

The Monte Carlo Tracer

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Abstract

In γ ray and cosmic ray astronomy it needs dedicated simulations of detectors to develop and run the instruments which observe particle interactions far beyond any energy accessible in the lab. The Monte Carlo Tracer exists since we do what we must, because we can.

Keywords: ray tracing, photon propagation

1. The scenery tree

1.1. The root of the scenery tree

The frame at the root of the tree structure represents the whole scenery. Before ray tracing is performed on the scenery tree, all frames in the tree estimate their position and orientation w.r.t. the root frame. This way rays can easily and fast be transformed back and forth from the root tree to an individual object frame.

2. How to set up a scenery in source code

We will build a little scenery of a house with a roof and chimney as well as a simple tree. Further we add a small telescope with a reflective imaging mirror. First we will define the geometry and their surfaces, second we will declare the relations between them. Third and finally we will update all frames relation w.r.t. the root frame to enable fast tracing (post initializing). First we define the main frame of our scenery. The main frame, often called world, will be the root of the scenery tree 1.1.

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```

32 |   Frame world;
33 |   world.set_name_pos_rot("World", Vector3D::null, Rotation3D::null);

```

Second we define frames that hold individual structures like a tree which will be composed from several objects. The tree will be placed in $x = 5$ m w.r.t. its later mother frame, i.e. the world.

```

35 |   Vector3D tree_pos(5.0, 0.0, 0.0);
36 |   Frame tree;
37 |   tree.set_name_pos_rot("My_Tree", tree_pos, Rotation3D::null);
38 |
39 |   Color leaf_green(0, 128, 0);
40 |   Sphere leaf_ball;
41 |   leaf_ball.set_name_pos_rot("leaf_ball", Vector3D(0.0, 0.0, 2.0), Rotation3D::null);
42 |   leaf_ball.set_outer_color(&leaf_green);
43 |   leaf_ball.set_sphere_radius(0.5);
44 |
45 |   Color wood_brown(64, 64, 0);
46 |   Cylinder tree_pole;
47 |   tree_pole.set_name_pos_rot("tree_pole", Vector3D(0.0, 0.0, 0.5), Rotation3D::null);
48 |   tree_pole.set_outer_color(&wood_brown);
49 |   tree_pole.set_radius_and_length(0.1, 1.0);
50 |
51 |   tree.set_mother_and_child(&leaf_ball);
52 |   tree.set_mother_and_child(&tree_pole);

```

Also part of the tree is the wooden pole.

and the rest of the source...

3. Numerical functions

The `Function::Func1D` class provides 1D mapping for floating numbers.

$$y = f(x) \tag{1}$$

$$x \in X \tag{2}$$

All functions have limits which need to be respected. Any call of a function $f(x)$ with $x \notin X$ will throw an exception. We are strict about this behaviour to enforce that no propagation passes silently where e.g. your mirror's reflective index is only defined up to 600 nm but you shoot 800 nm photons onto it. Functions live in their own namespace.

```
83 | using namespace Function;
```

3.1. Function limits

First we define limits to our functions.

```
89 | Limits our_limits(0.0, 1.0);
```

The limits here include the lower bound 0.0 and exclude the upper one 1.0.
Let's see the acceptance of our limits.

```
91 | EXPECT_THROW( our_limits.assert_contains(-0.1), Limits::OutOfRange );
92 | EXPECT_NO_THROW( our_limits.assert_contains(0.0) );
93 | EXPECT_NO_THROW( our_limits.assert_contains(0.5) );
94 | EXPECT_THROW( our_limits.assert_contains(1.0), Limits::OutOfRange );
```

When we create functions with our limits like

```
96 | Constant our_const(1.337, our_limits);
```

the function will also show the restrictive access:

```
98 | EXPECT_THROW( our_const(-0.1), Limits::OutOfRange );
99 | EXPECT_NO_THROW( our_const(0.0) );
100 | EXPECT_NO_THROW( our_const(0.5) );
101 | EXPECT_THROW( our_const(1.0), Limits::OutOfRange );
```

3.2. Constant

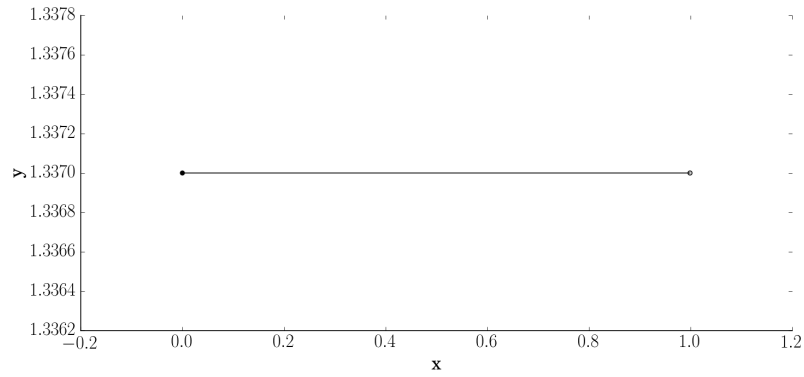
$$y = f(x) = c \tag{3}$$

A constant function takes its single constant value e.g. 1.337 and its limits.

```
108 | Limits l(0.0, 1.0);
109 | Constant c(1.337, l);
```

When called within the limits, it will always return its constant value.

```
111 | EXPECT_EQ( 1.337, c(0.0) );
112 | EXPECT_EQ( 1.337, c(0.2) );
113 | EXPECT_EQ( 1.337, c(0.3) );
114 | EXPECT_EQ( 1.337, c(0.43657657) );
115 | EXPECT_EQ( 1.337, c(0.78) );
116 | EXPECT_EQ( 1.337, c(0.9999) );
```



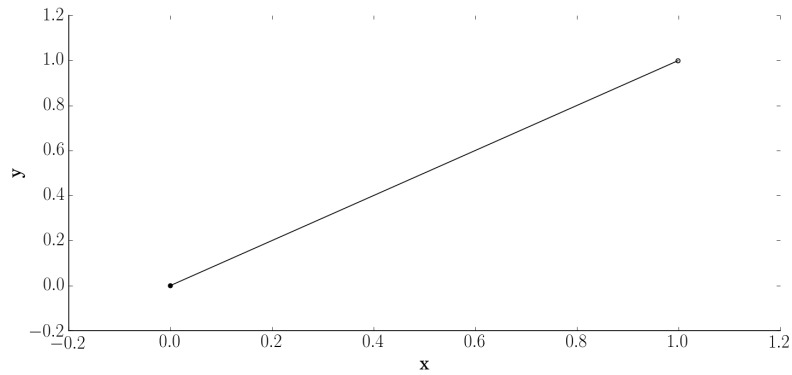
3.3. *Polynom3*

The versatile polynom of power 3 is defined by its four parameters a, b, c and d .

$$y = f(x) = ax^3 + bx^2 + cx^1 + dx^0 \quad (4)$$

We initialize it using a, b, c, d and the limits. Here we create a linear mapping.

```
125 Limits l(0.0, 1.0);
126 Polynom3 p3(0.0, 0.0, 1.0, 0.0, 1);
```



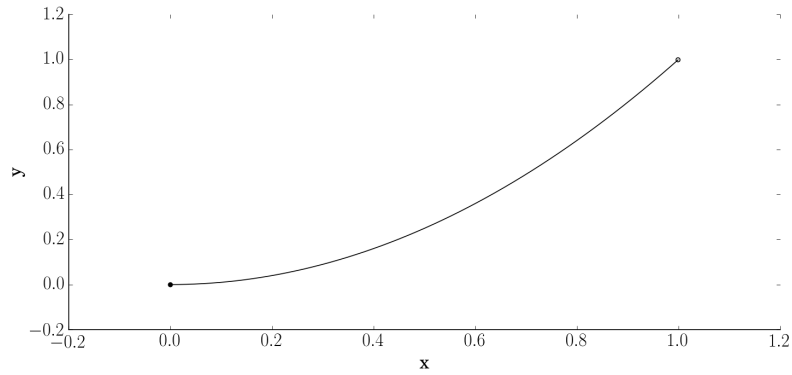
We can do a quadratic mapping:

```
138 Limits l(0.0, 1.0);
139 Polynom3 p3(0.0, 1.0, 0.0, 0.0, 1);
```

```

140
141 EXPECT_NEAR( 0.0, p3(0.0) ,1e-9);
142 EXPECT_NEAR( 0.25, p3(0.5) ,1e-9);
143 EXPECT_NEAR( 0.04, p3(0.2) ,1e-9);

```



3.4. Concatenation

```

151 Polynom3 f1(0.0, 1.0, 0.0, 0.0, Limits(-1.5, -0.5));
152 Polynom3 f2(0.0, 0.0, 2.0, 0.0, Limits(-0.5, 0.5));
153 Polynom3 f3(0.0, -1.0, 0.0, 0.0, Limits(0.5, 1.5));
154
155 std::vector<const Func1D*> funcs = {&f1, &f2, &f3};
156 Concat concat(funcs);

```

