

Status Update

11/16/2018

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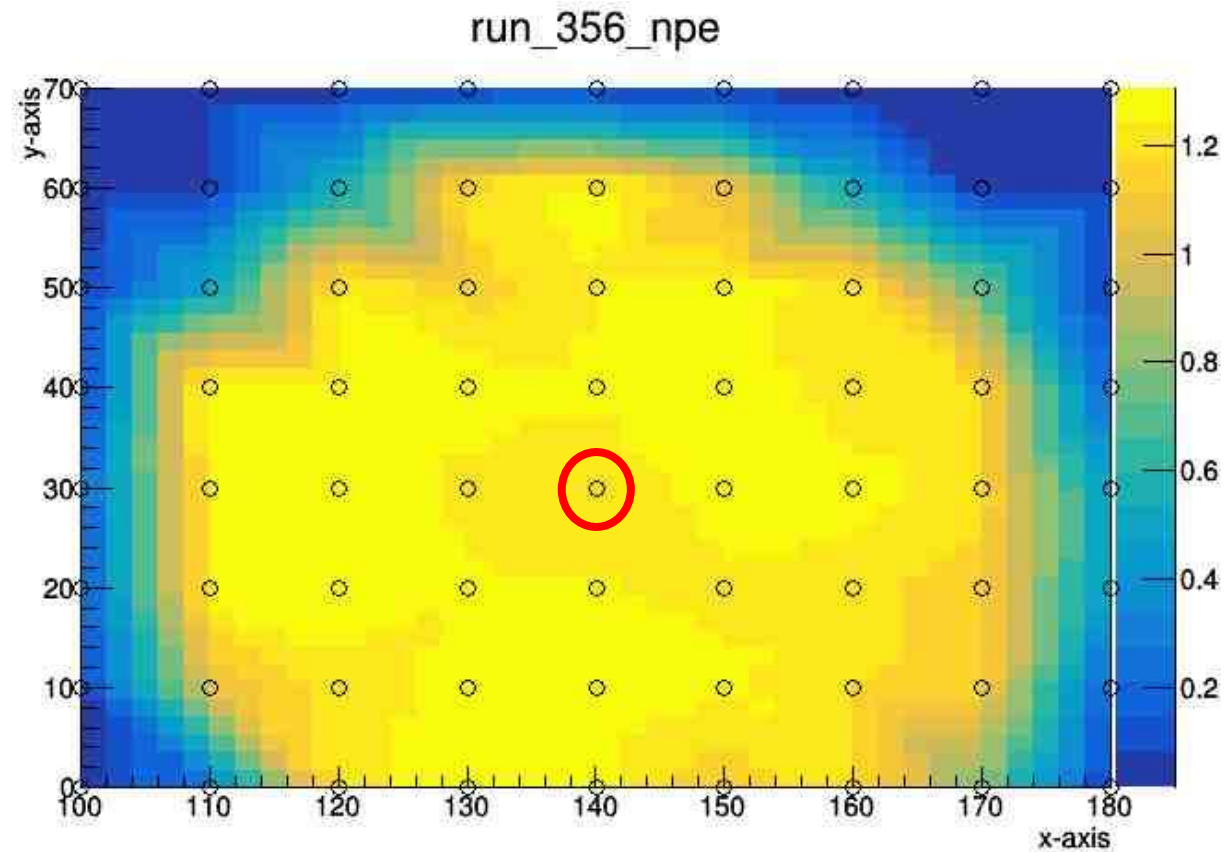
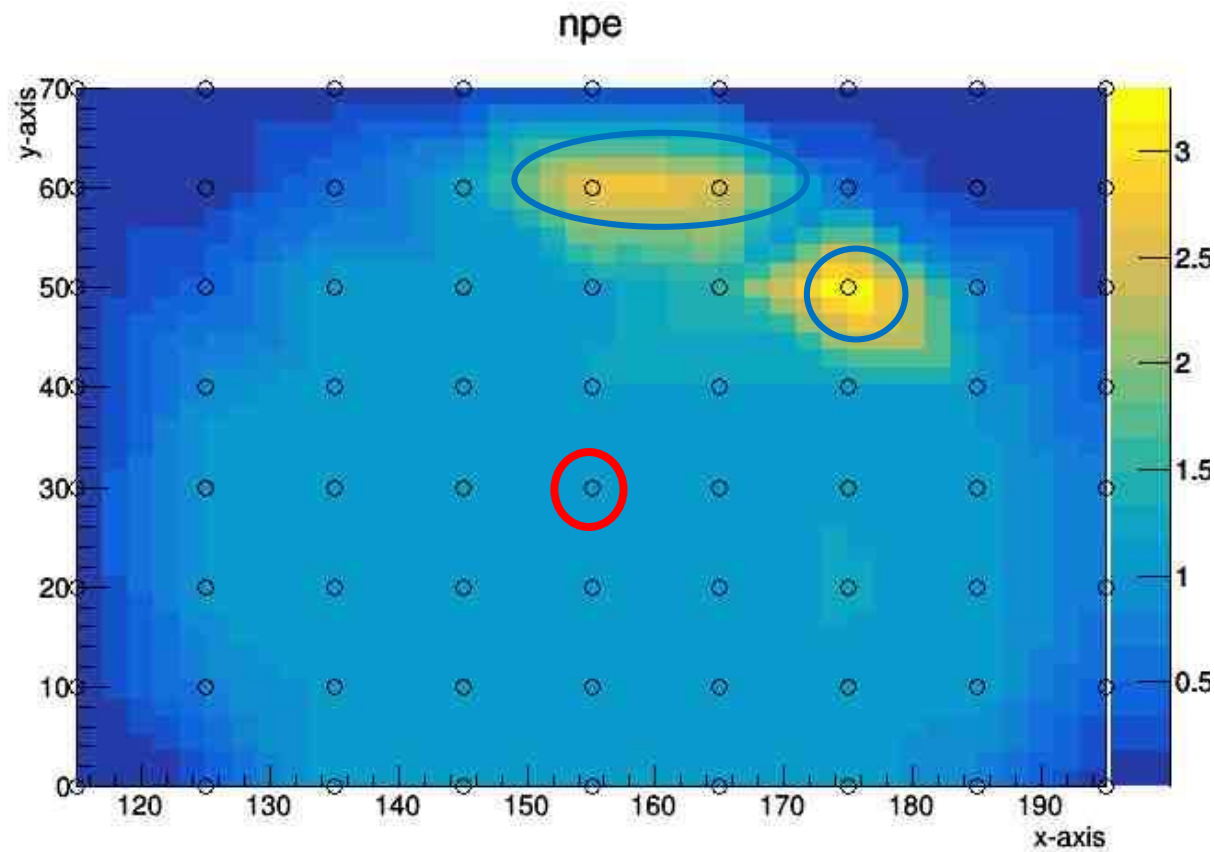
Motorized stand

- We are having trouble with connecting the main controller of the motorized stand to PC.
- I could send and receive packets from the main controller when I performed the ping test.
- There might be a problem with TCP(Transmission Control Protocol).

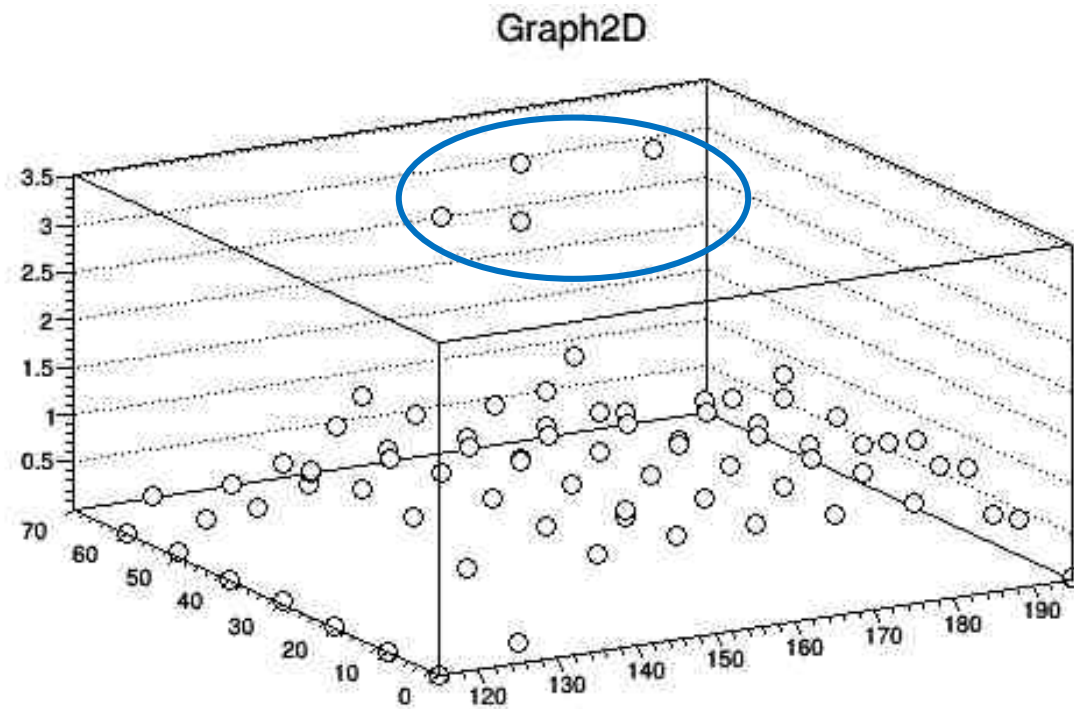
```
rtt min/avg/max/mdev = 0.045/0.049/0.053/0.003 ms
neutrino@neutrino:~/python/PMTTesting-master/MotorizedStand/python$ python3 xyz.py step_calibra
te
Number of arguments:2 arguments:['xyz.py', 'step_calibrate']
2018-11-15 15:05:48,253 ERROR XYZ: Traceback (most recent call last):
  File "xyz.py", line 103, in init_connection
    sock.connect((set.TCP_IP, set.TCP_PORT))
ConnectionRefusedError: [Errno 111] Connection refused

2018-11-15 15:05:48,253 ERROR XYZ: Cannot connect to controller
2018-11-15 15:05:48,253 INFO XYZ: Closing connection!
2018-11-15 15:05:48,253 ERROR XYZ: Traceback (most recent call last):
  File "xyz.py", line 1109, in main
    raise ConnectionError("Cannot connect to XYZ controller!")
ConnectionError: Cannot connect to XYZ controller!
```

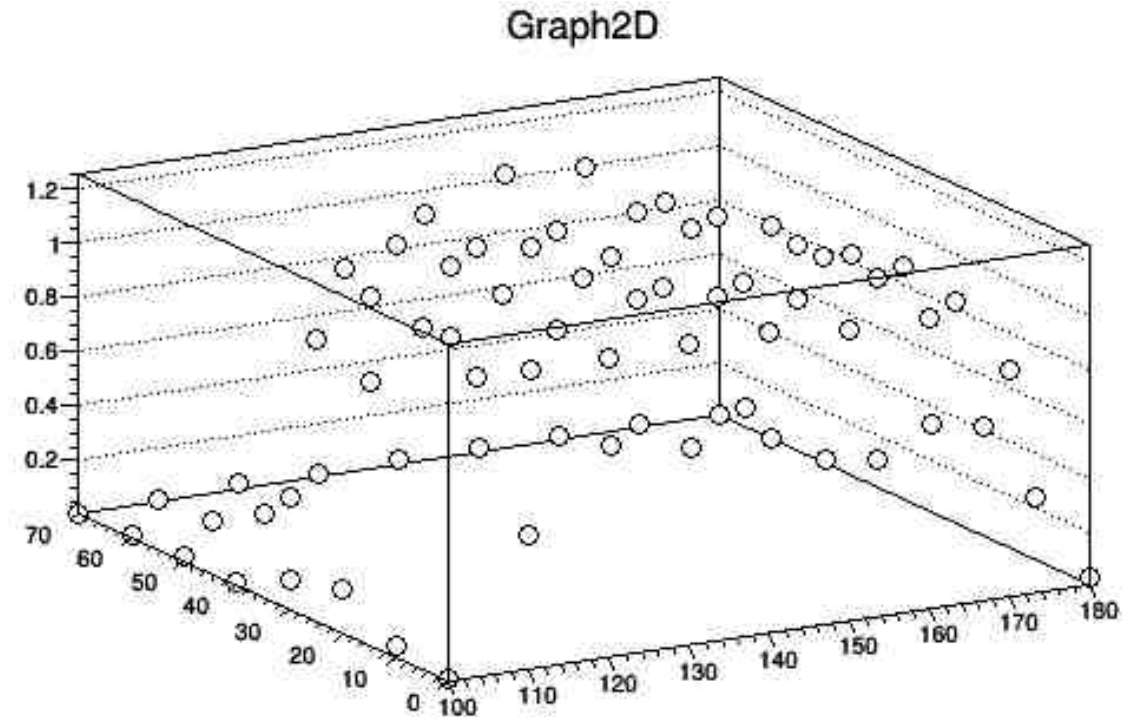
Results from the 300 sec measurement



Results from the 300 sec measurement

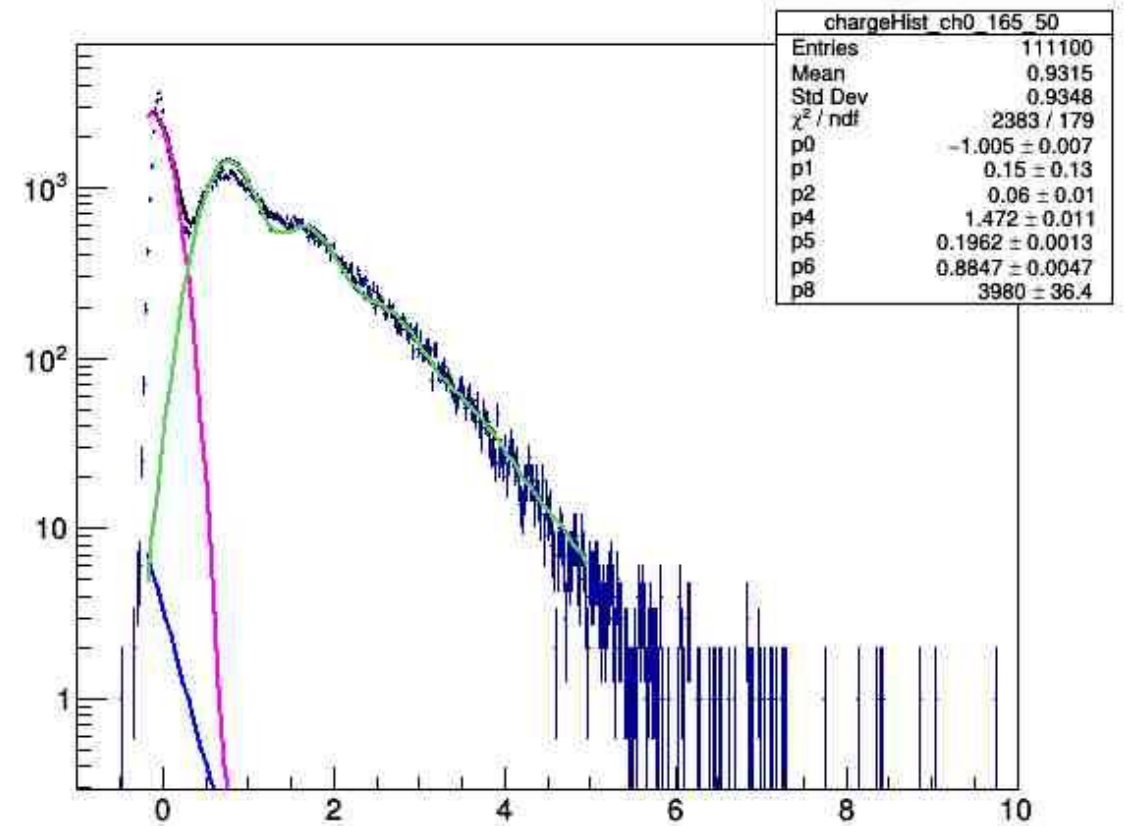
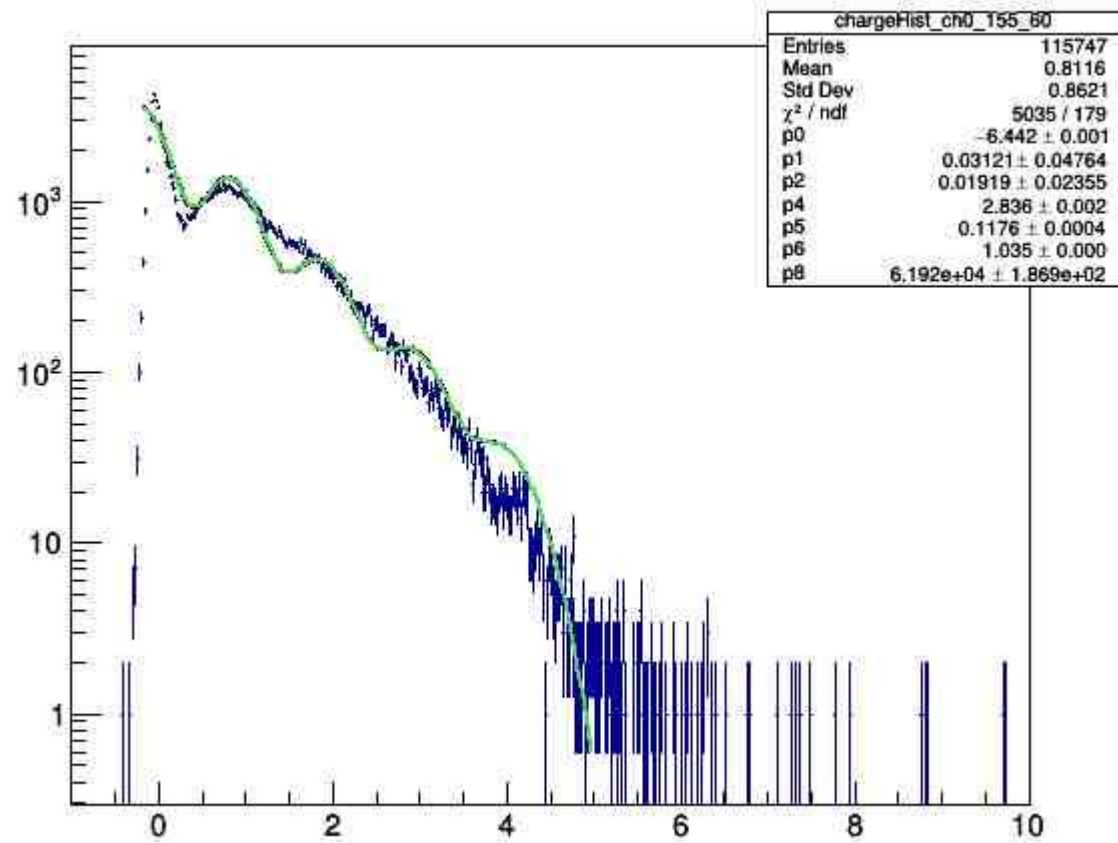


300 sec

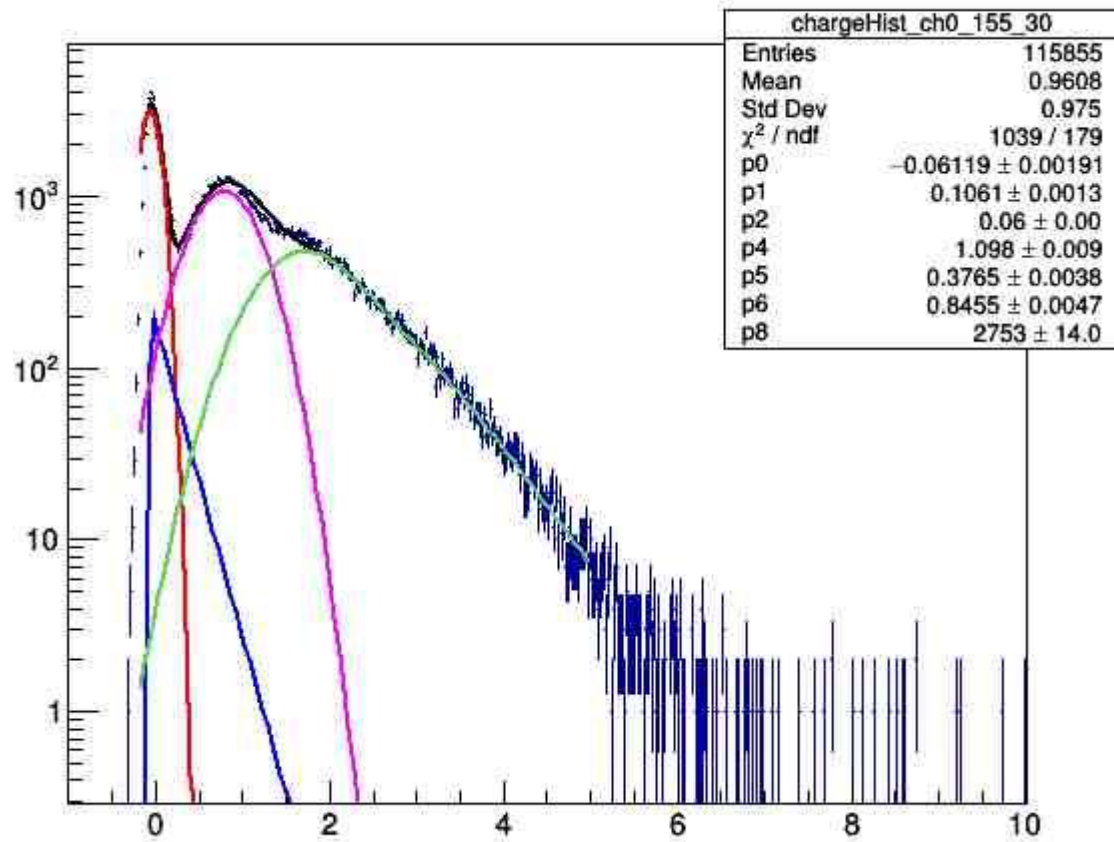


100 sec

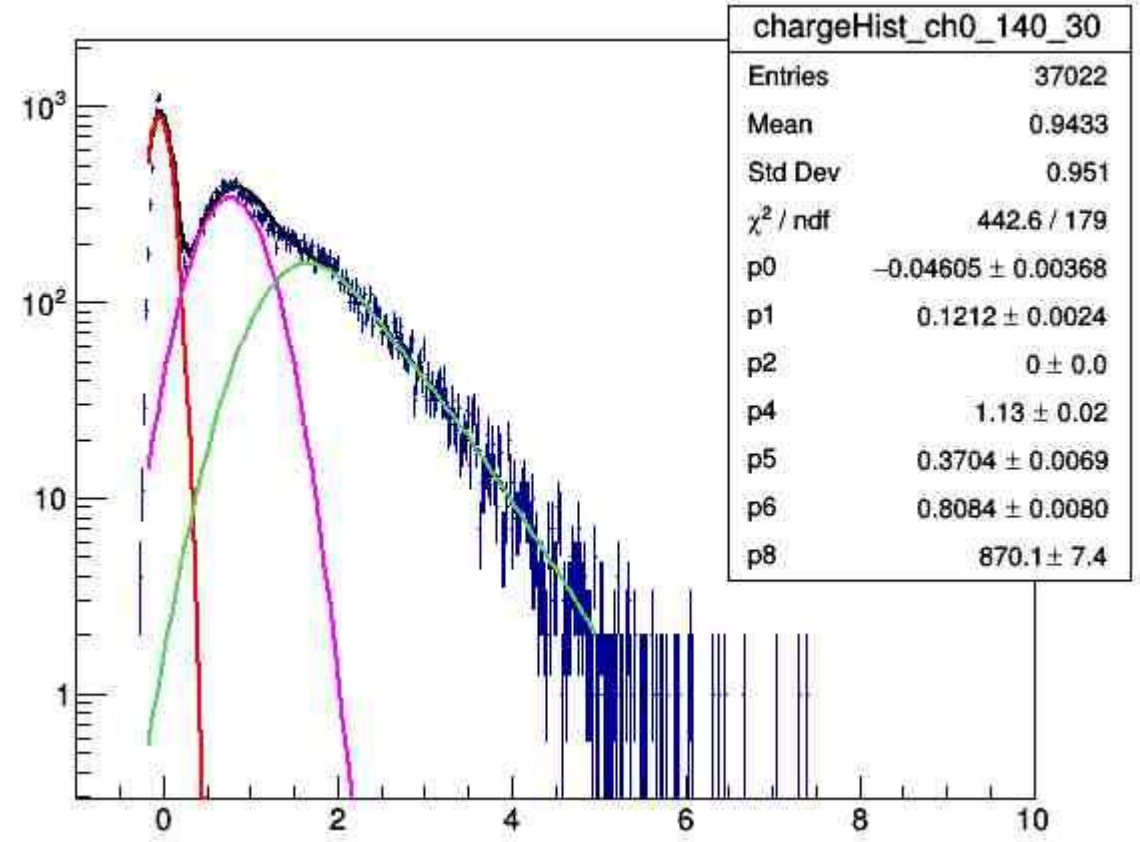
Fits seem to have failed at some points



at the center of the PMT

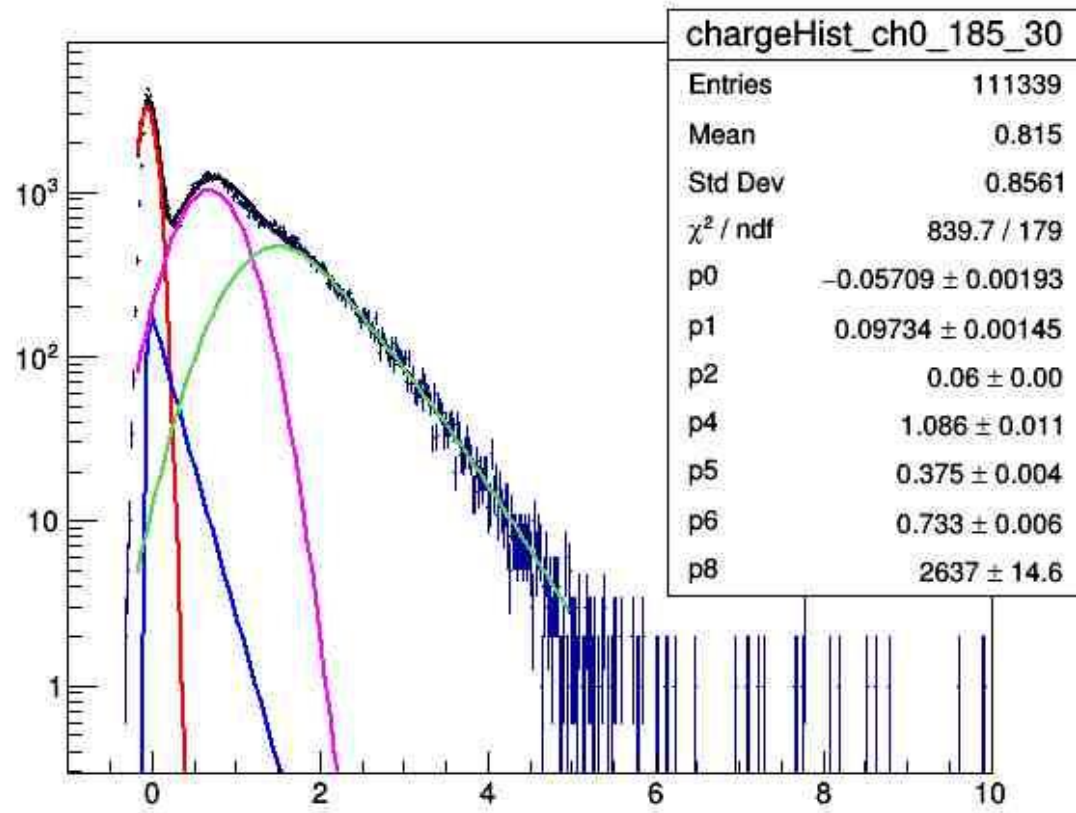


300 sec

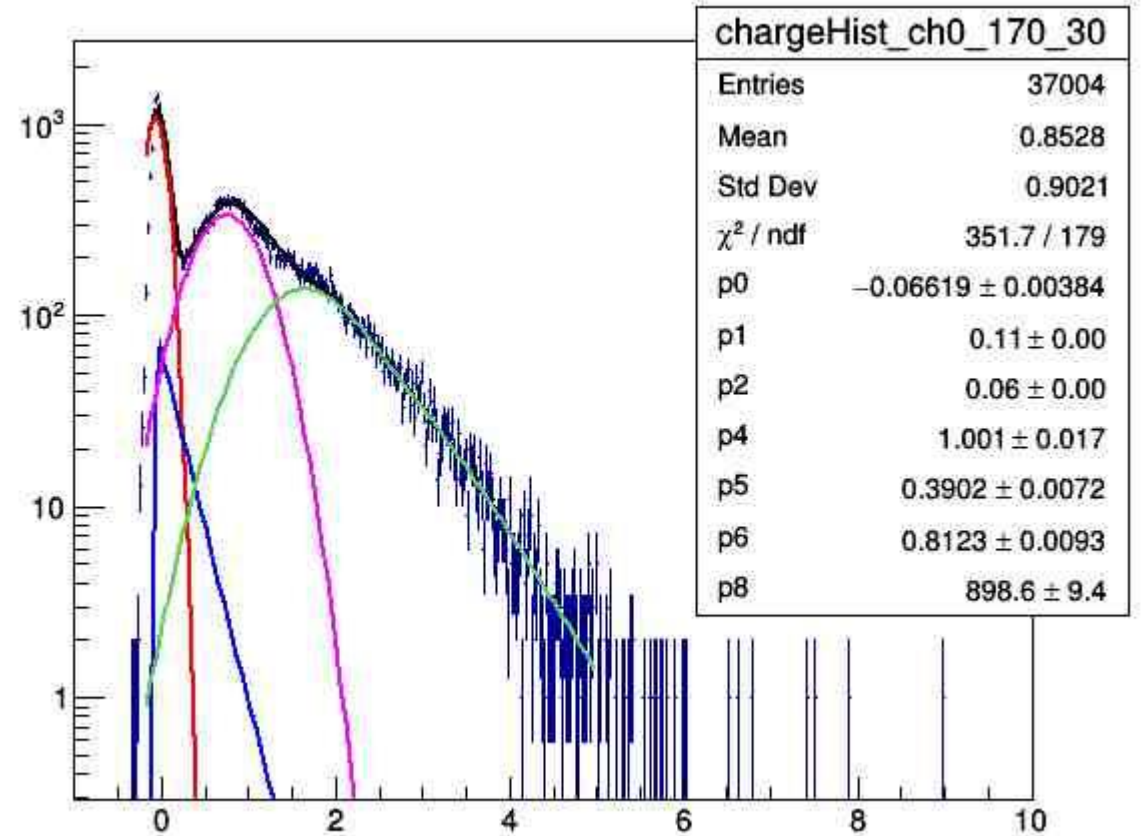


100 sec

At the edge of the PMT



300 sec



100 sec

Fit is not good?

To do next week

- Fix the motorized stand.
- Do the measurement with the rotated PMT(180 degrees?).
- Do the pure angular measurement.

