

Geometric Graph Neural Network based track finding

Dolores Garcia^{1*}, Brieuc Francois^{1*} and Michele Selvaggi^{1*}

¹CERN, Geneva, Switzerland.

*Corresponding author(s). E-mail(s): dolores.garcia@cern.ch;
brieuc.francois@cern.ch; michele.selvaggi@cern.ch;

An essential component of event reconstruction in particle physics experiments is identifying the trajectory of charged particles in the detector. Traditional methods for track finding are often complex, and tailored to specific detectors and input geometries, limiting their adaptability to new detector designs and optimization processes. To overcome these limitations, we present a novel, end-to-end track finding algorithm that is detector-agnostic and can take into account multiple input geometric types. To achieve this, our approach unifies inputs from multiple sub-detectors and detector types into a single geometric algebra representation, simplifying data handling compared to traditional methods. Then, we leverage an equivariant graph neural network, GATr, to perform track finding across all data from an event simultaneously. We validate the effectiveness of our pipeline on various detector concepts with different technologies for the FCC-ee at CERN, specifically the IDEA and CLD detectors. This work generalizes track finding across diverse types of input geometric data and tracking technologies, facilitating the development of innovative detector concepts, accelerating detector development cycles, and enabling comprehensive detector optimization.

1 Introduction

The Future Circular Collider is one of the proposed future colliders that could follow from the Large Hadron Collider (LHC) at CERN. In the first stage, FCC-ee, an electron and a positron beam are accelerated to nearly the speed of light to collide in multiple interaction points. These collisions generate sprays of outgoing particles. Sophisticated detector systems, comprising hundreds of millions of sensors are utilized to measure information about these particles. One of the main challenges is to identify and reconstruct the 3D trajectory and kinematic properties of a charged particles propagating inside the detector’s magnetic field (see Figure 1), this is referred to as tracking. Classic approaches solve this problem with combinatorial optimization methods such as Kalman filters [1–3]. However, these methods are detector dependent, and have a long development cycle, reducing their adaptability to new detector concepts. Novel approaches to tracking are needed to maximize the potential of future detectors.

Tracking is performed in two stages [4], first track finding and then track fitting. Track finding is essentially an object instantiation task, which requires to identify groups of hits that form a track. Where the hits are the collection of measurements resulting from the particles interacting with the detector. Hits are usually positions, but they can be more complex geometries, such as shapes or directions. Track finding is a challenging problem: tracks can have a different geometries and varying number of hits (10-100’s), a track can have missing hits in the trajectory, they can have hits in one or multiple sub-detectors, or an in-flight decay of a particle can produce an abrupt change in direction (kinked tracks) or disappear.

Track finding has been approached in multiple ways. Global methods cluster hits by transforming the coordinates to a feature space in which relevant patterns are easier to detect [5]. Another approach is seeding and track following, usually implemented with a Combinatorial Kalman Filter [6]. This approach evaluates combinations of hits and iteratively builds tracks [1, 7]. However, it is complex due to the large combinatorics, and it requires a detailed description of the geometry and materials of the experiment. In addition, when dealing with various types of input geometric data in each sub-detector, some works perform track finding for each sub-detector and then combine the track sections [2, 7]. For example, the Belle II experiment has two tracking detectors, and its track finding approach is composed of eight different algorithms including multiple algorithms for each tracking detector and for the combination [2]. Overall, these algorithms are detector dependent and have long development cycle.

Currently, there are new collider proposals with novel developments in detector technologies. For example, for the FCC-ee, there are several detector concepts under investigation [8–10]. Each different tracking component can result in multiple input geometric types, depending on the measurement. As these new detector concepts are envisioned, it is important to have adaptable tracking pipelines with fast turnaround that can cope with different sub-detector concepts, geometric input data, variations and optimizations thereof. Figure 1 shows two of the detectors which produce different track representations requiring usually different algorithms.

Novel Graph Neural Network (GNN) based methods have been recently shown to perform competitively to classic pattern recognition approaches for a generic silicon detector while remaining scalable and not depending on the geometry implementation

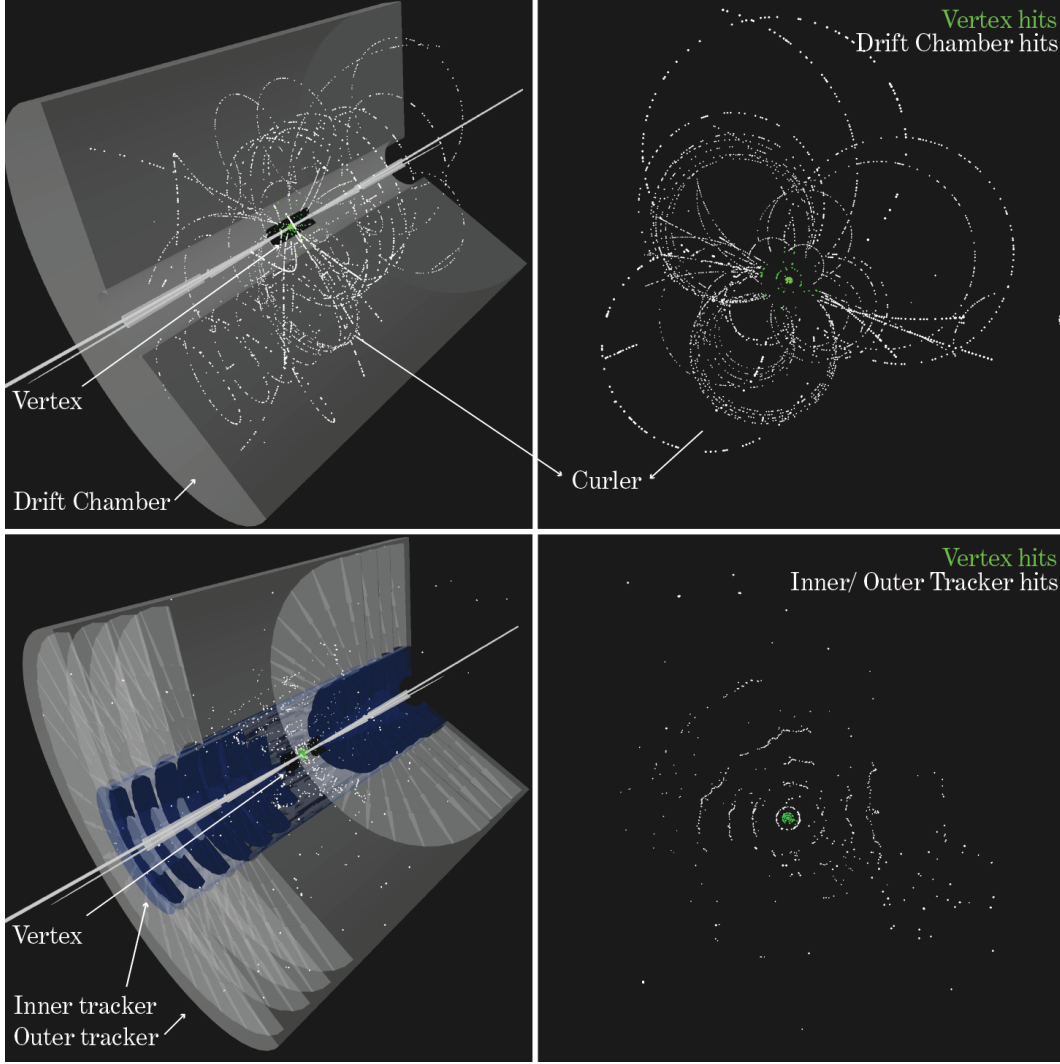


Fig. 1 Top left: Simulated collision event showing the hits (in white) in the tracker of the IDEA detector. In the drift chamber volume each hit is composed of two position coordinates due to the ambiguity in the measurement (more details are given in Section 4). Top right: front view of reconstructed hits. The circular shrinking pattern on the left corresponds to a low energy particle curling inside the detector while losing energy. The straight tracks correspond to higher energy particles. Bottom left: reconstructed hits in the CLD detector of the same event, the vertex-detector is shown in black, the inner tracker layers are shown in blue and the outer tracker disks are shown in grey. Bottom right: front view of the hits in the CLD detector.

of the detector [3, 11]. However, so far they have only been applied to silicon tracking systems, which have pointcloud-like inputs, and (author?) [11] also introduce pipelines with multiple preprocessing steps.

This work presents the detector agnostic Geometric Graph Track Finding (GGTF) method. This method is a generalized geometric track finding approach that:

- Can cope with multiple sub-detectors with different input geometries from multiple tracking technologies
- Does not require the geometry and materials specifications of the detector
- Does not rely on an analytical parametrization of the trajectories.

Specifically, our end-to-end pipeline considers the hits from all tracking components and outputs a set of tracks. A critical new component is a geometric algebra representation of the data that which allows multiple geometric types and a GNN, GATr [12], that exploits the symmetries of the detector through equivariance. The performance of the algorithm is assessed using two of the FCC-ee baseline detector concepts, the IDEA detector [8, 10] and the CLD detector [9].

2 Related Work

Legacy tracking approaches

Two main approaches are employed in track finding algorithms: coordinate transformation (global methods) and seeding and track following approaches.

Conformal tracking [13] is a circle fitting method that transforms circles in the plane passing through the origin into straight lines. Another similar approach is the Hough transform [14], which finds clusters of points that lie close to a parametric curve reducing tracking to finding intersection points. However, in practice it is computationally expensive since the points do not lie exactly in a single point, and binning the space is needed. Extensions of this approach are the Retina algorithm [15] and the Legendre transform.

The second set of approaches use seeding and a track following. Conformal tracking can be improved using this type of approach. The original method does not take into account deviations from the circular path, such as those due to multiple scattering or displaced vertices. (author?) [5] use the cellular automaton (CA) algorithm to take these deviations into account. The CA algorithm uses a seeding procedure followed by cell extrapolation. In other approaches, the seeding algorithm iteratively finds triplets of hits that are likely to belong to the same track. The track candidates are then built from the seeds using a Combinatorial Kalman Filter [6]. These types of approaches give high accuracy but are computationally demanding. Some of these algorithms have complex implementations as they use the geometry to calculate deviations from the expected path due to material interactions. This requires the algorithm to interact with the geometry of the detector for every step which can be costly [1, 16].

An extensive review of classic pattern recognition algorithms is out of the scope of this paper, we refer the reader to [4] for an in depth review. However, it is worth noting that track finding in real experiments, such as the Belle II [2] applies a mix of these algorithms to obtain the best tracking performance.

ML-based tracking

Neural Networks (NN) were also applied early to the problem of pattern recognition in [17]. (author?) [17, 18] consider the neurons in the network to be track segments connecting the hits. More recently, the HEP.TrkX project and its follow up, Exa.TrkX [3], were proposed to develop NN for track finding resulting in multiple works [11, 19, 20]. (author?) [19] presents multiple models based on Recurrent Neural Networks and GNNs. Two approaches are proposed, the first is a binary hit classification graph model that works on a subset of the event to extract tracks iteratively. The second is an edge classification model where an edge is correct if two hits belong to the same track. (author?) [11] combines multiple approaches by having an edge filtering model combined with an edge classification GNN and obtains track candidates from the connected components of the final graph. These methods relying on edge classification suffer from the costly post-processing step of finding connected components in a graph. A recent work [20], uses a similar approach but changes from edge classification to clustering the hits in embedding space using object condensation, avoiding the problems of previous architectures. This method improves the performance over the connected components baseline. GNN based approaches [11, 19, 20] have focused on the dataset proposed in [3] which considers pixel and strips tracking components. One of our key contribution is to generalize the method of track finding using GNNs to more complex tracking detectors.

3 Preliminaries

Problem statement

An event is a collection of measurements in a detector. The detector registers the signals deposited by the interaction of particles with its sensitive components, referred to as hits. The role of a tracking algorithm is to identify sets of hits produced by single particles and to derive information on the particles trajectory based on those. For a set of hits in a given event, $\mathcal{X}$, composed of hits from different tracking components $\mathcal{X} = \{X_v, X_i, X_o, \dots\}$, (vertex, inner tracker, outer tracker, endcap inner tracker,...) we want to obtain a set of tracks that approximates the target set of charged particles. The geometry of the detector is cylindrical, with a magnetic field along the z direction. We define the (x, y) as the transverse plane, and the z as the beam direction. Figure 1 shows an example set of hits for different detectors and Figure 2 shows a layout of the tracking components for each detector. In this work, this is framed as an object instantiation problem.

Trajectories

In a detector with a homogeneous magnetic field, the trajectory of a particle forms a helix, with varying curvature depending on its momentum. Particles with higher momentum result in an arc, while lower momentum particles can curl inside the detector. As they lose energy, the curvature of the helix increases, generating the shrinking displaced circles observed in Figure 1 top.

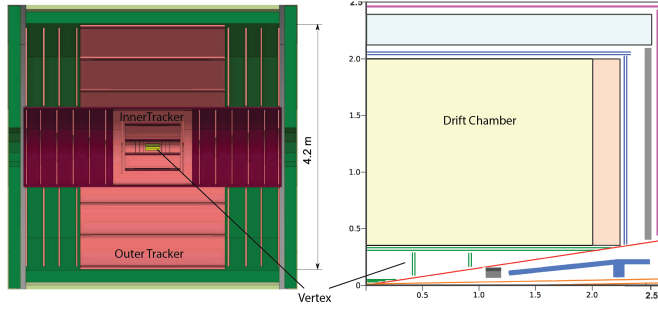


Fig. 2 Left: layout of the CLD tracking system from [9]. Right: layout of the IDEA tracking system from [21].

Representations

The inputs from the different tracking detectors, as well as the geometries of the tracks, are detector dependent. For a silicon detector, each hit $h = (\mathbf{x}, s)$ consist of a set of 3D coordinates $\mathbf{x} \in \mathbb{R}^3$ and a scalar s corresponding to the subdetector index. For other detector technologies, other information might be available. For example in a drift chamber, a gaseous detector filled with wires which register ionization signals, each hit leads to two sets of coordinates, $(\mathbf{x}_{\text{left}}, \mathbf{x}_{\text{right}})$, due to inherent left-right ambiguity in the measurement. This richer data structure, which steps away from point-like track representations, make the application of classical approaches complex.

In addition, tracks might have very different geometries in different detectors. For a silicon detector like CLD a particle will leave around 10-15 hits per track [9], while for a drift chamber each particle can generate $O(100)$ hits. Not only the number of hits are different, but also the presented geometries. A drift chamber like detector allows to capture particles of very low energy looping through the detector due to the magnetic field, as can be seen in Figure 1 left. Lower momentum particles have smaller curvature radius leading to spiral trajectories, which we will refer to as curlers. These curlers represent a complex reconstruction tasks for classical algorithms, which usually focus on the high momentum regime (higher curvature radius tracks).

4 Geometric-based generalized track finding

Our main contribution is the GGTF pipeline, which transitions from the hits of the different tracking detectors to a set of tracks. Our pipeline uses a novel geometric GNN, the GATr, [12] which represents the inputs in a projective geometric algebra respecting equivariance, and the object condensation loss [22] to cluster hits belonging to the same object close in an embedding space, as in [11]. Unlike [11, 20], our architecture does not require edge filtering which reduces the memory constraints. Also, our pipeline allows for more types of geometric inputs, unlocking this new approach for more tracking detectors such as the drift chamber.

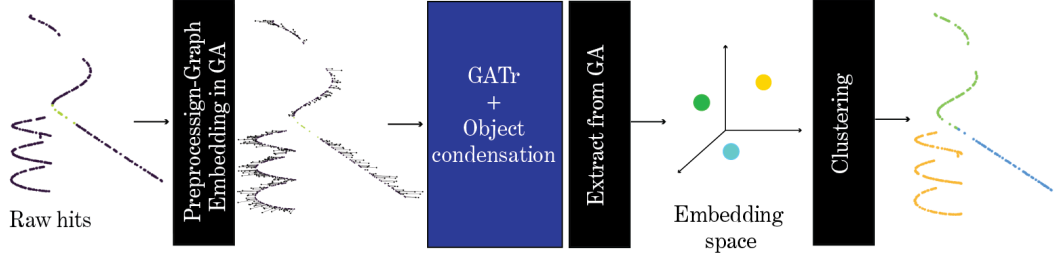


Fig. 3 Overview of the GGTF end-to-end approach for track finding. The raw hit are represented as multivectors in the geometric algebra. The multivectors are embedded into a low-dimensional space using the Geometric Algebra Transformer (GATr) architecture and an object condensation approach, finally a clustering step determines the track candidates.

Representation of hits in the graph

As an initial step, the set of hits for each event is converted into a graph. However, unlike traditional approaches, the GATr architecture allows to represent the raw hits as different geometrical objects and transformations in the projective geometric algebra $\mathcal{G}_{3,0,1}$. The elements of the algebra are 16-dimensional multivectors, these have direction, sign and can be linearly combined [12]. This method allows to have as an input planes, lines, point or scalars. For example, we choose to represent the hits from the vertex detector as points (trivectors) and the hits from the drift chamber as vectors. This vector goes from the left to the right hit coordinates, therefore accounting for the ambiguity in the measurement.

Geometric Algebra Transformer

The hits from the different systems are then unified in the multivector format, which represents the different geometrical objects in 16 dimensions. Then, we use the GATr architecture as shown in Figure 3. It consist of multiple transformer blocks. Each block has a *LayerNorm*, an *equivariant multivector self-attention* layer, a second *LayerNorm*, an *equivariant multivector MLP with geometric bilinear interactions*, and another residual connection. This architecture is $E(3)$ equivariant. The $E(3)$ -equivariant linear layers map multivectors using grade projections and multiplication with a homogenous basis vector. The geometric bilinears allow to build more expressive networks by allowing grade mixing. The network outputs multivectors which are used by the object condensation loss, defined below.

Loss and final track reconstruction

Modern approaches to reconstruct multiple objects focus on predicting a bounding box per object as an output [23, 24]. However, due to the helical trajectory of the tracks it would be hard to parameterize these boxes. On the other hand, the object condensation approach for multi-object detection [22] allows to reconstruct an unknown number of objects through a dedicated loss function without the use of bounding boxes. The intuition behind this approach is as follows: the loss function requires the output of hits belonging to the same track to be close in a low dimensional embedding space

and those belonging to different tracks to be far away. In this way, in the embedding space the tracks are easily separable.

The network is trained to predict a scalar $0 < \beta_i < 1$ and a coordinate x per node. The scalar is used to define a charge q_i with an increasing gradient:

$$q_i = \arctan^2 \beta_i + q_{min}, \quad (1)$$

q_{min} represents the minimum charge and avoids the minimum $q_i = 0$. This charge for every node is used to define a repulsive and an attractive potential $V_{i,k}(x)$. The potential affecting nodes belonging to an object is approximated by the potential of the node with the highest charge in the object, α . Each node j contributes with an attractive potential $\check{V}_k(x_j)$ for the object they belong to, and with a repulsive potential $\hat{V}_k(x_j)$ for the other $K-1$ objects. The mask M_{jk} is 1 if j belongs to k and 0 otherwise. This potential is multiplied by the charge. Therefore the loss corresponding to all hits can be written as follows

$$L_V = \frac{1}{N} \sum_{j=1}^N q_j \sum_{k=1}^K (M_{jk} \check{V}_k(x_j) + (1 - M_{jk}) \hat{V}_k(x_j)) \quad (2)$$

Then, L_β is defined to enforce one condensation point per particle (left side):

$$L_\beta = \frac{1}{K} \sum_k (1 - \beta_{\alpha k}) + \frac{1}{N_B} \sum_i n_i \beta_i \quad (3)$$

it also minimizes the β_i component for noise hits ($n_i = 1$), where N_B are the number of hits that are not assigned to a reconstructable particle. The full loss function is $L = L_V + L_\beta$.

More details on the loss can be found in (author?) [22]. Starting from the output multivectors of the network we define the coordinates of each node as the point component extracted from the multivector and the β for each node as the scalar component. This is represented on the right side of Figure 3. Finally, we cluster in the 3D embedding space using the HDBSCAN clustering algorithm [25] .

5 Experiments

Metrics

In order to measure the performance of the various algorithms, each reconstructed track is matched to a ground truth particle to which it shares the largest number of hits.

- *The track hit purity* is the ratio of the number of hits in the track that belong to the MC particle and the total number of hits of the reconstructed track.
- *The track hit efficiency* is the ratio of the number of hits in the track that belong to the MC particle and the total number of hits this particle left in the detector.

The *tracking efficiency* is the probability to reconstruct a track. It can be defined in multiple ways, we will consider the following variants:

1. The percentage of reconstructable charged particles that lead to a reconstructed track with track hit purity greater than 75%, as in (author?) [9] .
2. The percentage of reconstructable charged particles with both ratios, the track hit purity and the track hit efficiency, above 50%, as defined in the accuracy tracking challenge (author?) [3]. Tracks are further separated in four categories. *Good*: both ratios above 50%, reconstructed in this definition. *Split*: track hit efficiency below 50%, track hit purity above 50%, so only a fraction of the track is reconstructed. *Multiple*: track hit efficiency above 50%, but track hit purity below 50%, typically due to the aggregation of multiple particles. *Bad*: both below 50%.
3. For the CLD detector as there are only 10-15 hits per track, we consider the percentage of reconstructable charged particles that match with a reconstructed track with at least four hits (the minimum number of hits for track fitting, the second tracking step).

We evaluate the performance of our algorithm by showing the efficiency vs particle proximity and track displacement. *Particle proximity* is the smallest angular distance, Δ_{MC} , between the Monte Carlo particle associated to the track and any other MC particle. The angular distance between two particles can be defined as a function of the azimuthal angle ϕ and the pseudorapidity η as $\Delta_{MC} = \sqrt{\Delta\phi^2 + \Delta\eta^2}$. Reconstruction of *displaced tracks* is critical for the identification of longed lived particles. These tracks are originated from a secondary vertex rather than from the primary interaction point e.g b and d mesons which can travel a measurable distance before decaying. The displacement of a track can be measured looking at the production vertex radius, i.e. $R = \sqrt{x^2 + y^2}$.

5.1 CLD detector

We start the demonstration of the GGTF pipeline and performance with the CLD detector. This detector is an all-silicon tracker, therefore an easier case scenario as all hits are of the same type, and can be compared to a heuristic based algorithm: the conformal tracking [5, 9]. The input are the hits left by the particles in the different subdetectors: vertex, inner tracker and outer tracker. The experiment and different cuts applied to be comparable to the baseline are described in detail in Appendix A.1.1.

In the top left and center Figure 4 we show the track hit purity and track hit efficiency respectively. Conformal tracking has a higher track hit purity but captures up to 40% less hits than GGTF in the low p_T regime. This shows in the different efficiency definitions. Using the definition based only on purity, definition 1, the tracking efficiency is slightly lower than the baseline for low p_T , shown in bottom left of Figure 4. If we consider the second definition, based on track hit purity and efficiency, GGTF has an overall higher tracking efficiency, shown in bottom center of Figure 4. The discontinuity observed at 700 MeV can be explained by the fact that this is the minimal transverse momentum needed to reach the outside of the tracker, therefore this threshold set the limit for curlers.

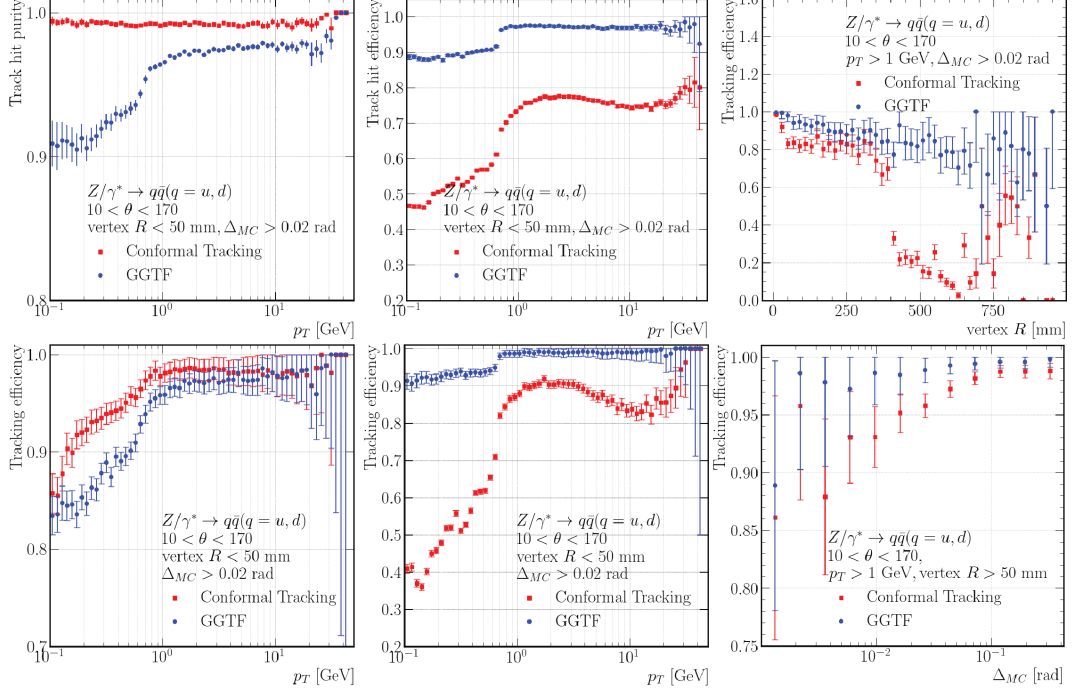


Fig. 4 Results for the CLD detector. Top left: track hit purity as a function of p_T . Top center: track hit efficiency as a function of p_T . Top right: tracking efficiency as a function of the production vertex radius (def. 3). Bottom left: tracking efficiency (def. 1) as a function of p_T . Bottom center: tracking efficiency (def. 2) as a function of p_T . Bottom right: tracking efficiency as a function of particle proximity.

We use the tracking efficiency definition 3 to study the performance on displaced tracks and particle proximity. This definition allows to compare both algorithms on equal grounds as it uses a loser definition of reconstructed track. GGTF outperforms the baseline for displaced tracks reconstruction, as shown in the top right of Figure 4. This is due to the conformal tracking algorithm assuming that all tracks originate from a common point. Therefore, these displaced tracks do not align with straight lines in the conformal plane, which leads to failure of the conformal tracking algorithm. The percentage of fake tracks is very similar for both algorithms: 4.8% for GGTF and 5.2% for **CT!** (**CT!**). Since the track fitting stage is not performed, the distribution per p_T is not available. Finally, the bottom right of Figure 4 shows the efficiency with the most inclusive definition 3 as a function of particle proximity. Overall, this follows the expected trend, if the closest track is further, it is easier to detect the tracks and GGTF improves the performance for really close tracks over the baseline. Figure 6 shows the classifications of tracks for reconstructable particles as described in Section 5. The conformal tracking approach presents more split tracks while the GGTF can reconstruct a higher percentage of 'full' tracks.

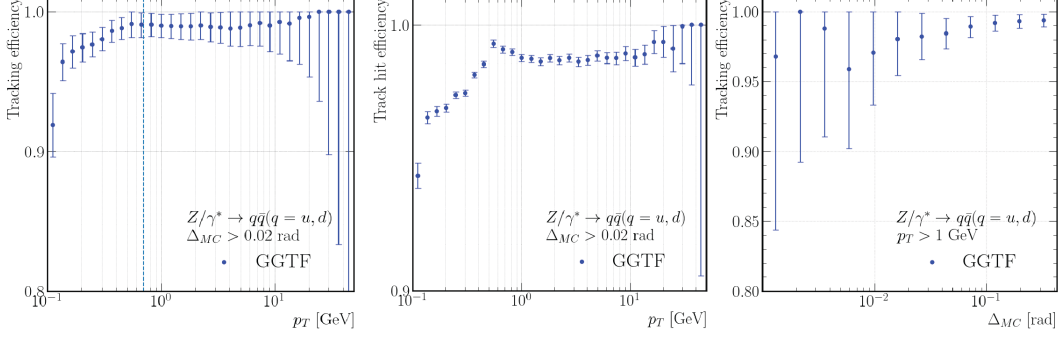


Fig. 5 Results for the IDEA detector. Left: tracking efficiency (def. 2) as a function of p_T . Center: percentage of hits of the MC particle captured by the reconstructed track as a function of p_T . Right: tracking efficiency as a function of particle proximity.

5.2 IDEA detector

Next, we turn towards a more complex detector involving multiple tracking technologies and producing more complex geometries. We study the IDEA detector which has a silicon inner vertex detector and a drift chamber. The drift chamber is filled with gas and wires that collect the ionization signal of particles. Each particle can leave $O(100)$ hits in the detector, which is an order of magnitude larger than for CLD. The IDEA detector does not have a baseline algorithm available. We therefore use these results to illustrate the algorithm versatility in terms of detector technology. See Appendix A.1.2 for all the experiment details.

The results are shown in Figure 5. Figure 5 shows that GGTF provides good tracking efficiency (definition 2). The curling limit of p_T is shown with a blue vertical line. As expected, the tracking efficiency is lower for lower p_T particles as these are curling in the detector leaving very long tracks which are hard to recover fully. This is shown in the center of Figure 5. These results are comparable to the tracking efficiency shown for the Belle II detector [2].

6 Conclusions

GGTF is a high-efficiency general track finding method for multiple sub-detectors with different input geometries. It is able to find varied track geometries via an equivariant GNN. The success of GGTF indicates that highly parameterized algorithms are likely unnecessary and can be replaced with suitable GNNs. This new pipeline significantly simplifies the application of track finding to optimization studies as the development cycle is largely reduced. An important future step is to evaluate the algorithm impact on the track fitting stage, as its higher track hit efficiency could improve the accuracy of the track parameters. Beyond the current applications, we suggest multiple research directions to address the current limitations. For example, the algorithm was evaluated without background, adding background would result in several 'noise' hits, thereby degrading the track hit purity and efficiency and increasing the probability of reconstructing fake tracks. Finally, scalability of the algorithm needs to be improved

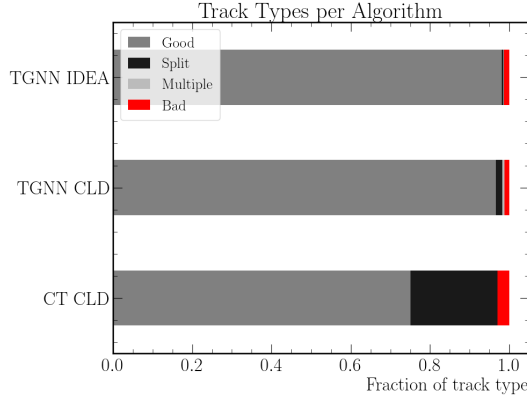


Fig. 6 Distribution of the reconstructed tracks with different definitions as described in section 5 for the GGTF and the baseline approach

to apply this method to full pile-up events, where the number of hits can be up to an order of magnitude larger.

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A Appendix

A.1 Experiments

Dataset

Raw hits are obtained by performing simulation using the Key4hep [26] framework, a software ecosystem for future colliders [26]. First, the simulation of the collisions, production and decay of the Z boson are generated with PYTHIA8 [27]. The considered decay is $e^+e^- \rightarrow Z \rightarrow q\bar{q}$, $q = u, d$, at a center of mass energy of 91.2 GeV/c. PYTHIA8 also evolves the produced particles, performing parton showers and hadronization to produce a final set of outgoing particles. These particles are then propagated through the detector using the DD4hep [28] toolkit which provides a convenient interface to

Geant4 [29]. Our approach is applied to the two detector concepts under consideration. We generate one dataset for each detector concept and describe their differences below.

We generate a training dataset with 320k events; a validation dataset with 10k events; and a regular evaluation set with 10k events for each detector concept.

A.1.1 CLD detector

The CLD detector [9] has an all-silicon tracker. The tracking system consists of a vertex pixel detector (V), an inner tracker with three barrel layers (ITB) and seven forward disks or endcap (ITE), and an outer tracker with additional three barrel layers (OTB) and four discs (OTE). We use version *CLDo2v05* of the CLD detector geometry [30].

The dataset includes hits from each tracking sub-detector, reconstructed tracks from the conformal tracking algorithm and association of each hit to a Monte Carlo particle to build the set of target tracks to train the model on. Each input hit has global detector coordinates (x, y, z) and a label of the subdetector they hit $\{V, ITB, ITE, OTB, OTE\}$. Additionally, hits created by MC particles with less than 3 hits in total are labelled as noise hits, and the algorithm does not try to reconstruct these tracks.

Models

For the GATr we consider the architecture in [12]. We embed the hits of all sub-detectors as trivectors. We use 10 attention blocks, 16 multivector and 64 scalar channels, and 8 attention heads, resulting in 1.1 million parameters. The β is extracted as the scalar component of the multivector, and the coordinate in the embedding space as the trivector component.

Training

All models are trained by minimizing the object condensation loss. We train for 20 epochs with the Adam optimizer, using a batch size of 8 and a step scheduler for the learning rate from 10^{-3} to 10^{-6} .

Baselines

We compare our approach to state-of-the art track finding algorithms. The reference track finding approach for this detector which is based on conformal tracking and cellular automaton [5, 9]. In order to reproduce the results of [9], we apply the following cuts to the reconstructable particles. For the efficiency calculations the cuts are: $10^\circ < \theta < 170^\circ$, production radius smaller than 50 mm and a minimum particle proximity larger than 0.02 rad. For the production vertex radius the applied cuts are: $p_T > 1$ GeV, $10^\circ < \theta < 170^\circ$, a particle proximity larger than 0.02 rad. For the particle proximity the applied cuts are: $p_T > 1$ GeV, $10^\circ < \theta < 170^\circ$, and a production vertex radius, $R < 50mm$.

Additional plots

Percentage of unique hits: A given particle can leave more than one hit per layer, in which case, only one of the hits is considered unique. Evaluating the percentage of unique hits allows to determine which algorithm captures more relevant hits. In addition, capturing the maximum amount of unique hit improves the second stage of tracking, track fitting. Figure 7 shows that GGTF captures up to 40% more unique hits for lower p_T particles and 20% for higher p_T .

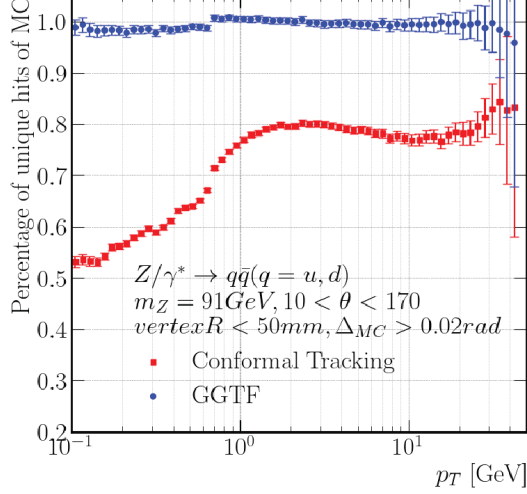


Fig. 7 Percentage of unique hits vs p_T of the particle.

A.1.2 IDEA detector

The tracking system of the IDEA detector [8, 10] is composed of an inner vertex detector, a drift chamber as main tracker and a silicon wrapper providing an additional precise measurement at large radius. The modeling of the silicon wrapper geometry being not available at the time of this study, only the vertex detector and drift chamber have been included in the simulation. The vertex detector is a silicon pixel detector surrounding the beam pipe for the precise determination of the impact parameter of charged tracks. The hits resulting from this detector include global coordinate information as in CLD. The drift chamber is a full-stereo, unique volume, highly granular cylindrical chamber. This tracking detector allows to measure the d_{along} along the wire and the distance to the wire, d_w . Therefore each hit can be described as $h = (w, d_w, d_{\text{along}})$, where w is the index of the wire. Using this information and the wire's information this can be converted to global coordinates. However, like in planar drift chamber there is an inherent left-right ambiguity of the spatial position relative to the sense wire, so that each hit has a mirror hit [4]. Therefore each hit corresponds to two sets of coordinates, $(\mathbf{x}_{\text{left}}, \mathbf{x}_{\text{right}})$, and the ambiguity can only be resolved after the track finding step [4]. Our pipeline allows to account for this ambiguity (sec: 4).

The hits of the IDEA detector are stored as:

$$h_i = (x, y, z, 0) \quad (4)$$

if they belong to the vertex. And,

$$h_i = (x_{\text{left}}, y_{\text{left}}, z_{\text{left}}, x_{\text{right}}, y_{\text{right}}, z_{\text{right}}, 1) \quad (5)$$

if they belong to the drift chamber.

Models

The model architecture has the same parameters as those described in [Appendix A.1.1](#).

Training

All models are trained by minimizing the object condensation loss. We train for 10 epochs with the Adam optimizer, using a batch size of 8 and a step scheduler for the learning rate from 10^{-3} to 10^{-6} .

Baselines

The IDEA detector does not have a baseline algorithm available. The Belle II experiment also has a tracking system composed of a vertex detector and a drift chamber. The results are not directly comparable as the detectors have different geometries and the set up of the wires of the drift chamber is different [\[2\]](#). However we use the results presented in [\[2\]](#) as a guideline.

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