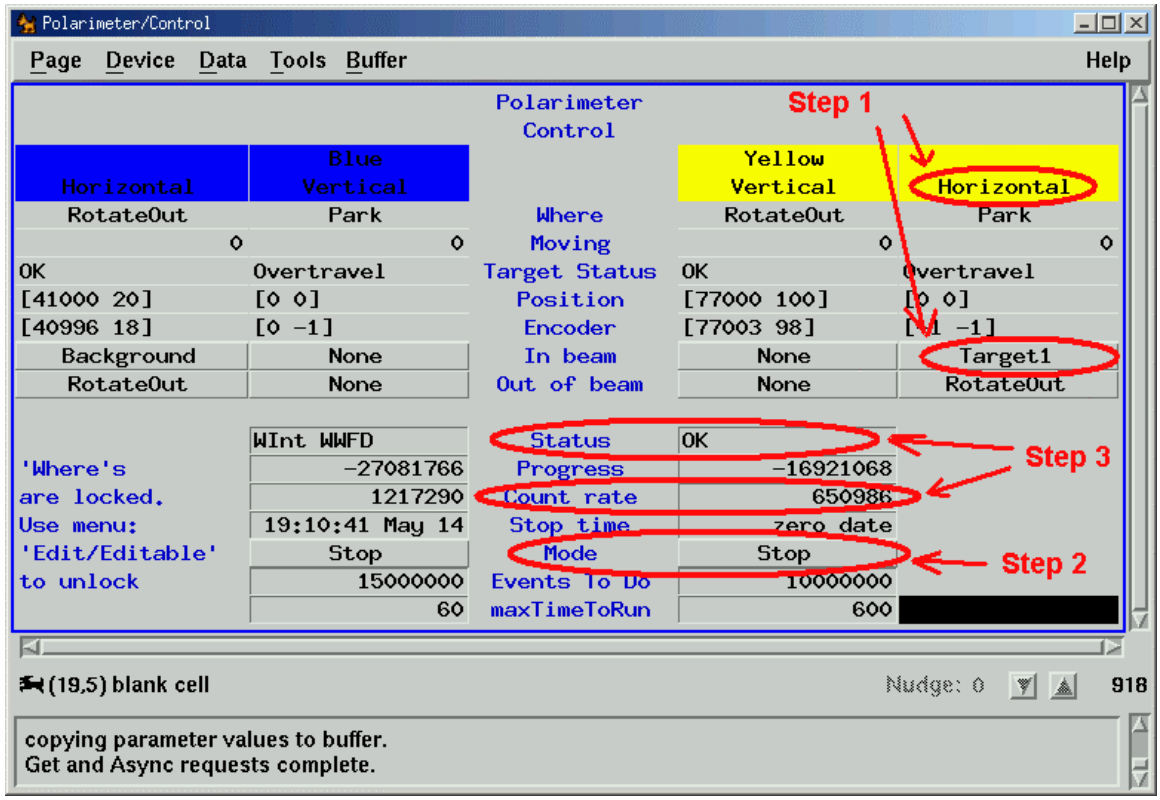
6. Resend the “Target” **Command** in order to make the target move to its new position

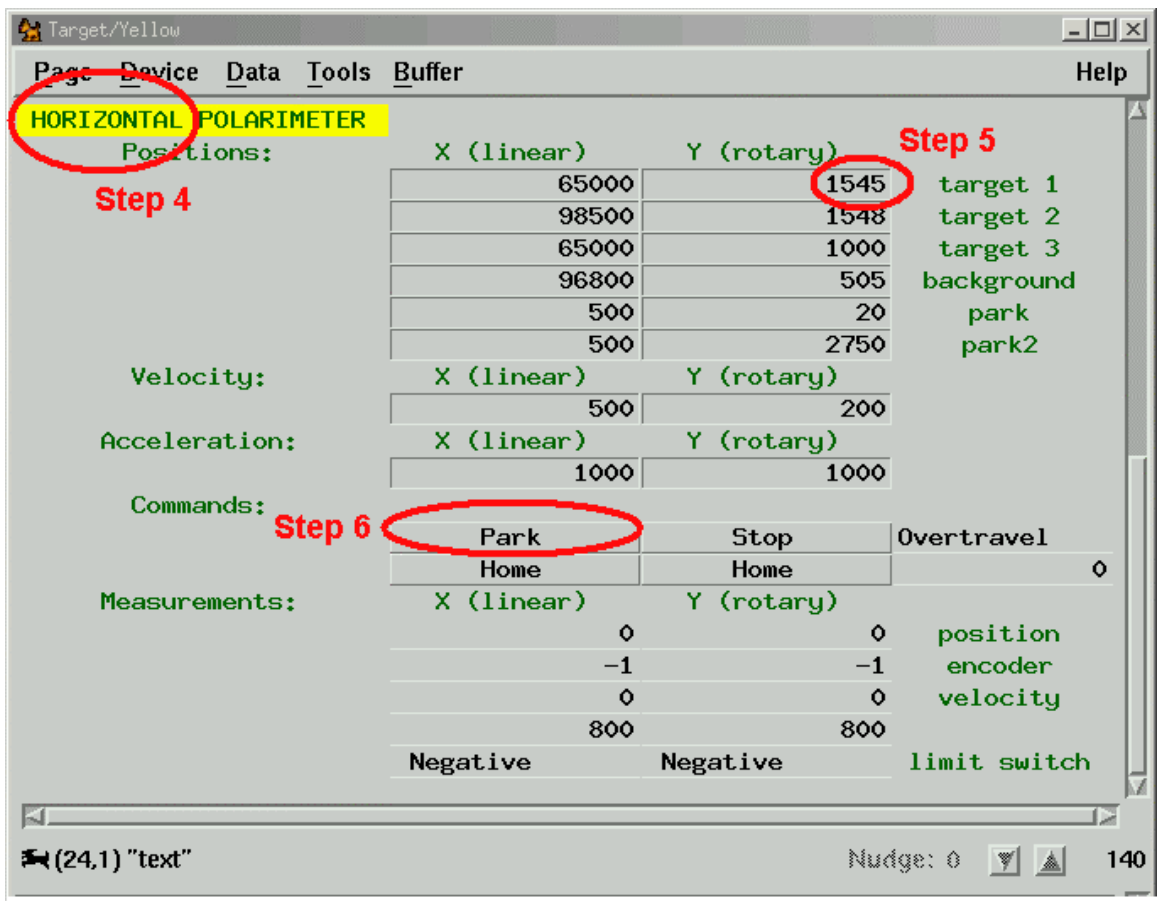
7. Again note the **Count Rate** on the Polarimeter/Control Pet page as in step 3

8. Repeat steps 5, 6 and 7 until you maximize the **Count Rate** (if the **Count Rate** never goes up, then you need start over from the original target position and decrease the counts in step 5)

9. Note: This iterative process must be done while the **Status** on the Polarimeter/Control page is still “Running.” After a short period of time the “Test Run” automatically ends and removes the target. When this occurs, you must wait for the target to stop moving and start over from step 2

10. Repeat for Blue Ring


Polarimeter/Control
Page Device Data Tools Buffer Help
Polarimeter Control
Step 1
Horizontal
Blue Vertical
Yellow Vertical
Horizontal
RotateOut
Park
Where
RotateOut
Park
0
0
Moving
0
0
OK
Overtravel
Target Status
OK
Overtravel
[41000 20]
[0 0]
Position
[77000 100]
[0 0]
[40996 18]
[0 -1]
Encoder
[77003 98]
[1 -1]
Background
None
In beam
None
Target1
RotateOut
None
Out of beam
None
RotateOut
WInt WWFD
Status
OK
Step 3
'Where's
-27081766
Progress
-16921068
are locked.
1217290
Count rate
650986
Use menu:
19:10:41 May 14
Stop time
zero date
'Edit/Editable'
Stop
Mode
Stop
Step 2
to unlock
15000000
Events To Do
10000000
60
maxTimeToRun
600
(19,5) blank cell
Nudge: 0
918
copying parameter values to buffer.
Get and Async requests complete.


Target/Yellow
Page Device Data Tools Buffer Help
HORIZONTAL POLARIMETER
Step 5
Positions:
X (linear)
Y (rotary)
Step 4
65000
1545
target 1
98500
1548
target 2
65000
1000
target 3
96800
505
background
500
20
park
500
2750
park2
Velocity:
X (linear)
Y (rotary)
500
200
Acceleration:
X (linear)
Y (rotary)
1000
1000
Commands:
Step 6
Park
Stop
Overtravel
Home
Home
0
Measurements:
X (linear)
Y (rotary)
0
0
position
-1
-1
encoder
0
0
velocity
800
800
Negative
Negative
limit switch
(24,1) "text"
Nudge: 0
140