Kinematics

*m<sub>T(2)</sub>* &c The boundary Generalizations Conclusions

# Transverse observables and the kinematic boundary

**Ben Gripaios** 

CERN

3rd September 2009

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Barr, BMG & Lester, arXiv:0908.3779 [hep-ph]

### Outline

- *m*<sub>T(2)</sub>, kinks &c.
- What does it all mean? The kinematic boundary

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 Generalizations: combinatorics, non-identical decays, and the inverse of m<sub>T(2)</sub> Kinematics

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In the beginning ...

### The transverse mass

$$m_0^2 = m_v^2 + m_i^2 + 2(E_v E_i - \mathbf{p}_v \cdot \mathbf{p}_i - q_v q_i)$$

•  $(E, \mathbf{p}, q)$  is 4-momentum

 $m_T^2 = m_v^2 + m_i^2 + 2(e_v e_i - \mathbf{p}_v \cdot \mathbf{p}_i)$ 

• 
$$e = \sqrt{\mathbf{p} \cdot \mathbf{p} + m^2}$$
 is transverse energy

 $m_0 \ge m_T$ 

#### Kinematics

*m*<sub>T(2)</sub> &c The boundary Generalizations Conclusions

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Kinematics

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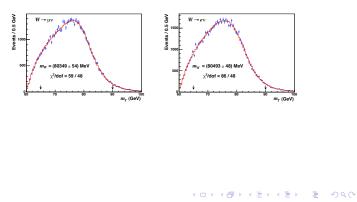
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### Transverse Mass $m_T$

 $W \rightarrow Iv$ 

CDF:  $m_W = 80.413 \pm 0.048$  GeV

arXiv:0708.3642



Kinematics

$$m_T^2 = m_v^2 + m_i^2 + 2(e_v e_i - \mathbf{p}_v \cdot \mathbf{p}_i)$$

unobservable

 $m_{T2} = \min \max m_T$ 

Lester & Summers, PLB 463 99,1999

Barr et al., J.Phys.G29:2343-2363,2003

observable

 $m_{T2} \leq m_0$ 

Kinematics

*m*<sub>T(2)</sub> &c The boundary Generalizations Conclusions

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Kinematics

### Pair Decays and $m_T 2$

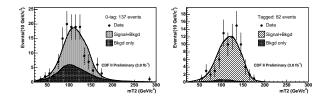
 $t\overline{t} \rightarrow 2b2W \rightarrow 2b2l2v$ 

Cho et al. 0804.2185

*m<sub>T(2)</sub>* &c The boundary Generalizations Conclusions

CDF  $m_{T2}$  only:  $m_t = 167.9^{+5.6}_{-5.0}$  GeV

CDF note 9769



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Kinematics

# $m_{T(2)}$ and the kink

$$m_T^2 = m_v^2 + m_i^2 + 2(e_v e_i - \mathbf{p}_v \cdot \mathbf{p}_i)$$

•  $m_T$  is unobservable if  $m_i$  unknown

• Consider  $m_T = m_T(m_i)$ 

Lose boundedness but gain a kink

t KITIK Choi et al., 0709.0288 BMG, JHEP 0208 051 2008 Barr, BMG & Lester, JHEP 0208 014, 2008 Choi et al., 0711.4526

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Kinematics

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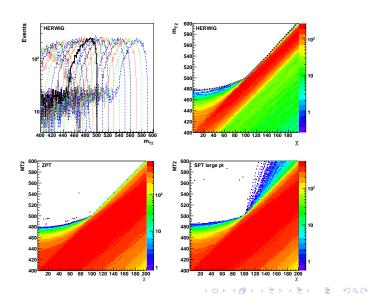
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#### Kinematics

# $m_{T(2)}$ and the kink Pair Three-body decay $2\tilde{g} \to 2q2\overline{q}2\tilde{\chi}^0_1$



Barr, BMG & Lester, JHEP 0208 014,2008

*m<sub>T(2)</sub>* &c The boundary Generalizations Conclusions

#### Kinematics

Kinematics

m<sub>T(2)</sub> &c The boundary Generalizations Conclusions

### What does all of this mean?

### What does all of this mean?

- ad hoc definition of m<sub>T(2)</sub>
- ad hoc generalization to hypothesized masses
- In fact these are natural objects ....

Cheng and Han, arXiv:0810.5178

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Kinematics

#### Kinematics

*m*<sub>T(2)</sub> &c **The boundary** Generalizations Conclusions

### The Kinematic Boundary

### $m_{T(2)}$ is the kinematic boundary of an event

Serna, arXiv:0804.3344

Cheng and Han, arXiv:0810.5178

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Kinematic constraints for an event:

• 
$$(p_i + p_v)^2 = m_0^2$$
  
•  $p_i^2 = m_i^2$ 

$$\triangleright$$
  $\mathbf{p}_i = \mathbf{p}$ 

Unknowns are  $p_i$  and  $(m_i, m_0)$ 

#### Kinematics

 $m_{T(2)}$  is the kinematic boundary of an event

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$$(p_i + p_v)^2 = m_0^2$$
  
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When do these admit a solution with real momentum and real, positive energy?

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Theorem: a solution exists for  $m_0 \ge m_T(m_i)$ 

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#### Kinematics

Theorem: a solution exists for  $m_0 \ge m_T(m_i)$ 

Proof: Two parts

- Part 1: Prove any solution has  $m_0 \ge m_T(m_i)$
- Part 2: Prove that there is a solution with m<sub>0</sub> = m<sub>T</sub>(m<sub>i</sub>)

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m<sub>T(2)</sub> &c The boundary Generalizations Conclusions

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# Part 1

### Prove any solution has $m_0 \ge m_T(m_i)$

- $\bullet \ m_0^2 = m_i^2 + m_v^2 + 2(E_i E_v \mathbf{p}_i \cdot \mathbf{p}_v q_i q_v)$
- $\mathbf{P} m_T^2 \equiv m_i^2 + m_v^2 + 2(\mathbf{e}_i \mathbf{e}_v \mathbf{p}_i \cdot \mathbf{p}_v)$
- $E_i E_v q_i q_v \ge e_i e_v$ , equality at  $E_i q_v E_v q_i = 0$

 $\blacktriangleright \implies m_0 \ge m_T(m_i)$ 

#### Kinematics

Prove any solution has  $m_0 \ge m_T(m_i)$ 

$$m_0^2 = m_i^2 + m_v^2 + 2(E_i E_v - \mathbf{p}_i \cdot \mathbf{p}_v - q_i q_v)$$
  
$$m_0^2 = m_i^2 + m_v^2 + 2(q_i q_v - \mathbf{p}_i \cdot \mathbf{p}_v)$$

• 
$$m_T^2 \equiv m_i^2 + m_v^2 + 2(e_i e_v - \mathbf{p}_i \cdot \mathbf{p}_v)$$

• 
$$E_i E_v - q_i q_v \ge e_i e_v$$
, equality at  $E_i q_v - E_v q_i = 0$ 

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$$\blacktriangleright \implies m_0 \ge m_T(m_i)$$

# Part 2

### Prove $m_0 = m_T(m_i)$ has a solution

Find suitable  $E_i, q_i$ 

• Need 
$$\frac{q_i}{q_i^2 + e_i^2} = \frac{q_v}{E_v} \in [-1, +1]$$

Proof for  $m_{T2}$  not much harder

Cheng and Han, arXiv:0810.5178

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Kinematics

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New definition of  $m_{T(2)}$  as "the kinematic boundary of an event"

So what?

Faster algorithm for computing m<sub>T2</sub>

Cheng and Han, arXiv:0810.5178

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- *m*<sub>T(2)</sub> is the best one can do without extra kinematics or dynamics
- Easier proofs of kinks &c.
- ► Generalize ...

#### Kinematics

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Kinematics

#### Kinematics

m<sub>T(2)</sub> &c The boundary Generalizations Conclusions

### Generalizations

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# **Generalizations I: Combinatorics**

### Combinatoric ambiguities

- Branch assignments
- Initial State Radiation

Barr and Lester, arXiv:0708.1028

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Alwall et al, arXiv:0905.1201

What is the kinematic boundary?

Union of allowed regions

Kinematics

# **Generalizations I: Combinatorics**

Combinatoric ambiguities

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What is the kinematic boundary?

Union of allowed regions

## Generalizations II: Non-identical decays

### Always considered identical pair decays.

### But parents/daughters need not be the same

Distinct parents:

Squark-gluino production in MSSM

Distinct daughters

- Distinct daughters: > 1 neutral particle with lifetime > few m
  - e.g. Neutrini, Multiple photini

Dimopoulos et al, to appear

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#### Kinematics

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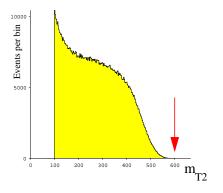
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#### Kinematics

 $m_{T2}$  is not much good ...



#### ... use the kinematic boundary?

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#### Focus on case with non-identical parents

- ► 3-d space of unknown masses (m<sub>i</sub>, m<sub>0</sub>, m'<sub>0</sub>)
- Kinematic boundary is a surface

Extremal surface from decoupling argument ...

#### Kinematics

m<sub>T(2)</sub> &c The boundary Generalizations Conclusions

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m<sub>T(2)</sub> &c The boundary Generalizations Conclusions

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Constraints

• 
$$(p_i + p_v)^2 = m_0^2$$
  
•  $p_i^2 = m_i^2$ 

Ditto for the other decay, plus

$$\triangleright \mathbf{p}_i + \mathbf{p}'_i = \mathbf{p}'$$

Last equation decouples for extremal surface

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#### Kinematics

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Kinematics

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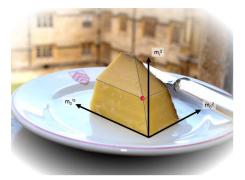
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Kinematics

#### Extremal surface



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Lots of interesting kinks ...

#### Kinematics

#### Is there an analogue of the usual $m_{T2}$ ?

# $m_{T2}^2(m_i, m'_i, rac{m_0}{m'_0}) = \min \max(rac{m'_0}{m_0} m_T^2, rac{m_0}{m'_0} m_T'^2)$

Kinematics

m<sub>T(2)</sub> &c The boundary Generalizations Conclusions

Is there an analogue of the usual  $m_{T2}$ ?

$$m_{T2}^2(m_i, m_i', \frac{m_0}{m_0'}) = \min \max(\frac{m_0'}{m_0}m_T^2, \frac{m_0}{m_0'}m_T'^2)$$

Kinematics

*m*<sub>T(2)</sub> &c The boundary Generalizations Conclusions

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Use  $m_0 = m_{T(2)}(m_i)$  if you know the mass of the daughter but not the parent ...

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... what about the other way round?

Kinematic boundary the same

• Need the inverse of  $m_0 = m_{T(2)}(m_i)$ 

Kinematics

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Kinematics

• 
$$m_T^2 = (\alpha_i + \alpha_v)^2, \ \alpha = (e, \mathbf{p})$$
  
•  $(m_T^2)^{-1} = (\alpha_0 - \alpha_v)^2$ 

• 
$$m_{T2} = \min \max(m_T, m'_T)$$
  
•  $m_{T2}^{-1} = \max \min(m_T^{-1}, m'_T^{-1})$ 

Kinematics

m<sub>T(2)</sub> &c The boundary Generalizations Conclusions

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$$m_T^2 = (\alpha_i + \alpha_v)^2, \ \alpha = (e, \mathbf{p})$$
  
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•  $m_{T2} = \min \max(m_T, m'_T)$ •  $m_{T2}^{-1} = \max \min(m_T^{-1}, m'_T^{-1})$  Kinematics

m<sub>T(2)</sub> &c The boundary Generalizations Conclusions

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- *m*<sub>T(2)</sub> &c are natural objects: define kinematic boundary
- Also the "best" objects
- Easily generalized

m<sub>T(2)</sub> &c The boundary Generalizations Conclusions

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