

Enhancing Rubin Science with Robust Cross-Matches in the Crowded LSST Sky

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LSST@EU5 – *Joint TVS-SMWLV SC Session 28/Sep/23*

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github.io www



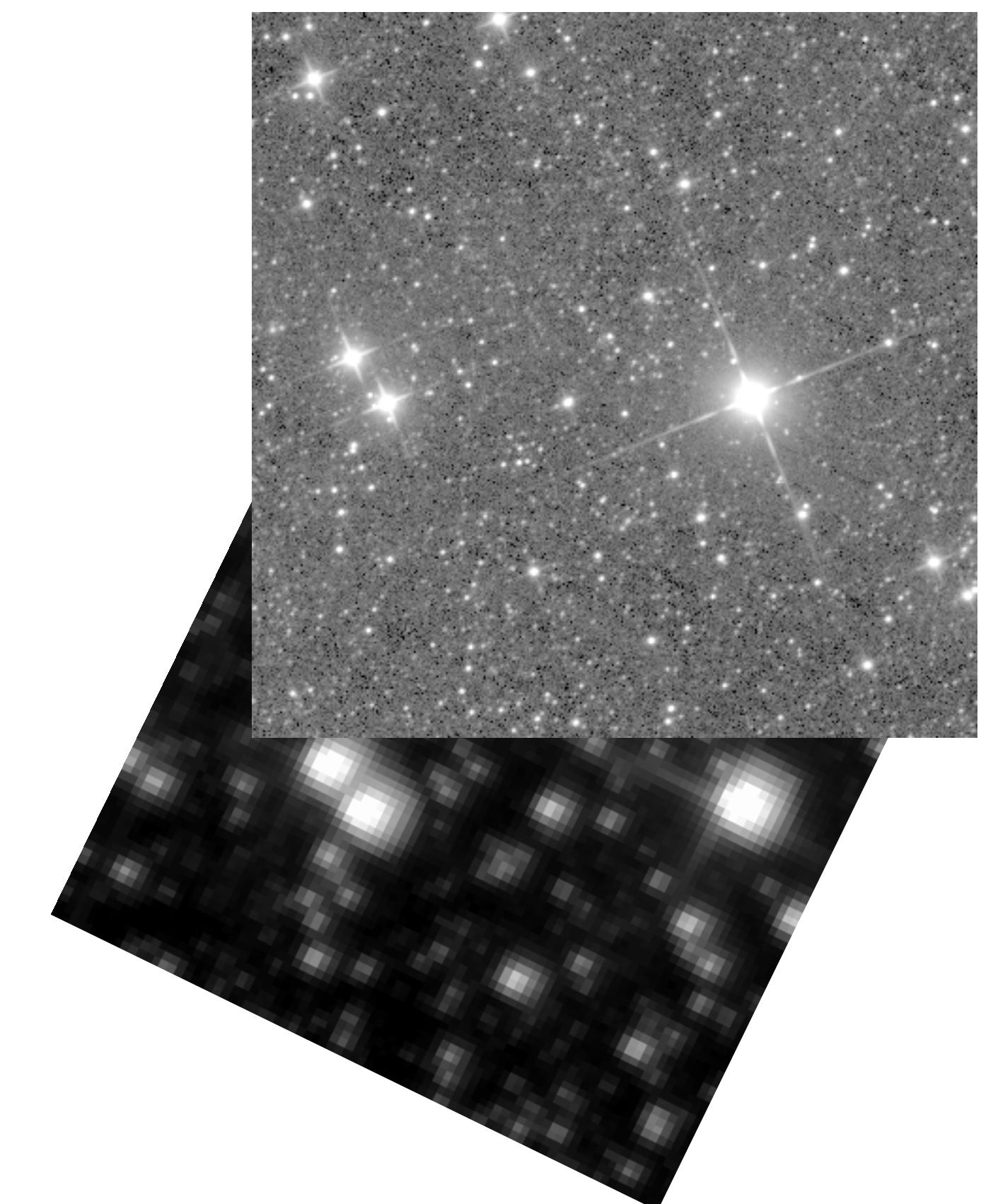
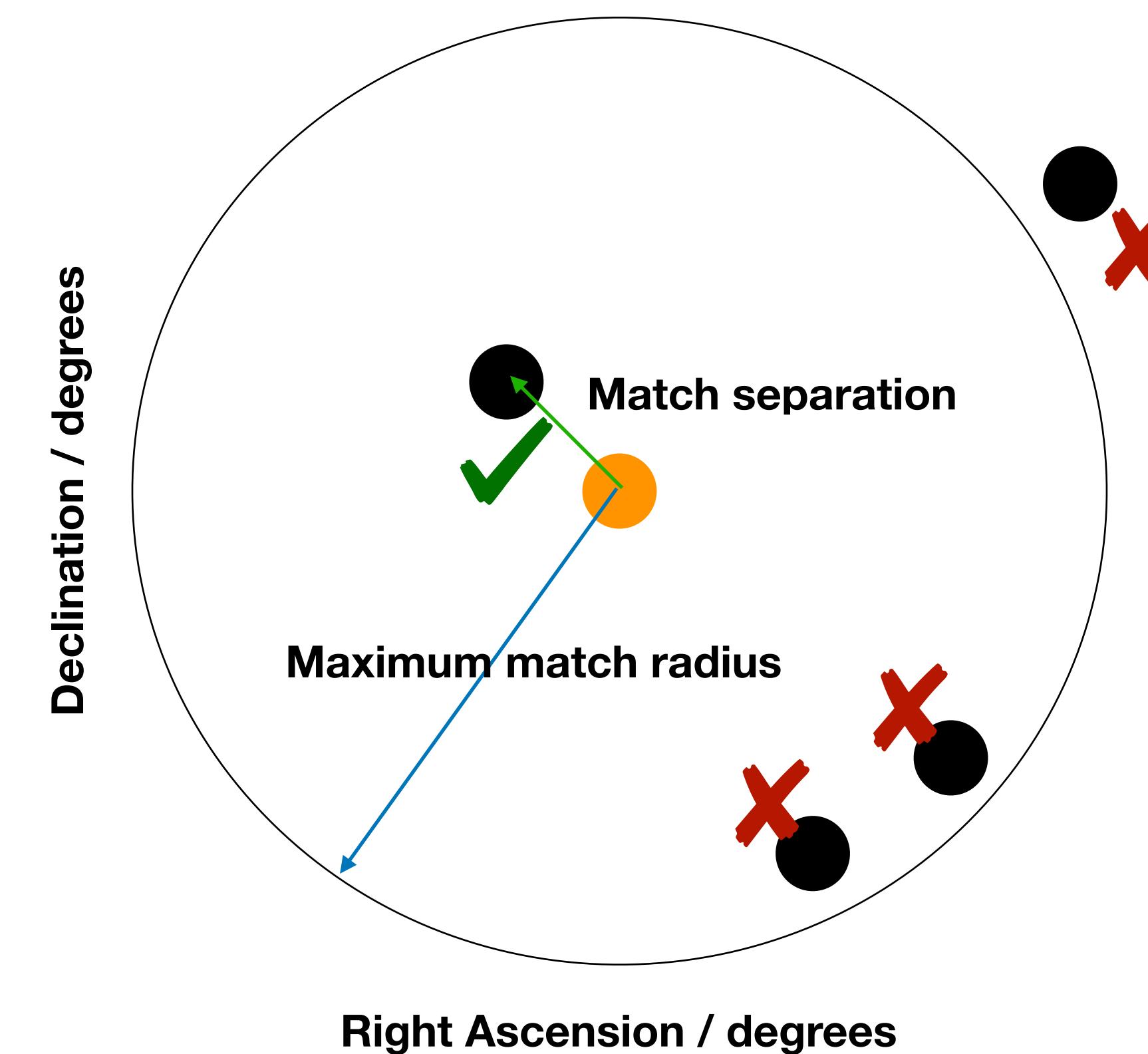
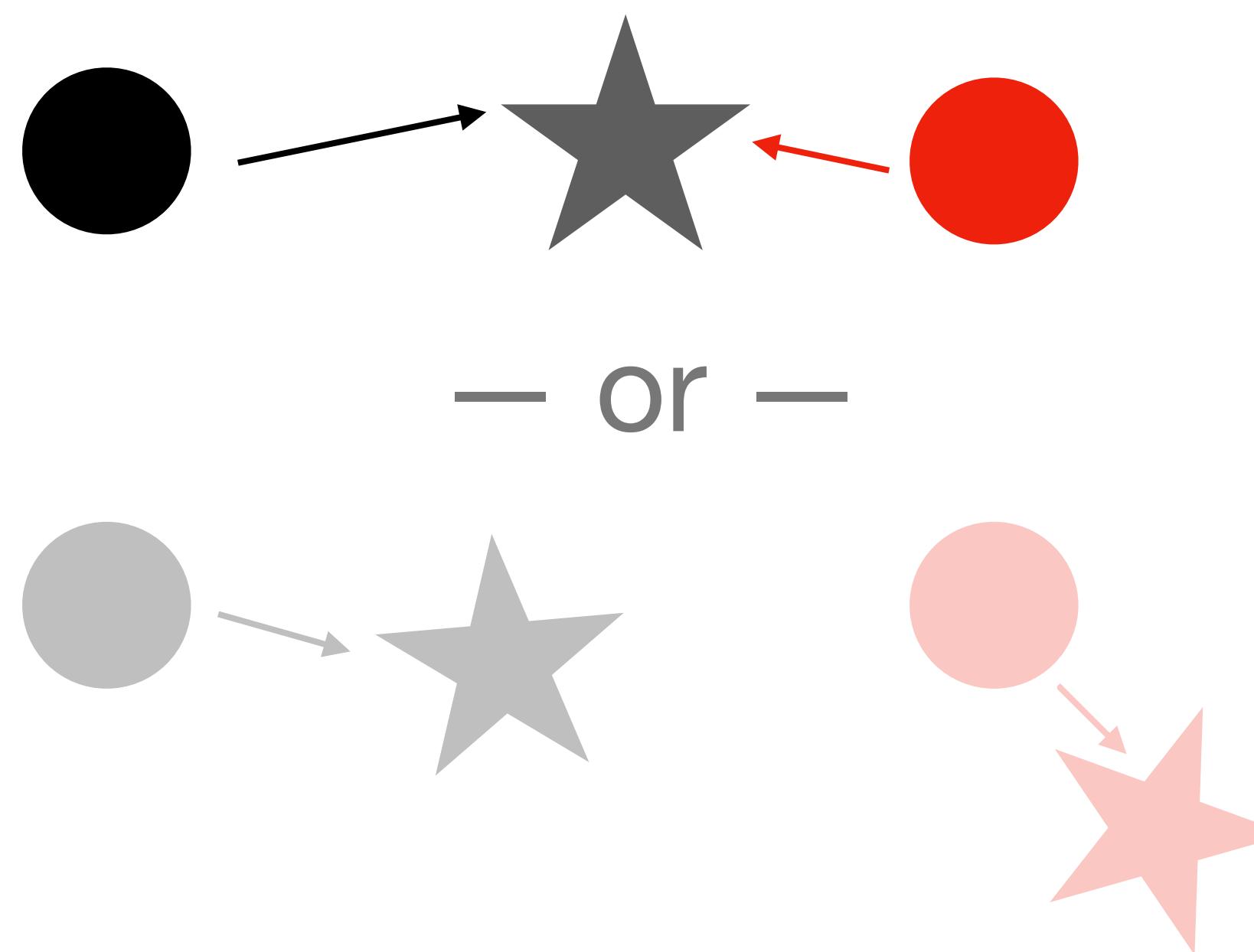
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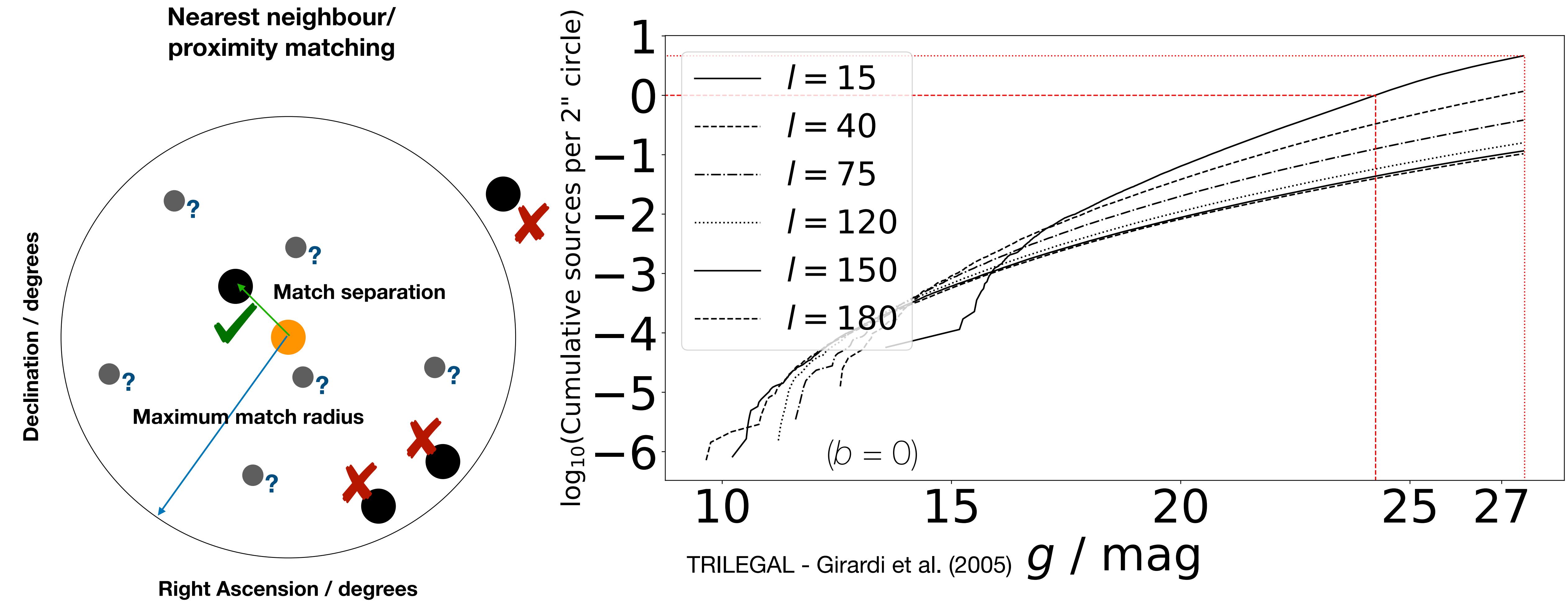
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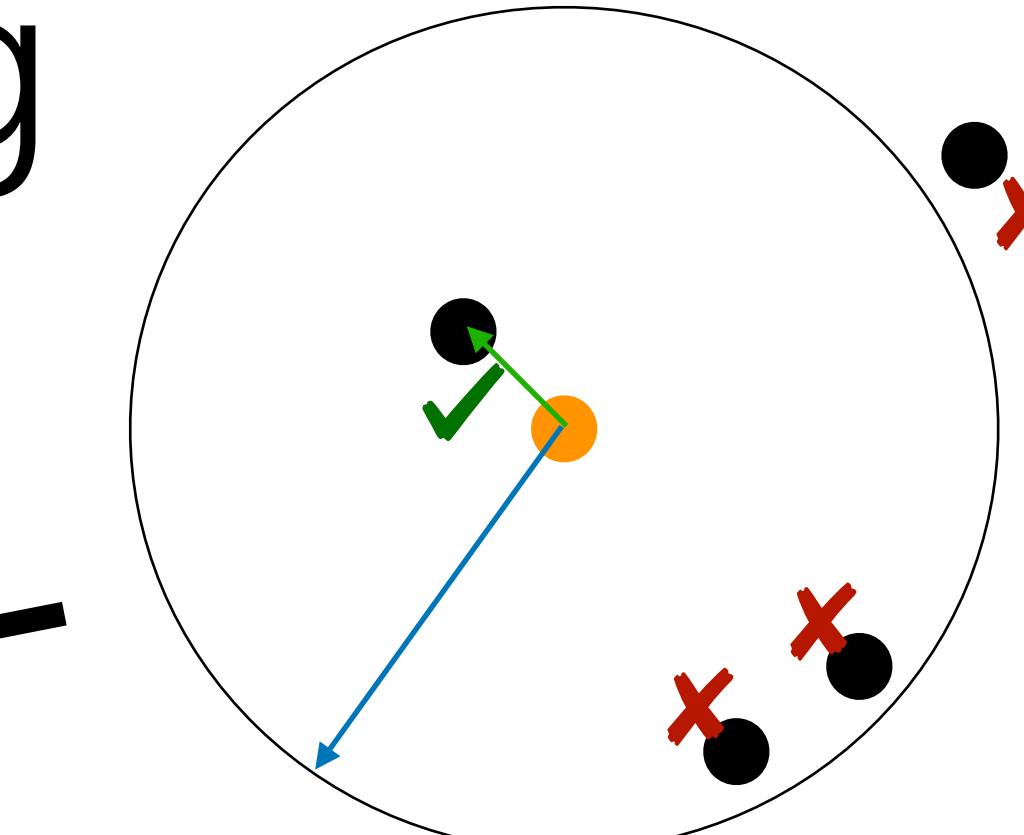
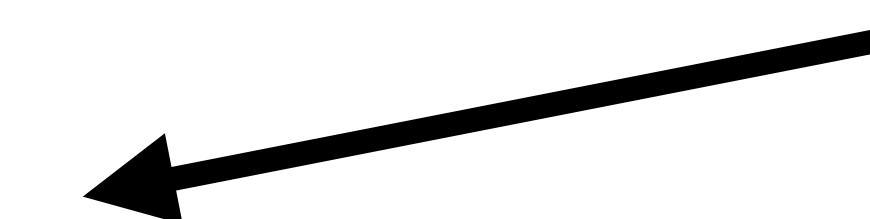
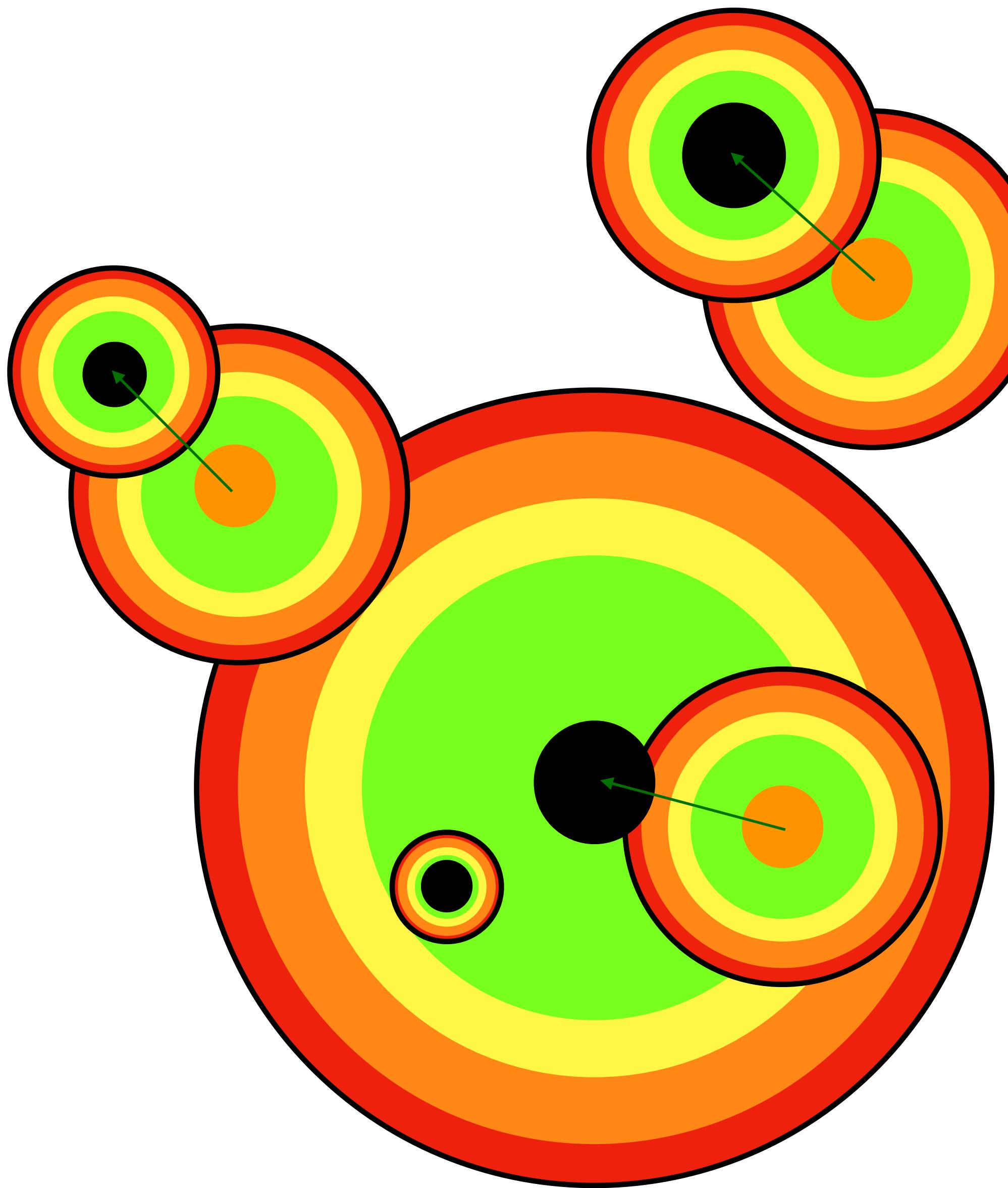
“Simple” Cross-Matching



The Problem With Rubin Obs.'s LSST



Probabilistic Cross-Matching



Probability of two sources having their on-sky separation given the hypothesis they are counterparts

$$P(\zeta, \lambda, k | \gamma, \phi) = \frac{1}{K} \times \prod_{\delta \notin \zeta \cap \delta \in \gamma} N_\gamma f_\gamma^\delta \prod_{\omega \notin \lambda \cap \omega \in \phi} N_\phi f_\phi^\omega \prod_{i=1}^k N_c G_{\gamma\phi}^{\zeta_i \lambda_i} c_{\gamma\phi}^{\zeta_i \lambda_i}$$

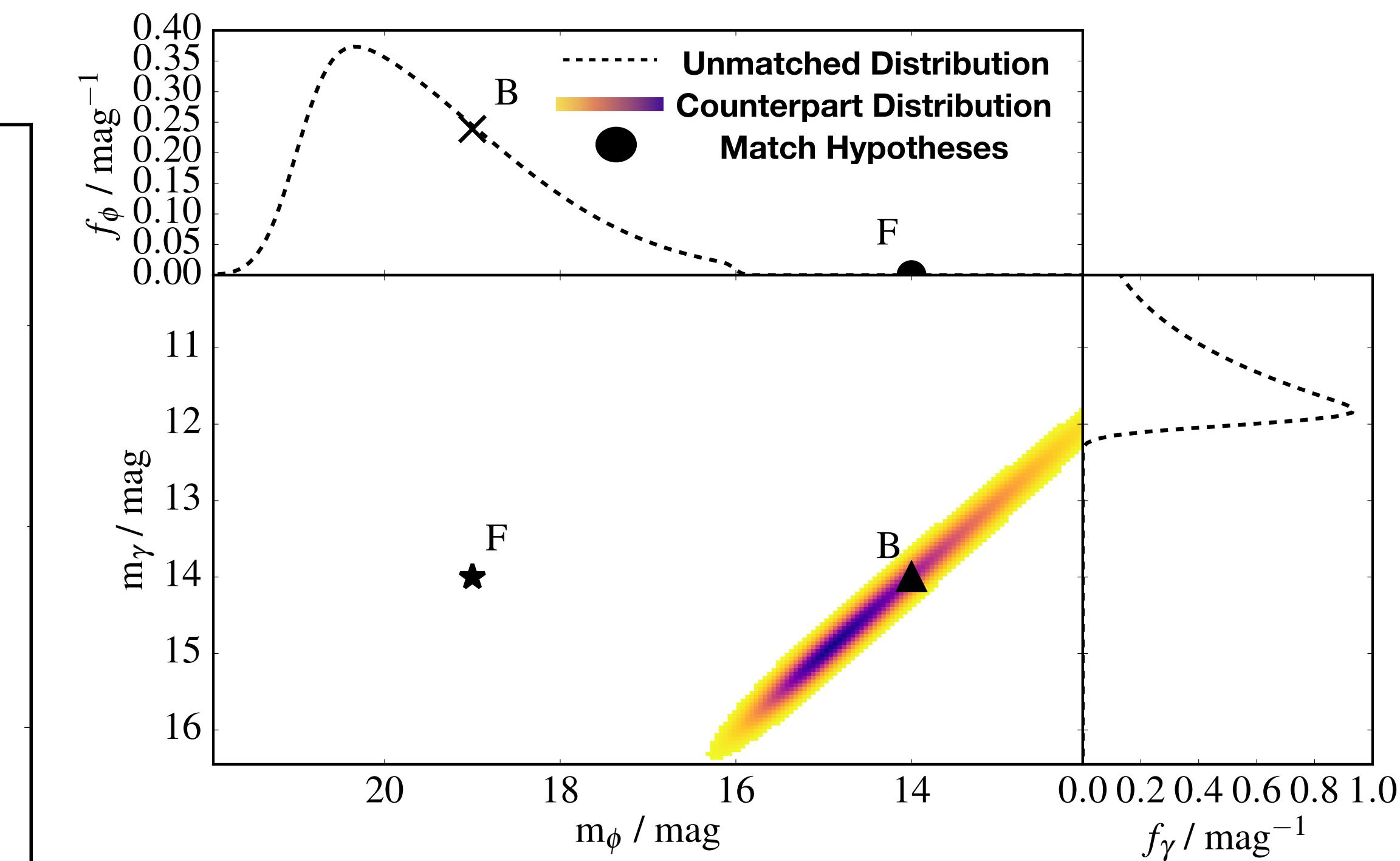
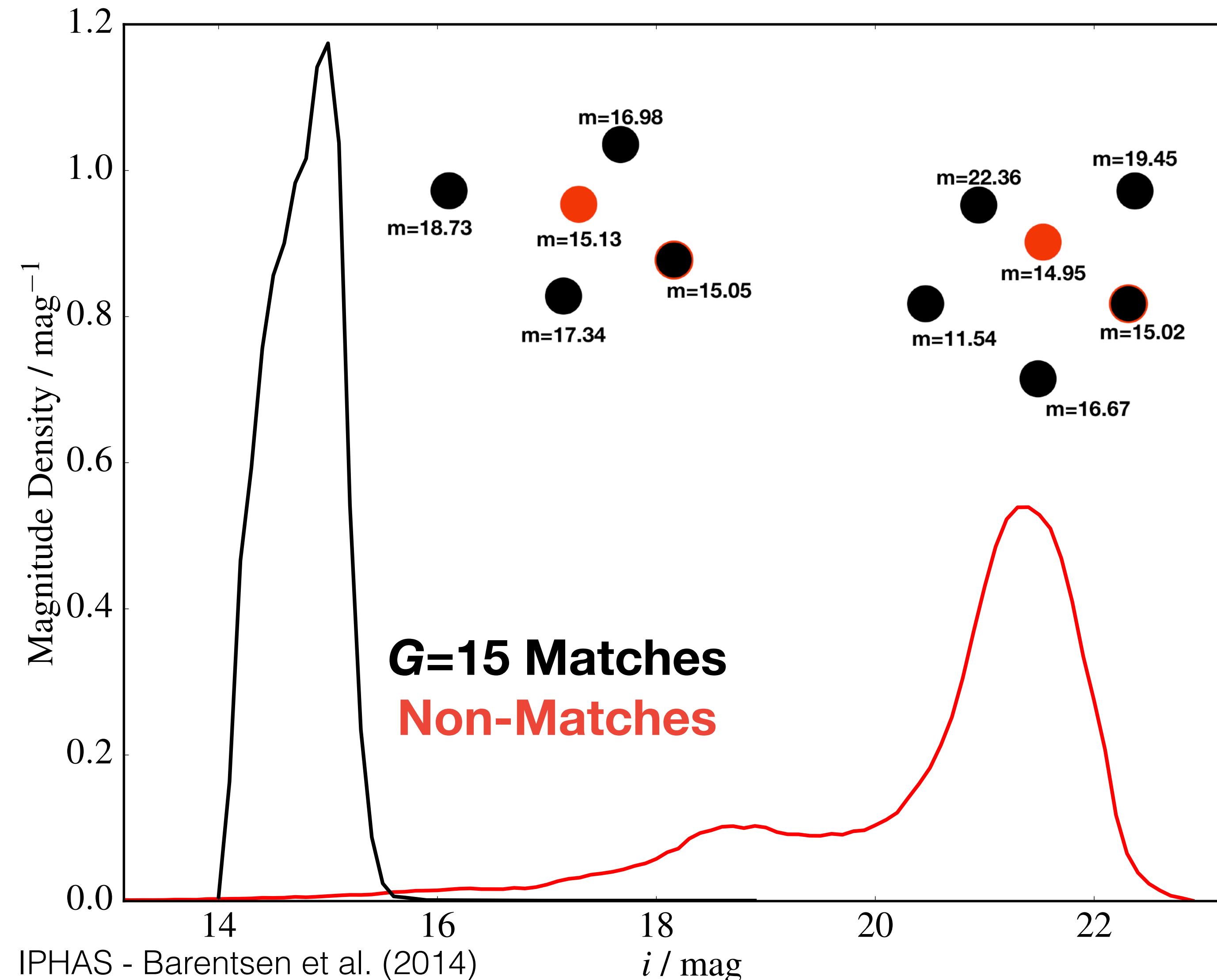
Wilson & Naylor (2018a)

Probability of sources having their brightnesses given they are unrelated to one another (“field stars”)

Probability of sources having their brightnesses given they are counterparts

Including Magnitude Information: Rejecting False Positives

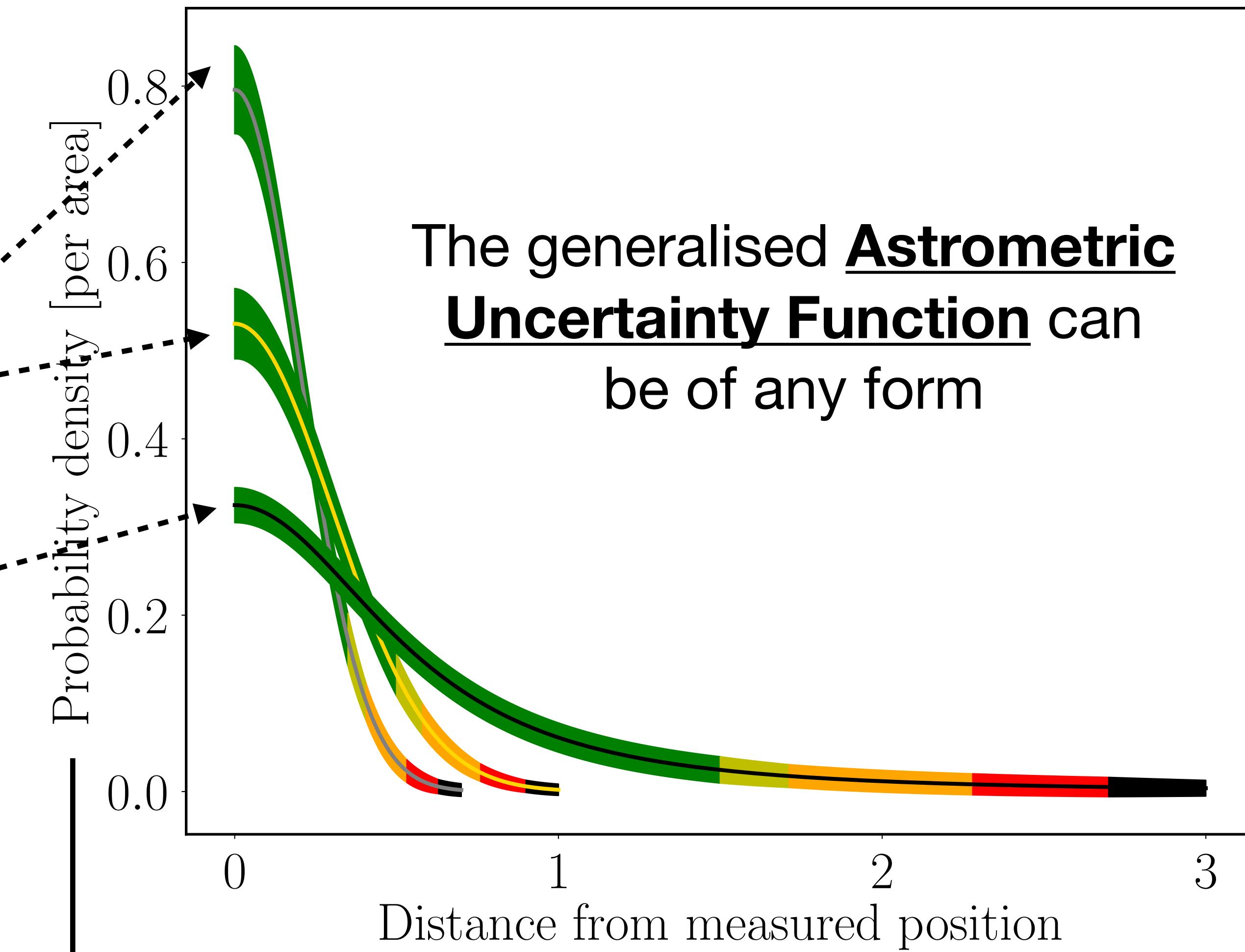
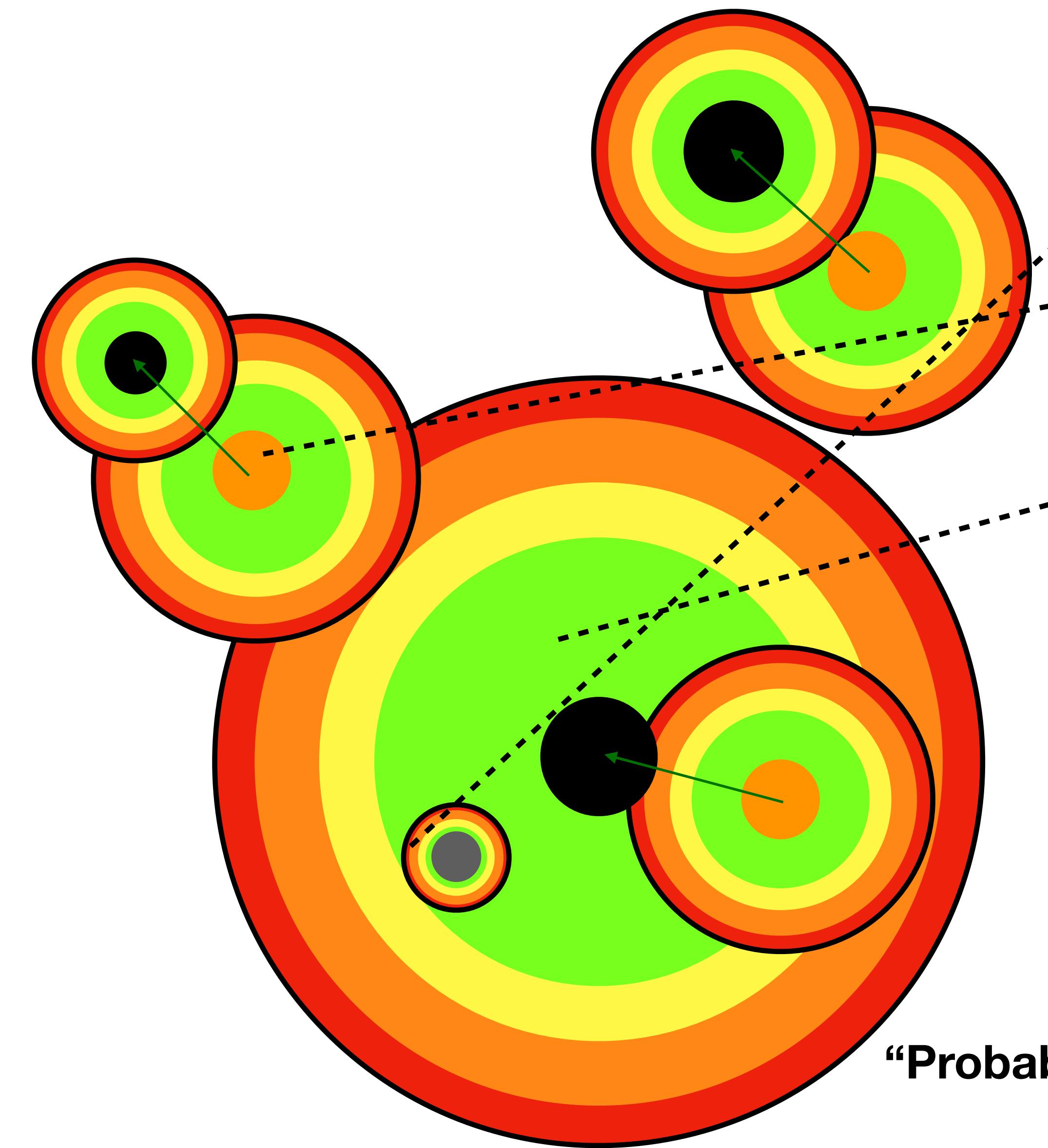
$$P(\zeta, \lambda, k | \gamma, \phi) = \frac{1}{K} \times \prod_{\delta \notin \zeta \cap \delta \in \gamma} N_\gamma f_\gamma^\delta \prod_{\omega \notin \lambda \cap \omega \in \phi} N_\phi f_\phi^\omega \prod_{i=1}^k N_c G_{\gamma\phi}^{\zeta_i \lambda_i} c_{\gamma\phi}^{\zeta_i \lambda_i}$$



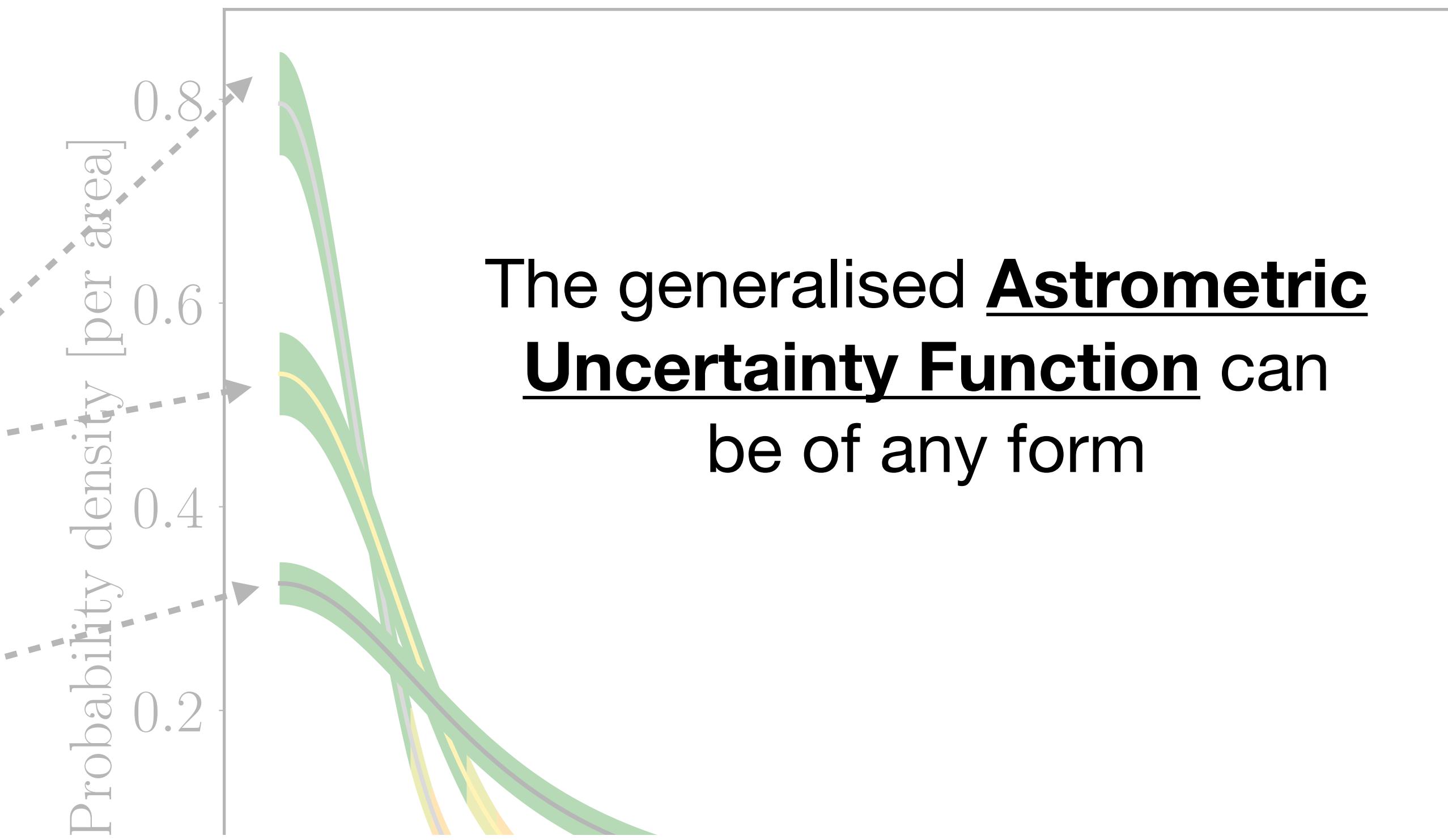
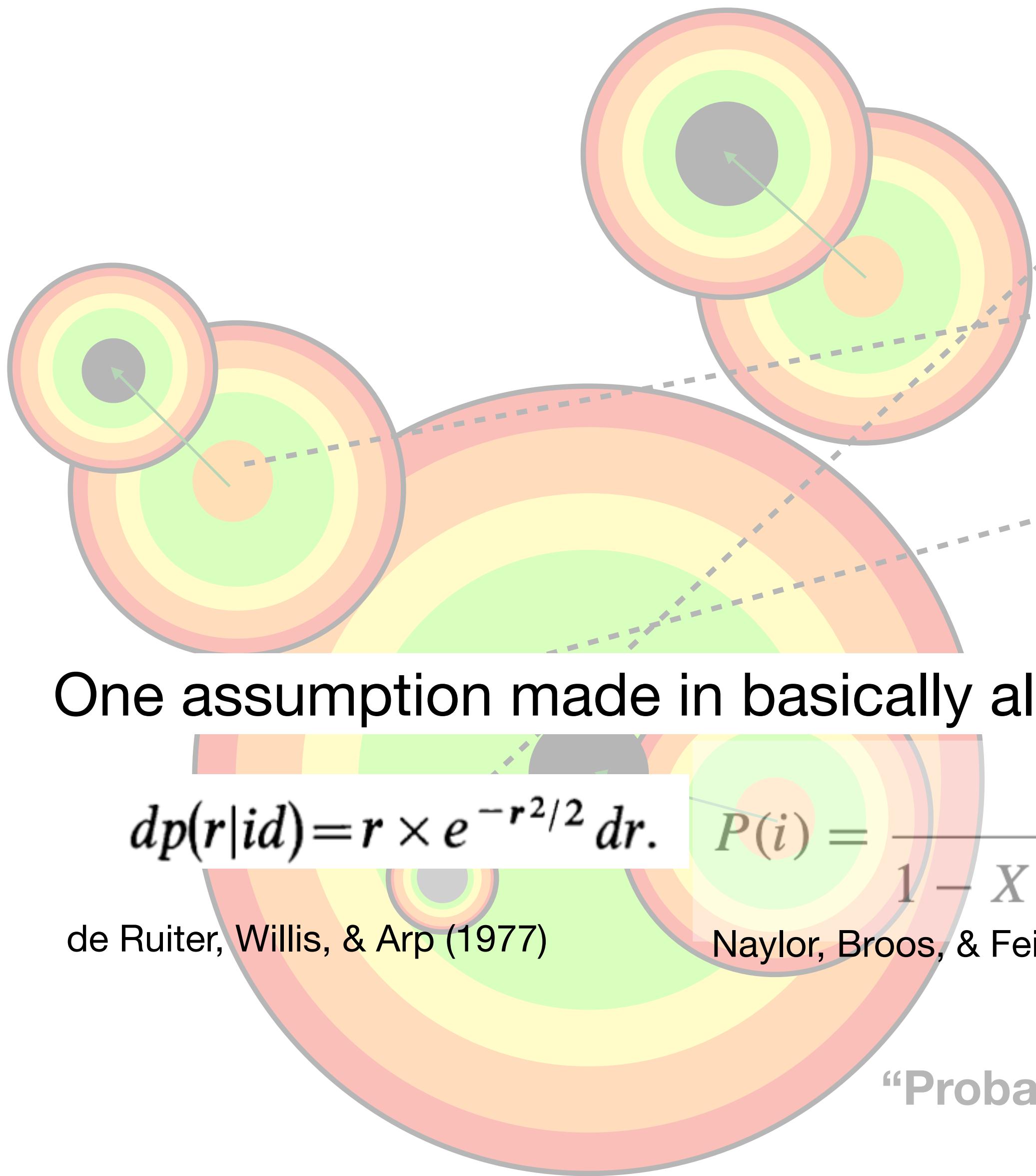
Wilson & Naylor (2018a)

The photometry-based likelihoods (c and f) allow us to mitigate high false positive rate in crowded fields, but now we need the position-based likelihood G

Probabilistic Cross-Matching: the AUF



Probabilistic Cross-Matching: the AUF



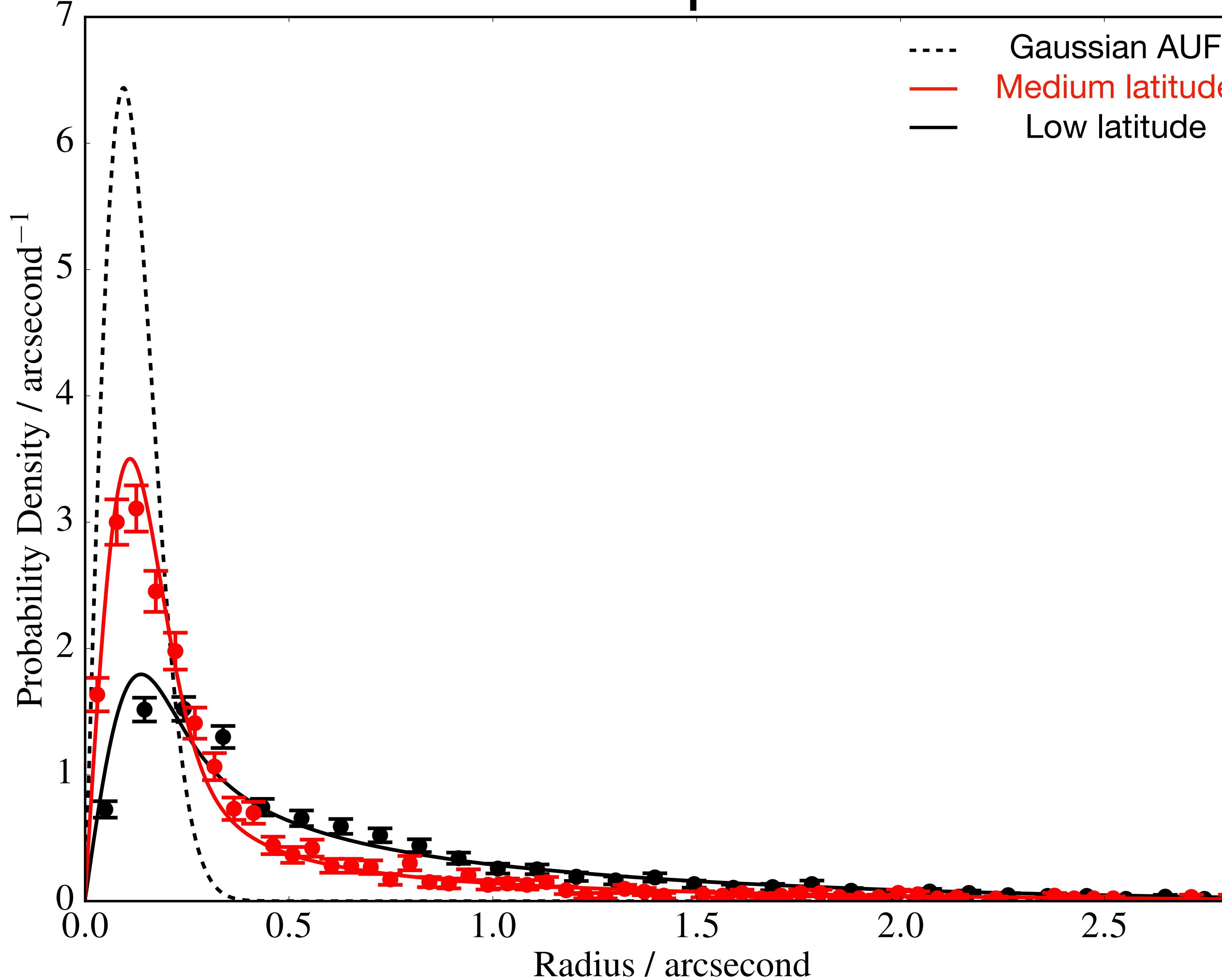
The generalised **Astrometric Uncertainty Function** can be of any form

$$p(D|H) = \int p(\mathbf{m}|H) \prod_{i=1}^n p_i(\mathbf{x}_i|\mathbf{m}, H) d^3 m$$

$\frac{\frac{Xc(m_i) g(\Delta x_i, \Delta y_i)}{Nf(m_i)}}{1 - X + \sum_j \frac{Xc(m_j) g(\Delta x_j, \Delta y_j)}{Nf(m_j)}}$ Distance from measured position

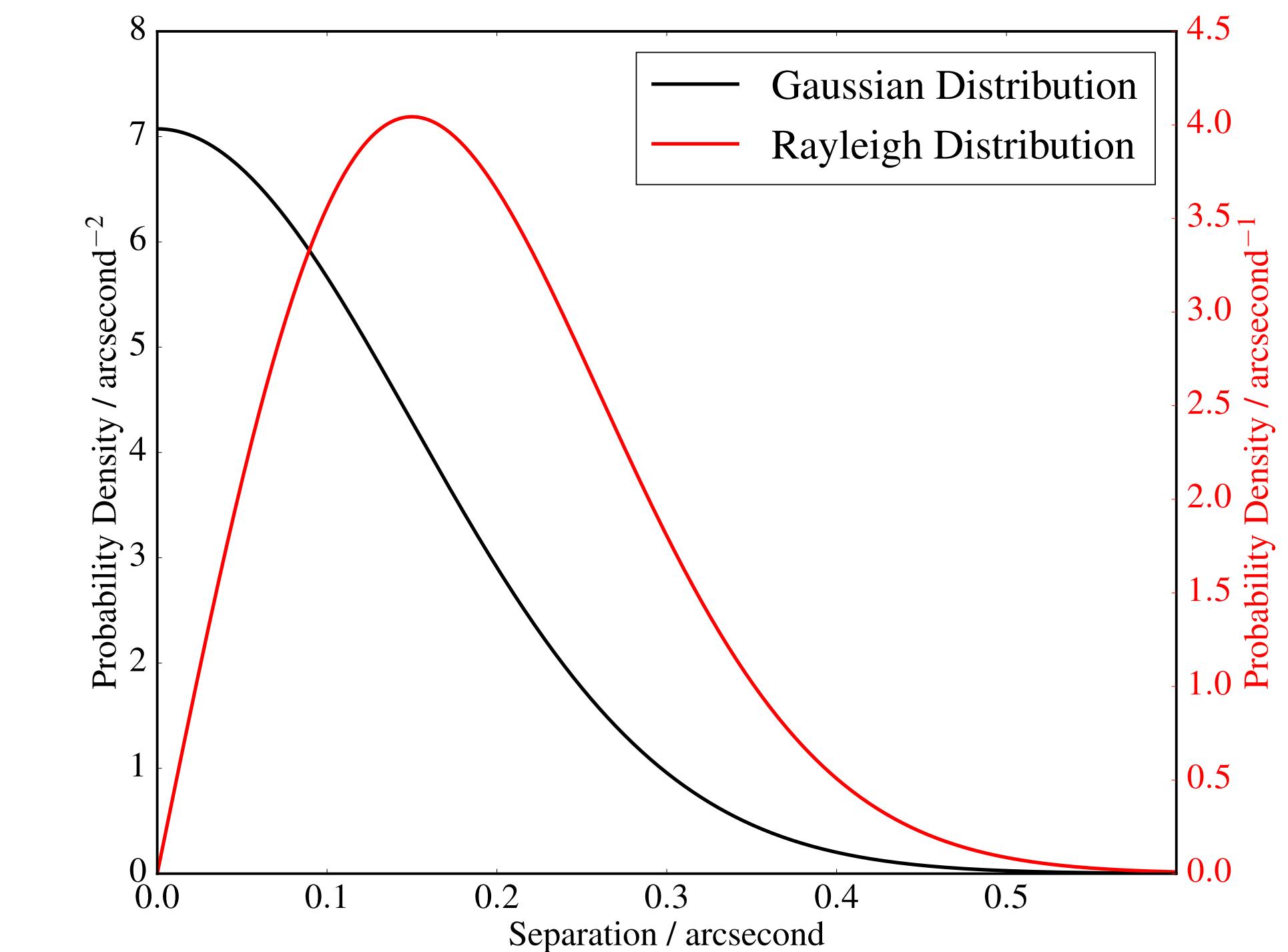
Budavári & Szalay (2008)

Additional Components of the AUF

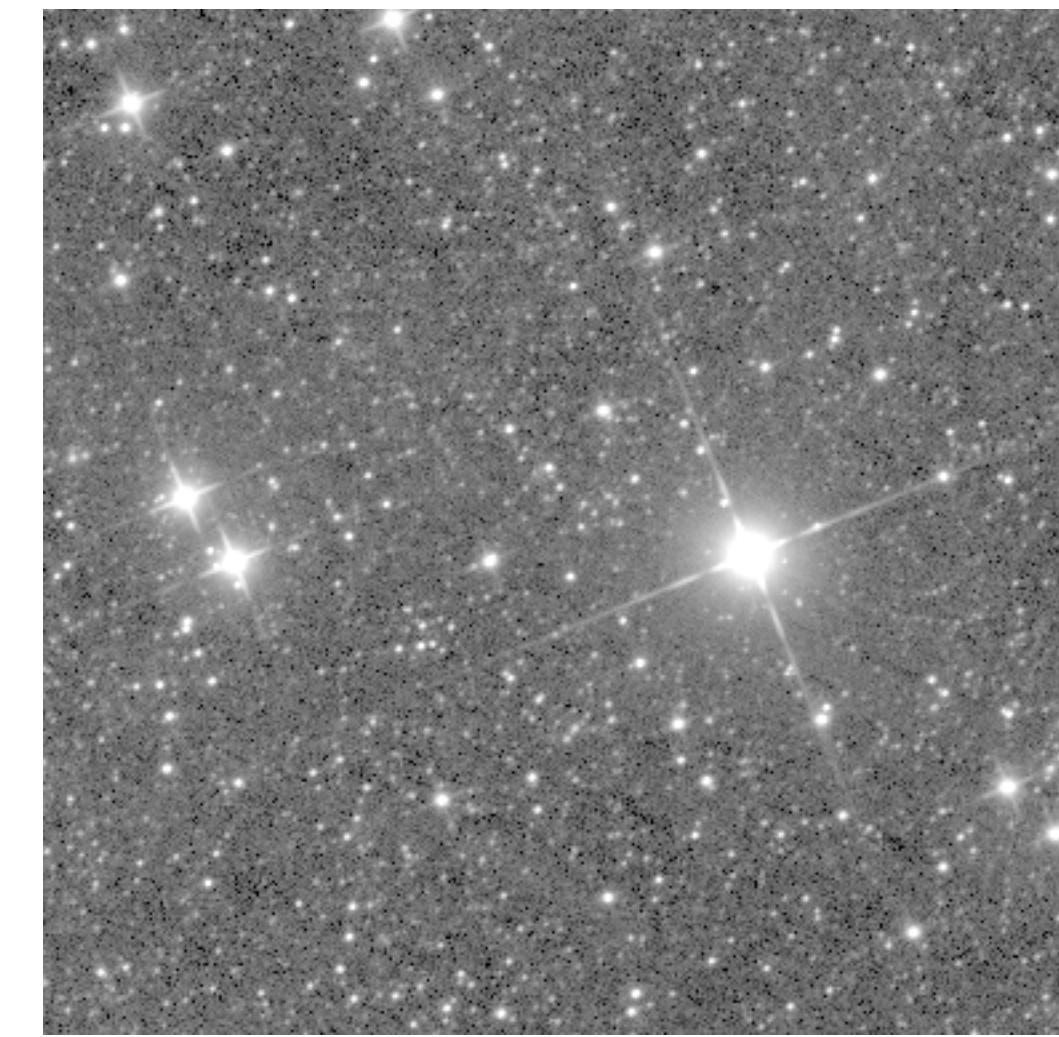
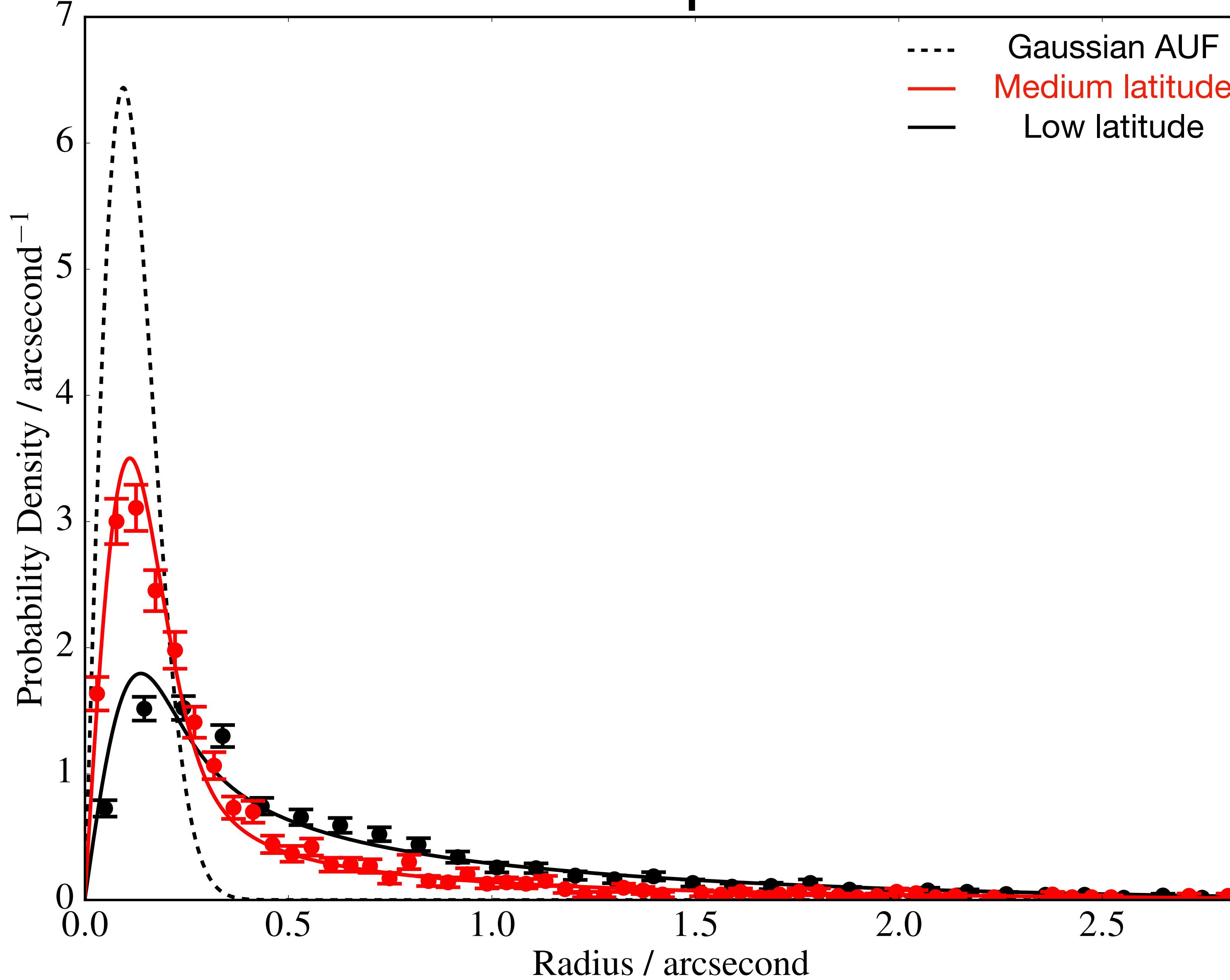


$$g(x, y, \sigma) = (2\pi\sigma^2)^{-1} \exp\left(-\frac{1}{2}\frac{x^2 + y^2}{\sigma^2}\right)$$

$$g(r, \sigma) = \frac{r}{\sigma^2} \exp\left(-\frac{1}{2}\frac{r^2}{\sigma^2}\right)$$

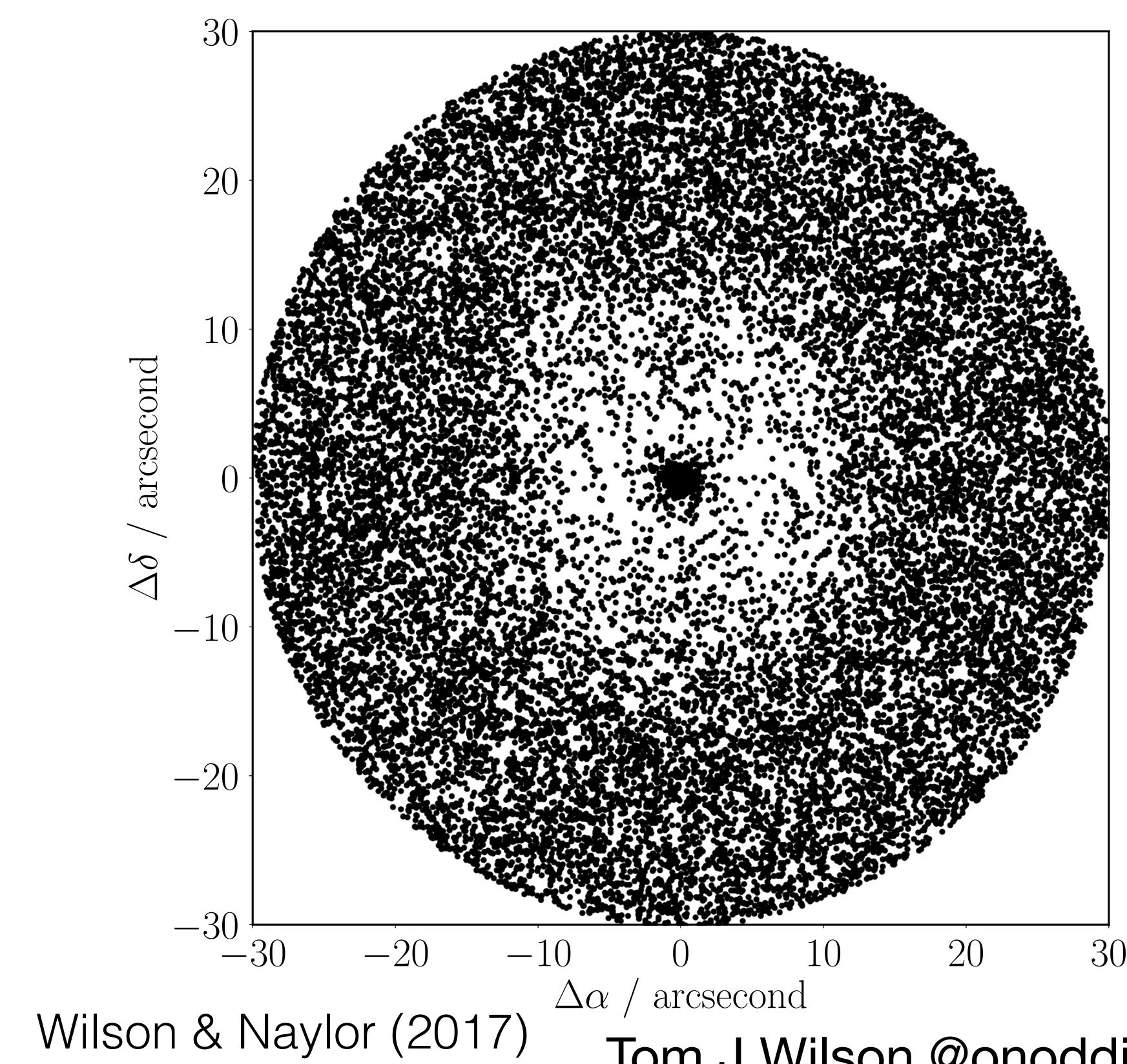
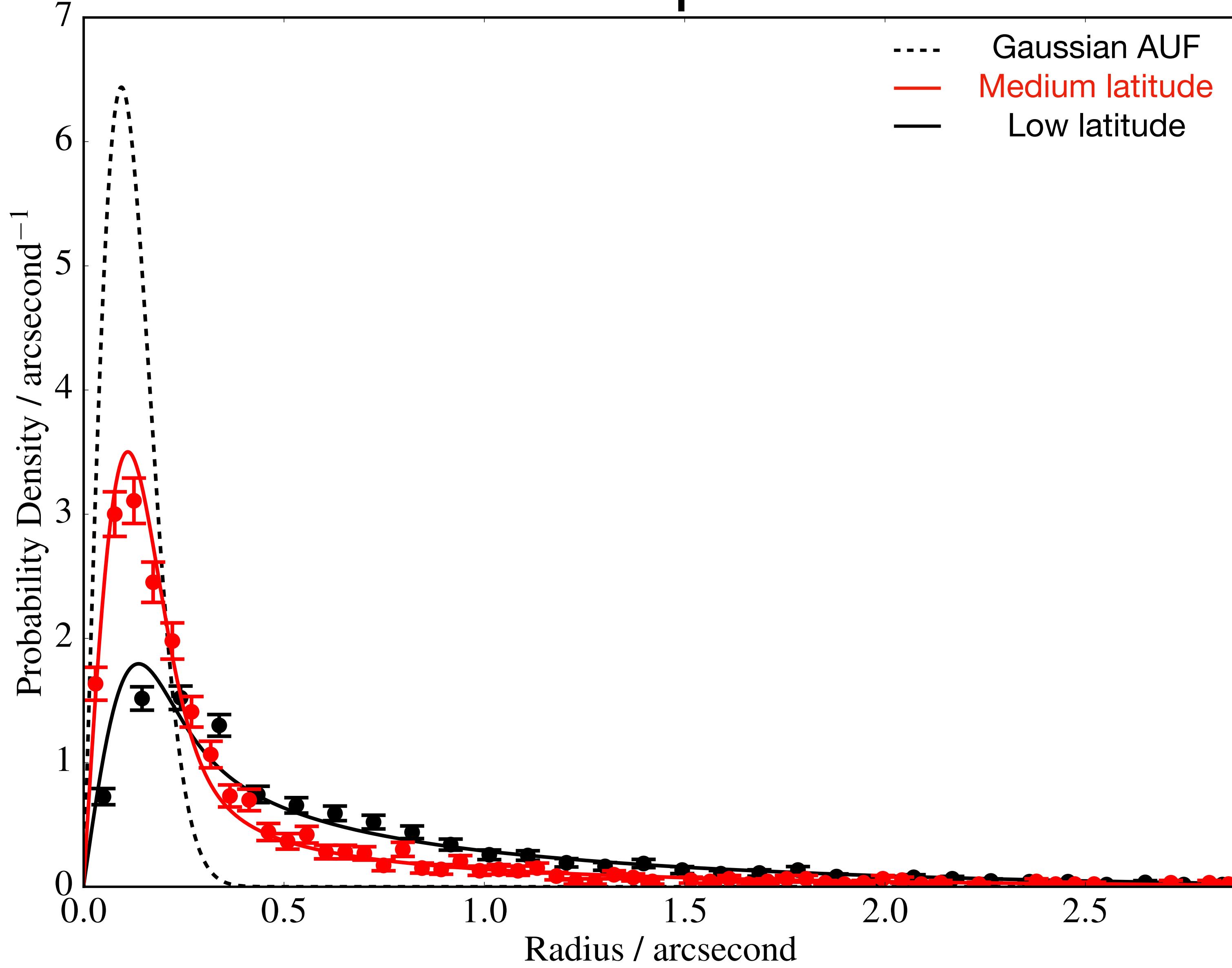


Additional Components of the AUF



Additional Components of the AUF

(and any other systematic — e.g. proper motions, cf. Wilson 2023, RASTI)



WISE - Wright et al. (2010)

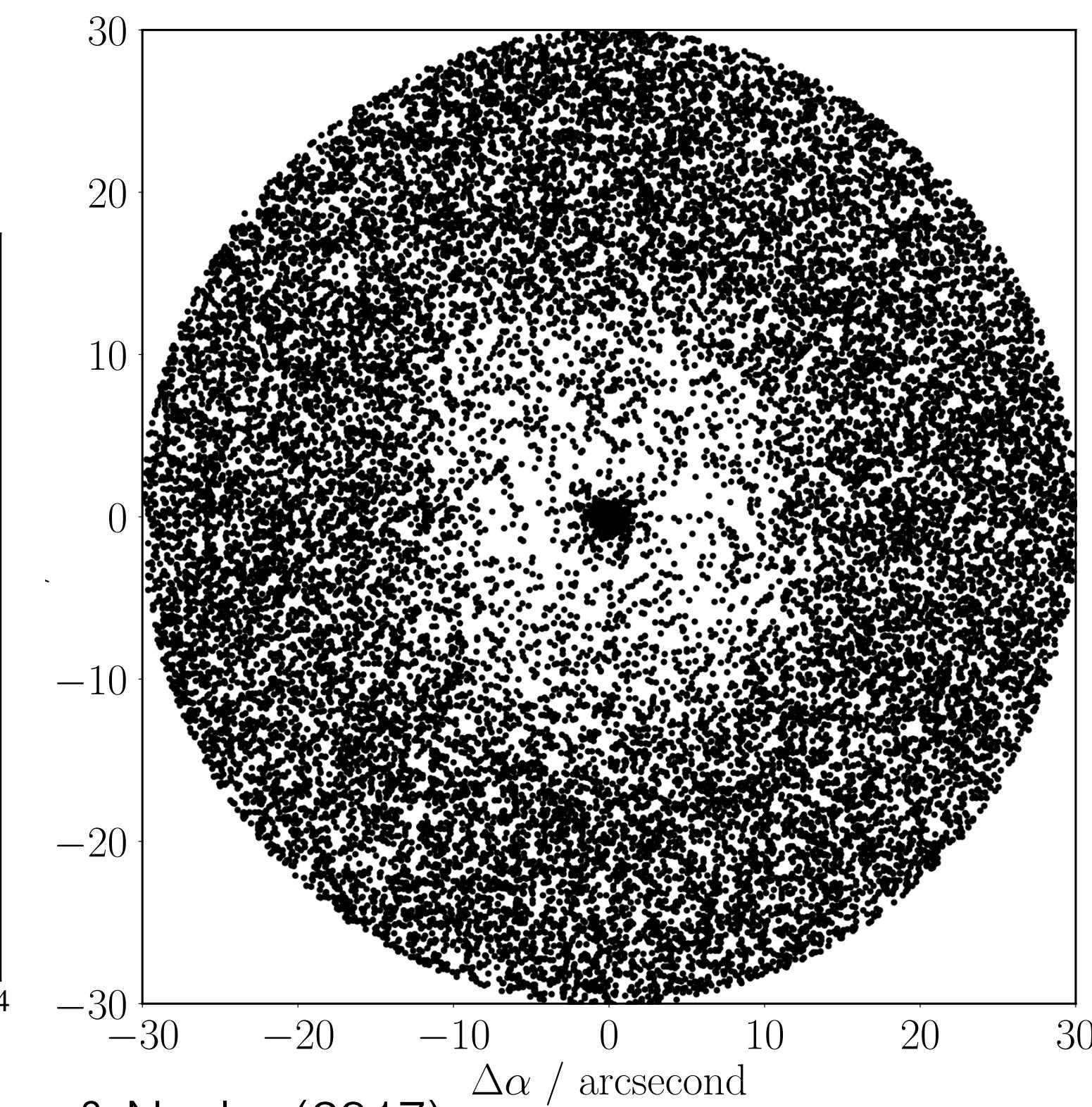
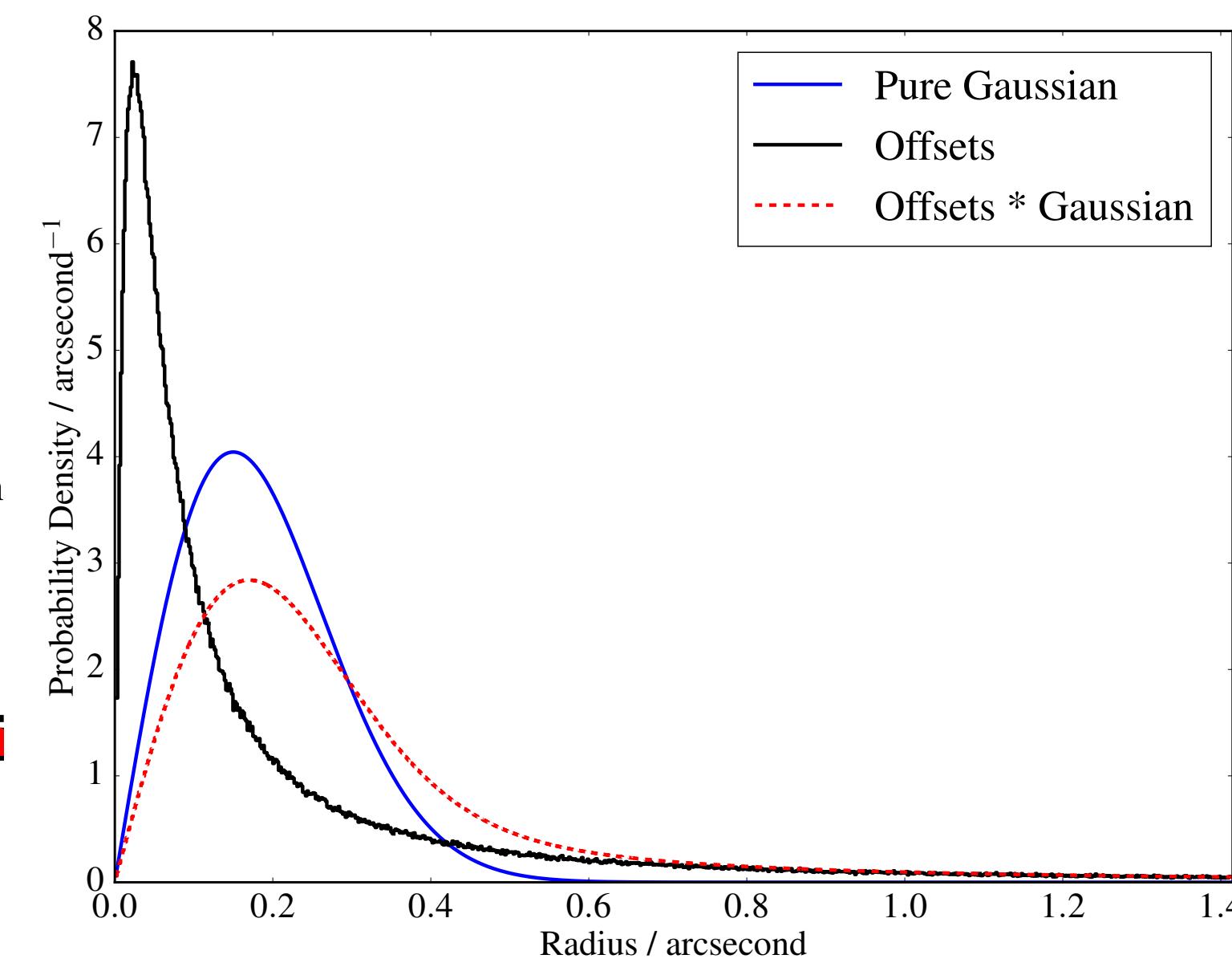
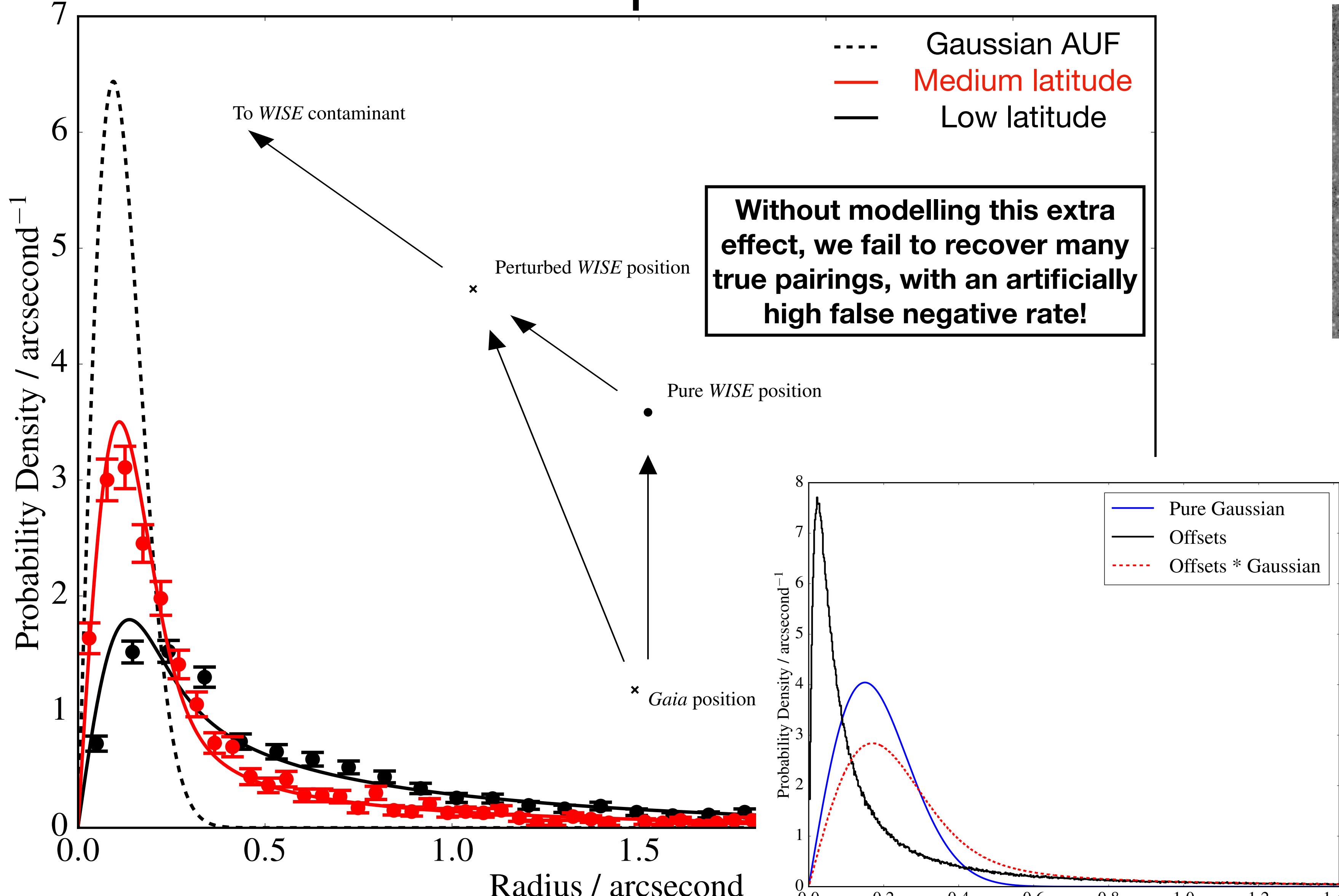
Gaia DR2 - Gaia Collaboration, Brown A. G. A., et al. (2018)

Wilson & Naylor (2017)

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Additional Components of the AUF

(and any other systematic – e.g. proper motions, cf. Wilson 2023, RASTI)

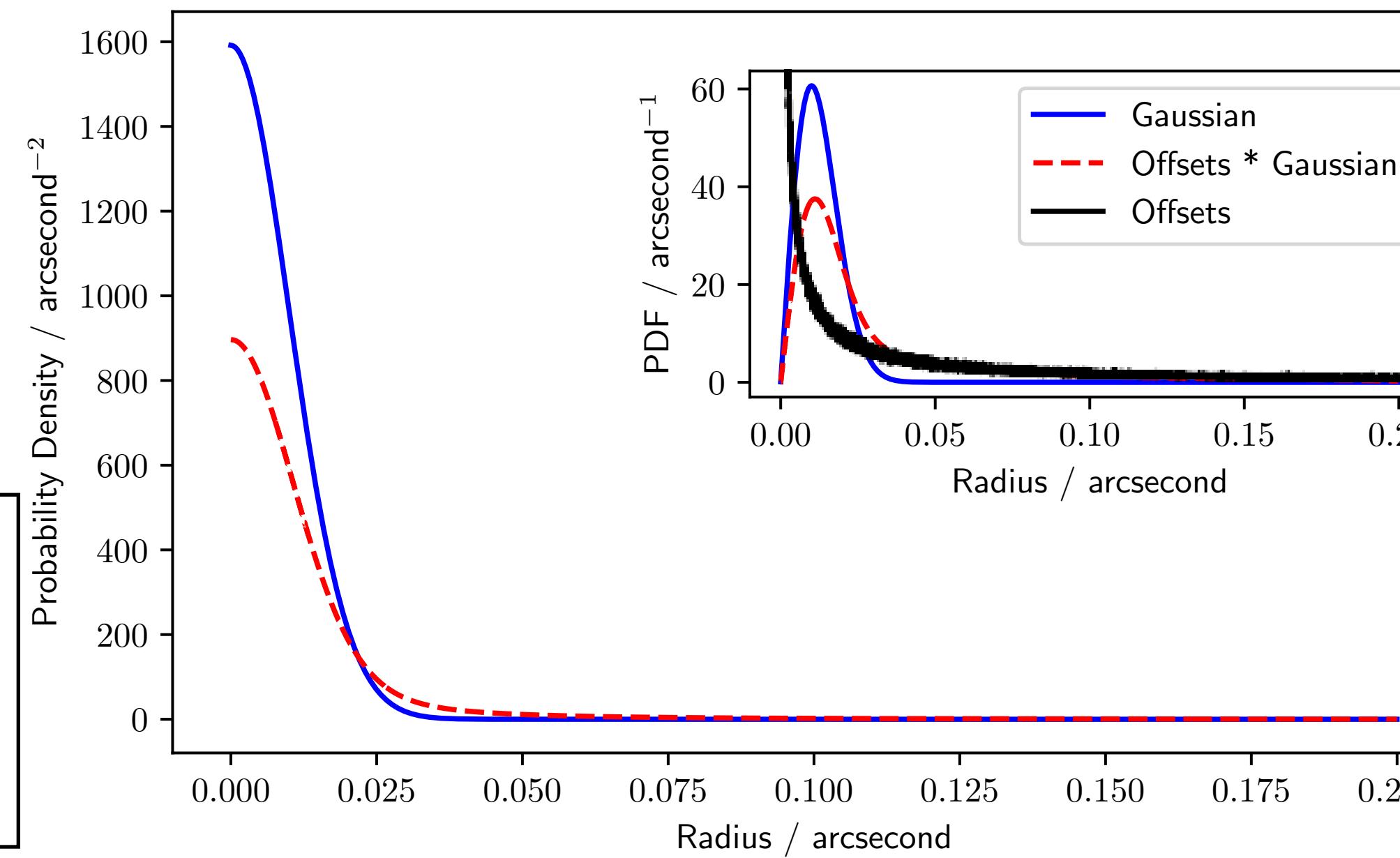


The Rubin AUF: Galactic Plane

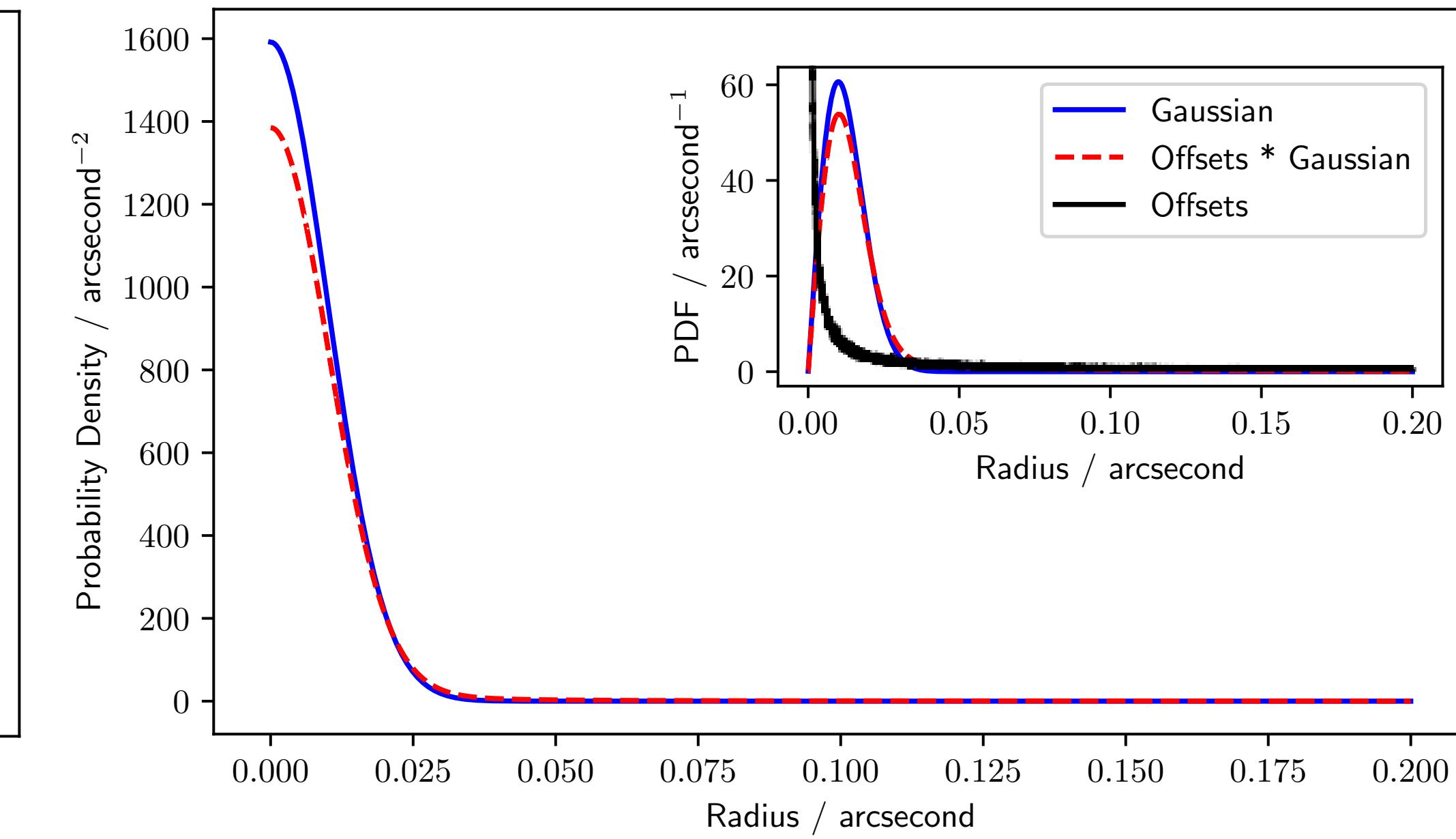
Galactic Centre

Single-visit

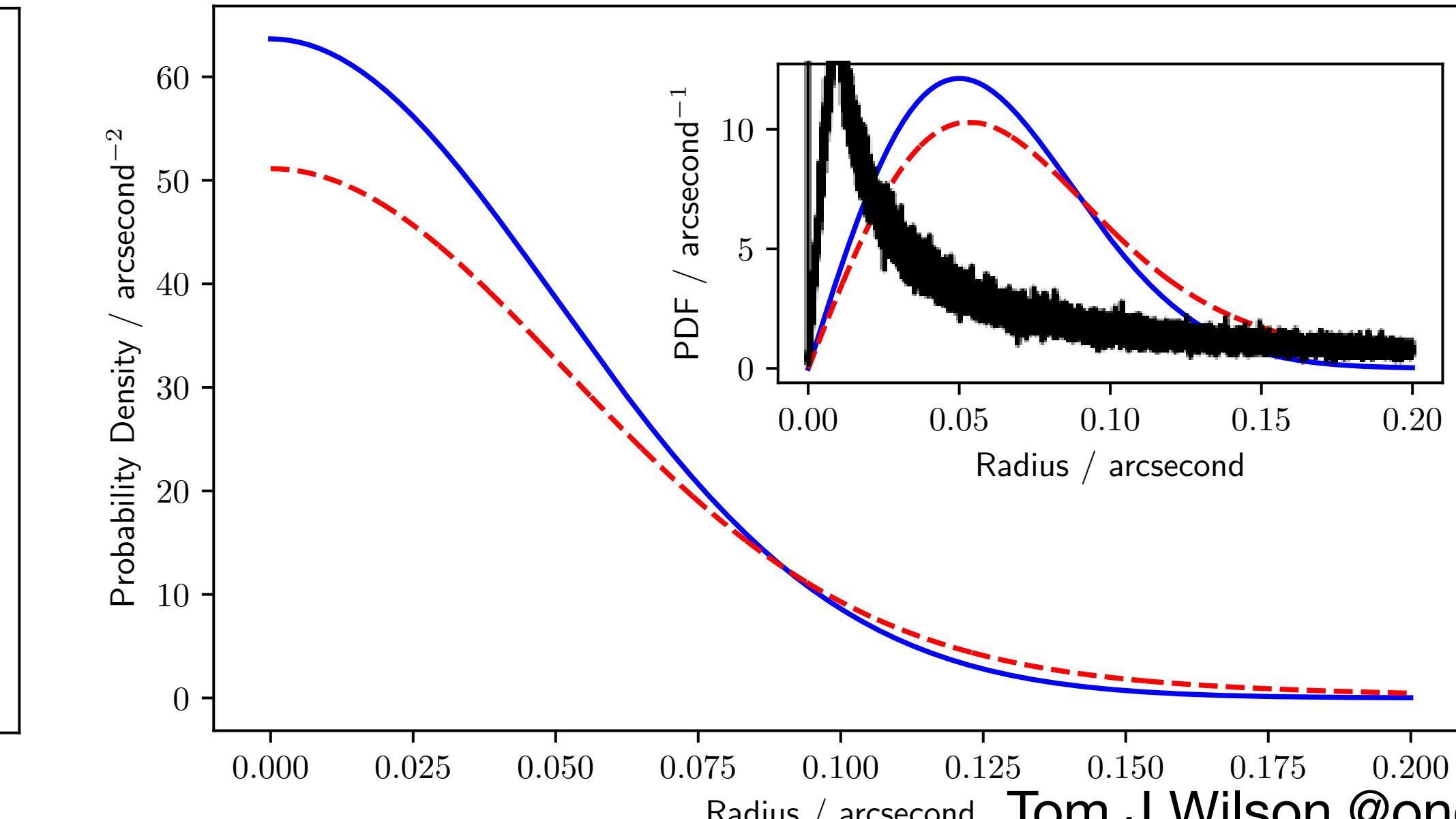
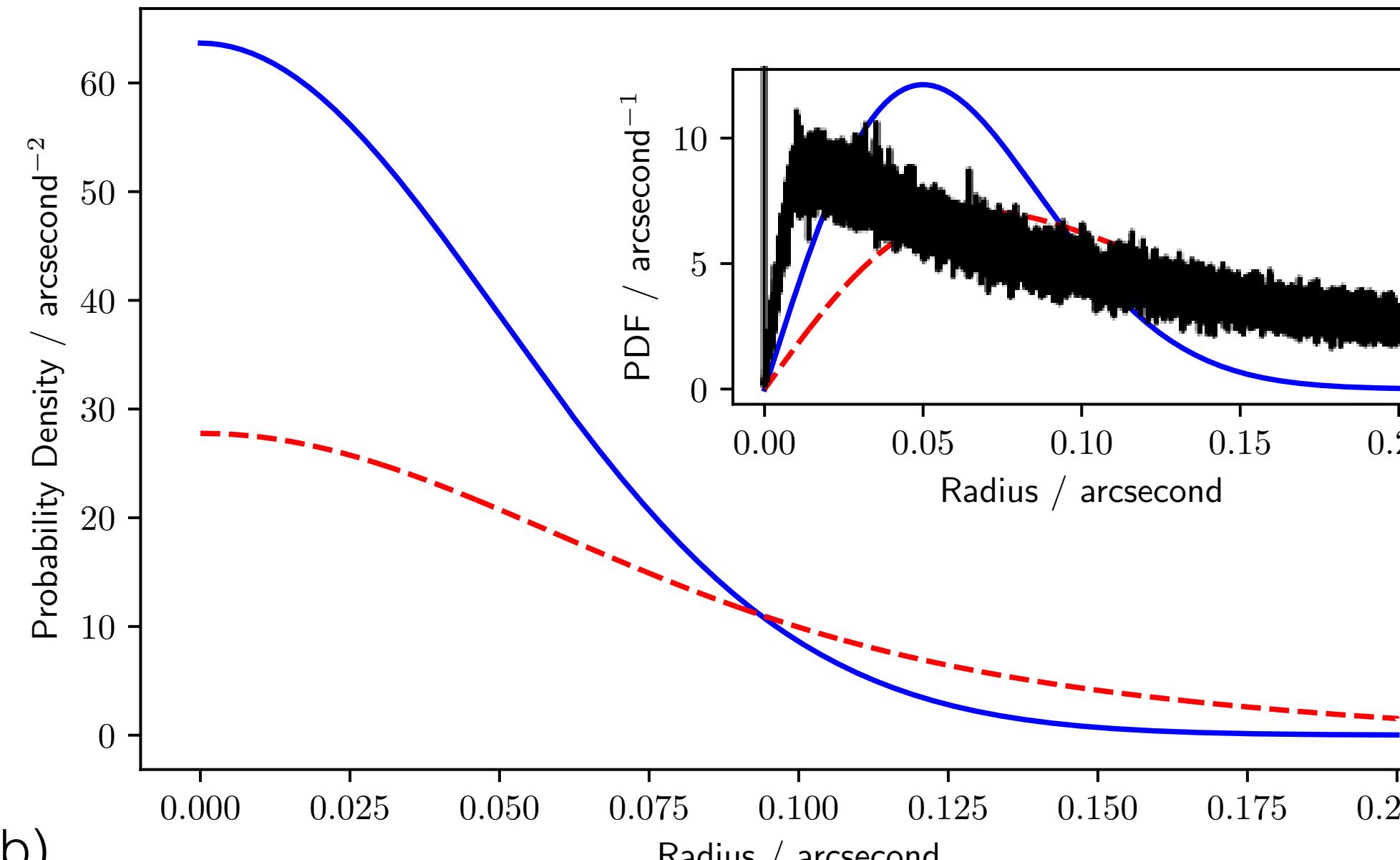
**Without modelling
this extra effect, we
fail to recover many
true pairings, with an
artificially high false
negative rate!**



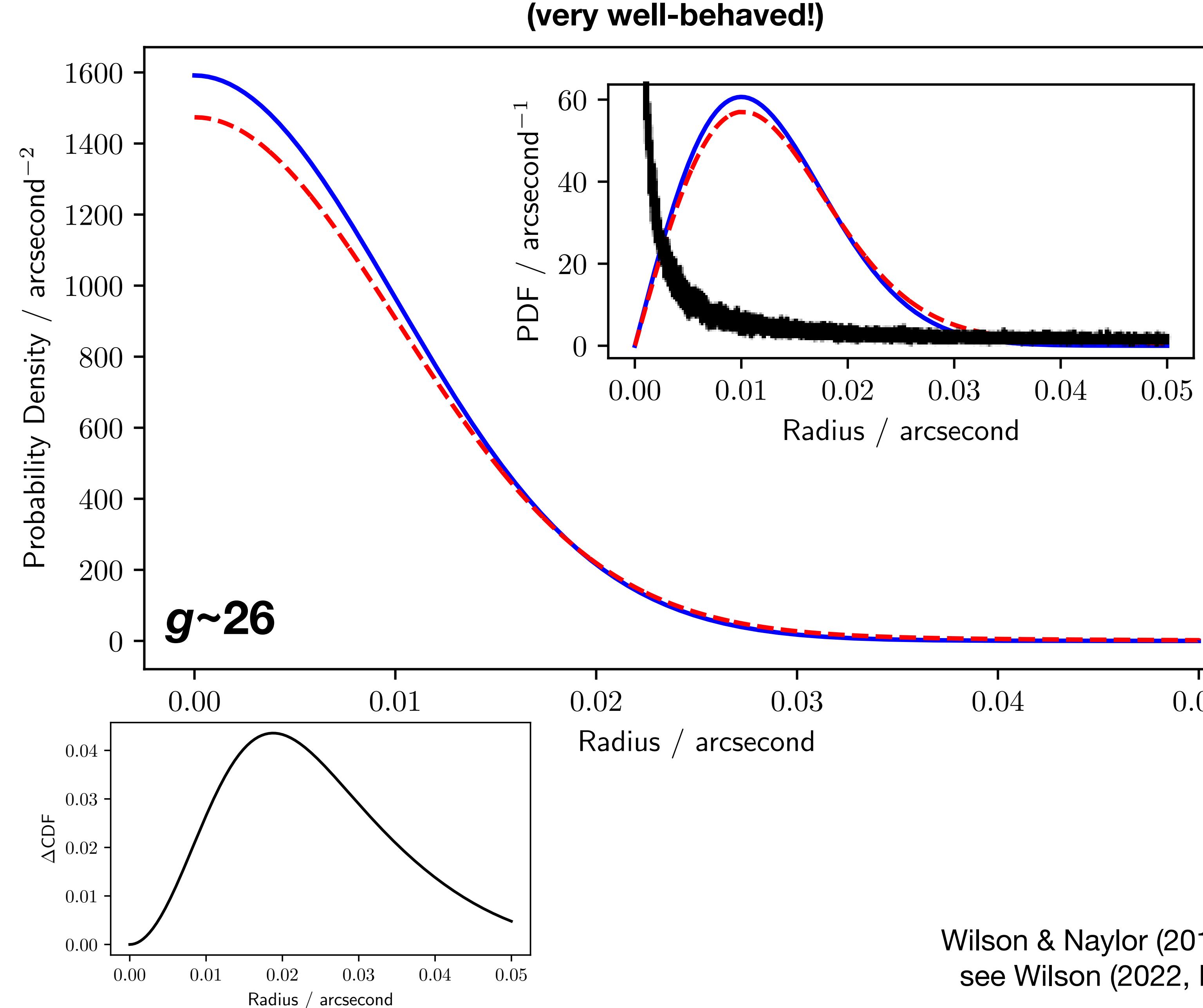
Not the Galactic Centre



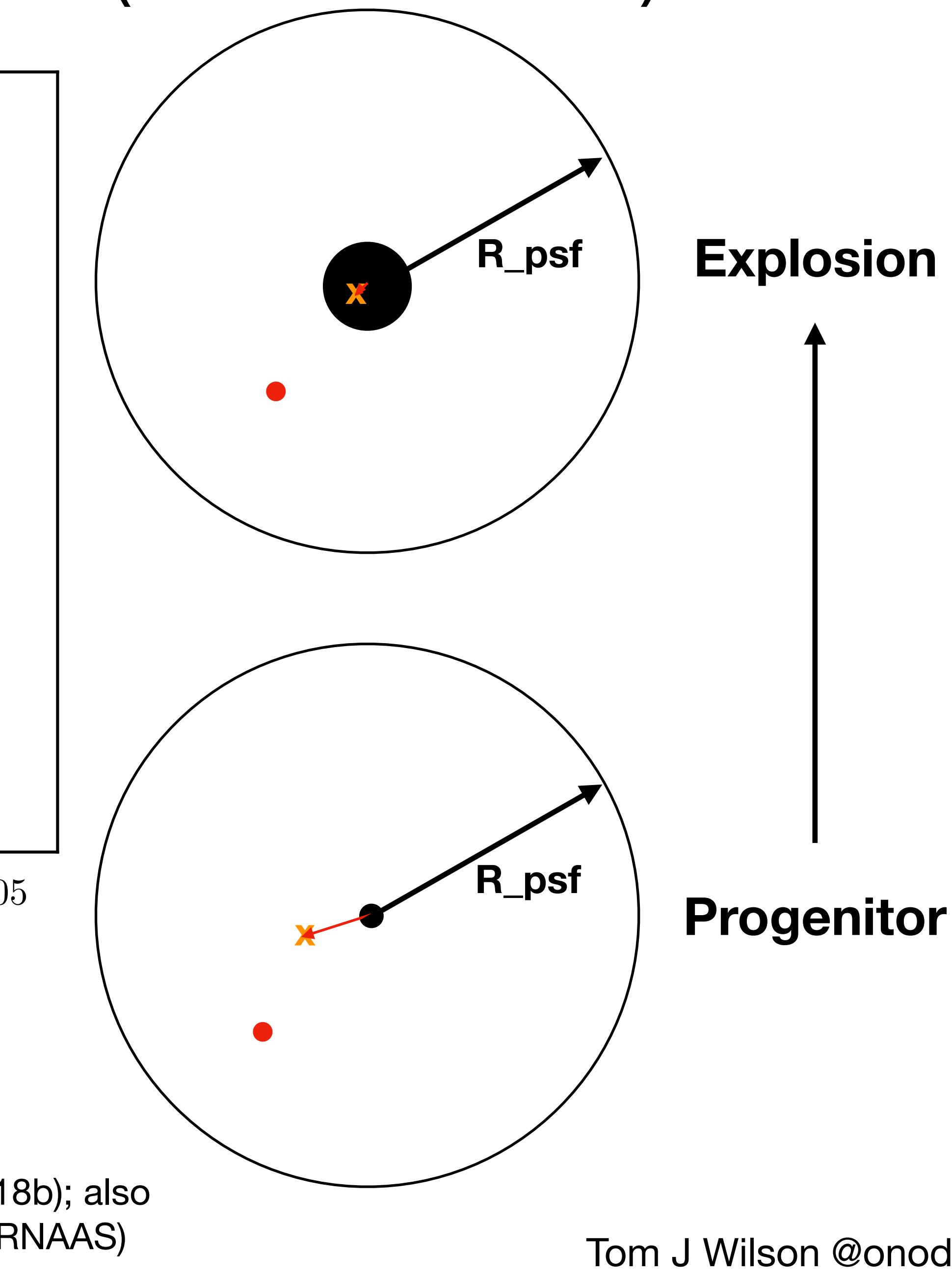
Co-add



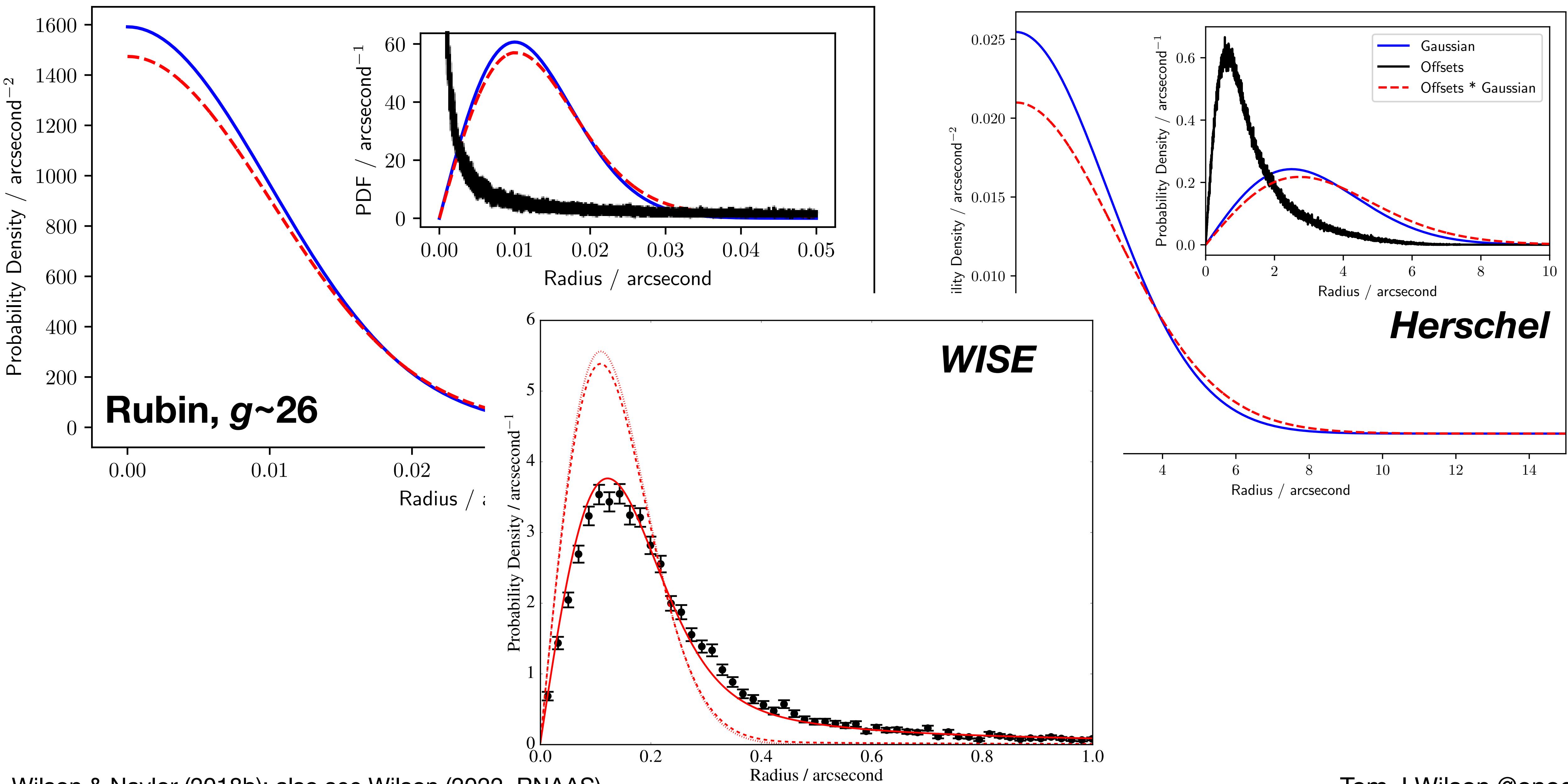
The Rubin AUF: \checkmark Extra-Galactic (Transients)



Wilson & Naylor (2018b); also
see Wilson (2022, RNAAS)

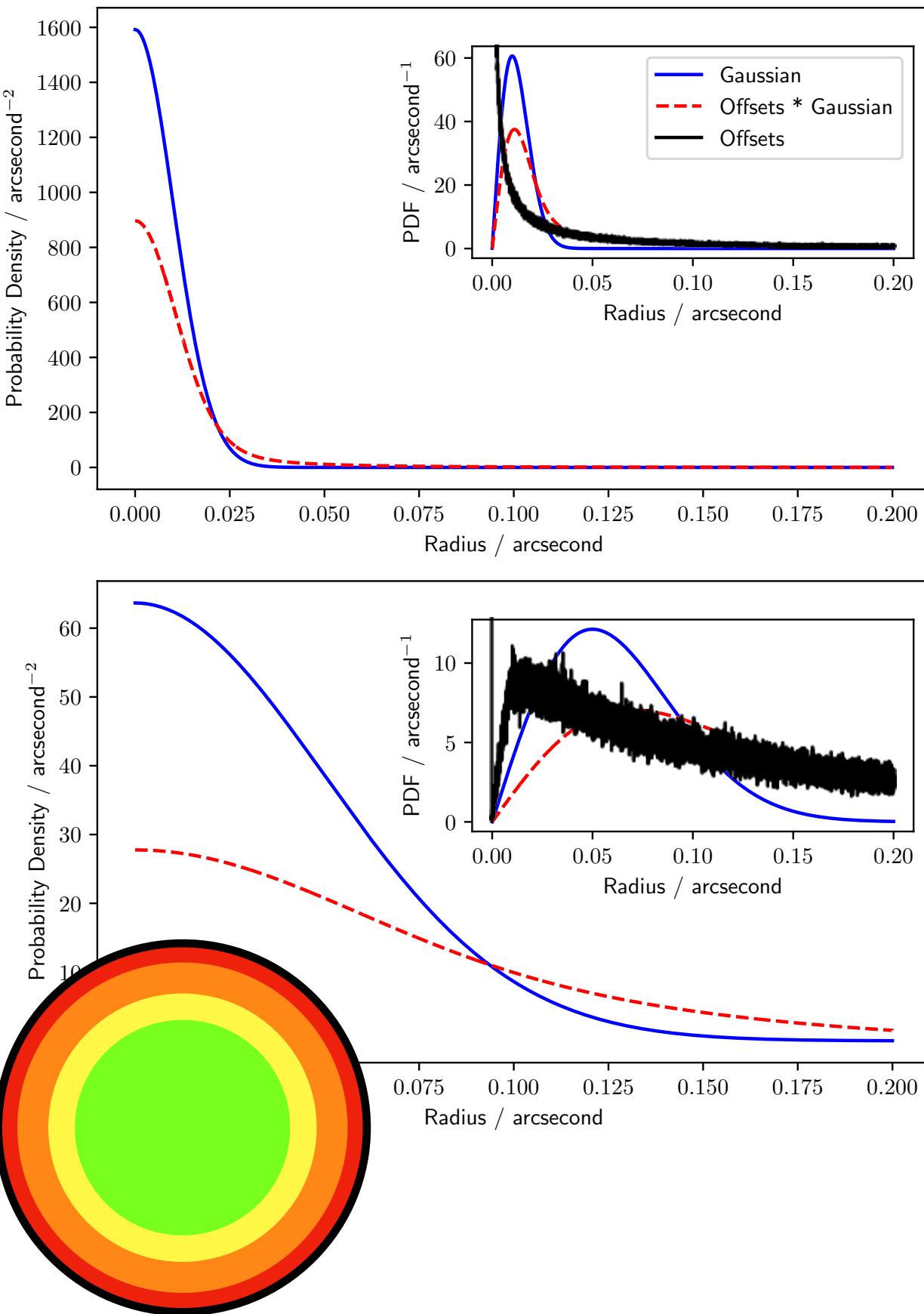


The Rubin AUF: Extra-Galactic (Transients)



Conclusions

- Our cross-match algorithms include two key elements to avoid issues with crowded & confused data
 - A generalised approach to the Astrometric Uncertainty Function allows for the full inclusion of the effects of perturbation due to blended sources — reduce false -ves!
 - Where it can be applied (i.e., the static sky) use of (two-sided) photometry to sort out multiplicity of higher resolution data — reduce false +ves!
- Software package macauff developed to cross-match catalogues, including the effect of unresolved contaminant sources (and rejection of interloper objects using photometry in the static sky)
 - Developed through an IKC to Rubin/LSST:UK, matches planned to *Gaia*, *WISE*, *VISTA*, *SDSS*, ...
 - We have compute time to cross-match datasets — let me know your favourite combo, and what you need matched (to LSST or otherwise)!
- Incorporating this extension of position uncertainty into real-time matches allows for more robust counterpart identification in the alert stream and a more accurate and precise transient SED
 - Furthermore, we can provide *statistical* information on the level of photometric contamination unresolved contaminant sources cause, which can be subtracted in a probabilistic framework!



The AUF does not need to, and in fact quite often should not, be Gaussian!



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Wilson & Naylor, 2017, MNRAS, 468, 2517
Wilson & Naylor, 2018a, MNRAS, 473, 5570
Wilson & Naylor, 2018b, MNRAS, 481, 2148

Wilson, 2022, RNAAS, 6, 60

Wilson, 2023, RASTI, 2, 1

<https://github.com/Onoddil/macaff>



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