

MTCA for Optical Links

for the Laser Based Synchronization System at XFEL

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> Introduction

- Laser Based Synchronization System
- Optical Links at XFEL

> Link Signals and Interfaces

- MTCA Interfaces
- Crate Configuration

> Open Questions

Introduction – LBSync System

Provide a global reference for the synchronization of timing-critical subsystems of the accelerator

> Bunch arrival time measurements (BAM)

- These monitors are used by the beam-based feedback to synchronize (= stabilize) the arrival time of individual bunches to the optical reference

> Laser synchronization (L2L)

- Injector-, Seed-, and Pump-Probe lasers (their repetition rate and phase of the pulse train) are synchronized to the optical reference.

> RF synchronization for LLRF-reference (L2RF)

- The 1.3 GHz reference input for LOGM (& Klystron RF) from the main drive line is synchronized to the optical reference in the REFMs

→ Long- and short-term phase-stable optical pulse train has to be distributed along the XFEL (≤ 3.4 km)



Introduction – LBSync System

Provide a global reference for the synchronization of timing-critical subsystems of the accelerator

2 types of pulsed optical links:

> Bunch arrival time measurements (BAM)

- These monitors are used by the beam-based feedback to synchronize (= stabilize) the arrival time of individual bunches to the optical reference

> Laser synchronization (L2L)

- Injector-, Seed-, and Pump-Probe lasers (their repetition rate and phase of the pulse train) are synchronized to the optical reference.

> RF synchronization for LLRF-reference (L2RF)

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Cross-correlator based link stabilization
“Link”

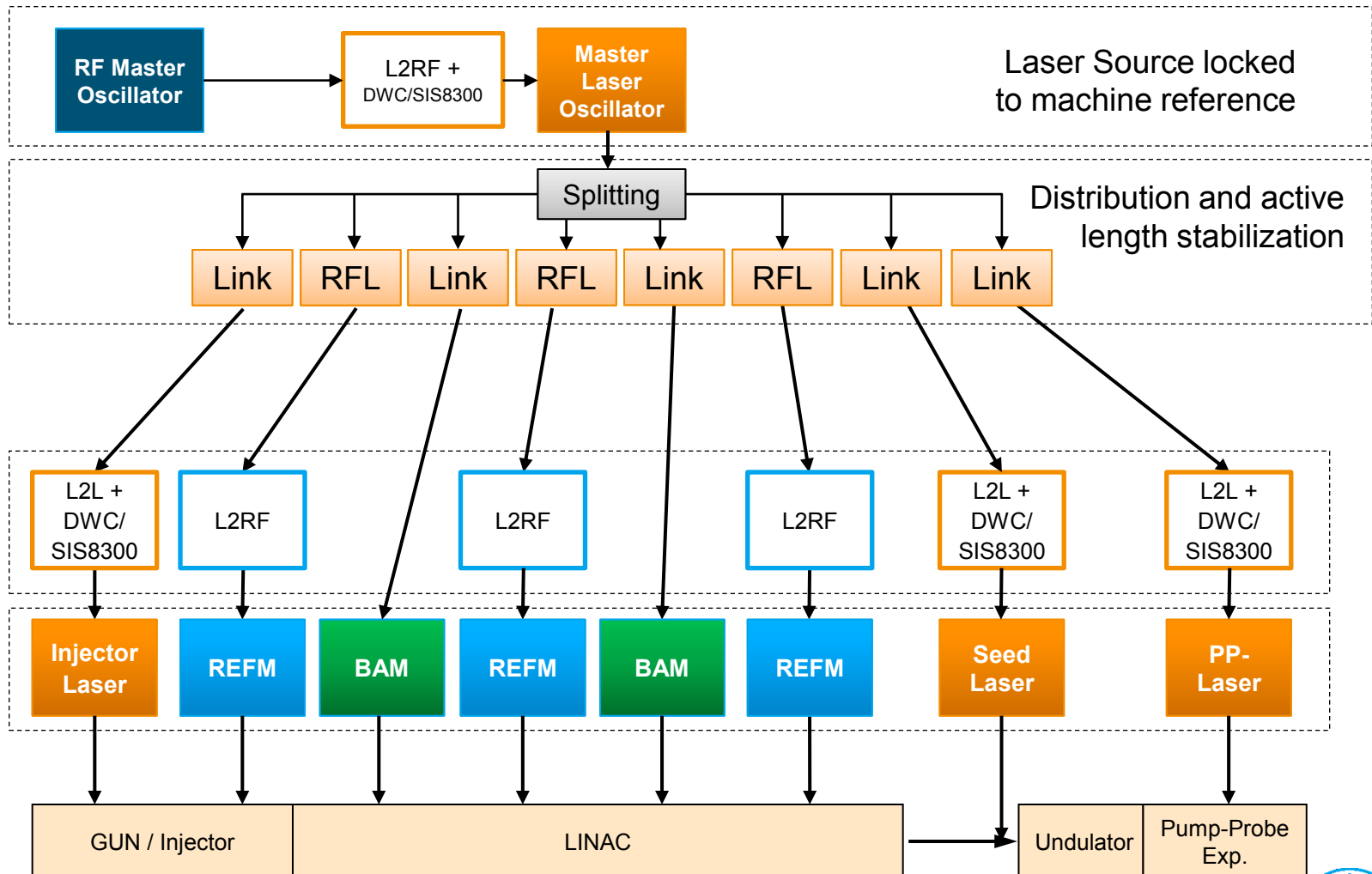
RF based link stabilization
“RF Link”

→ Long- and short-term phase-stable optical pulse train has to be distributed along the XFEL (≤ 3.4 km)

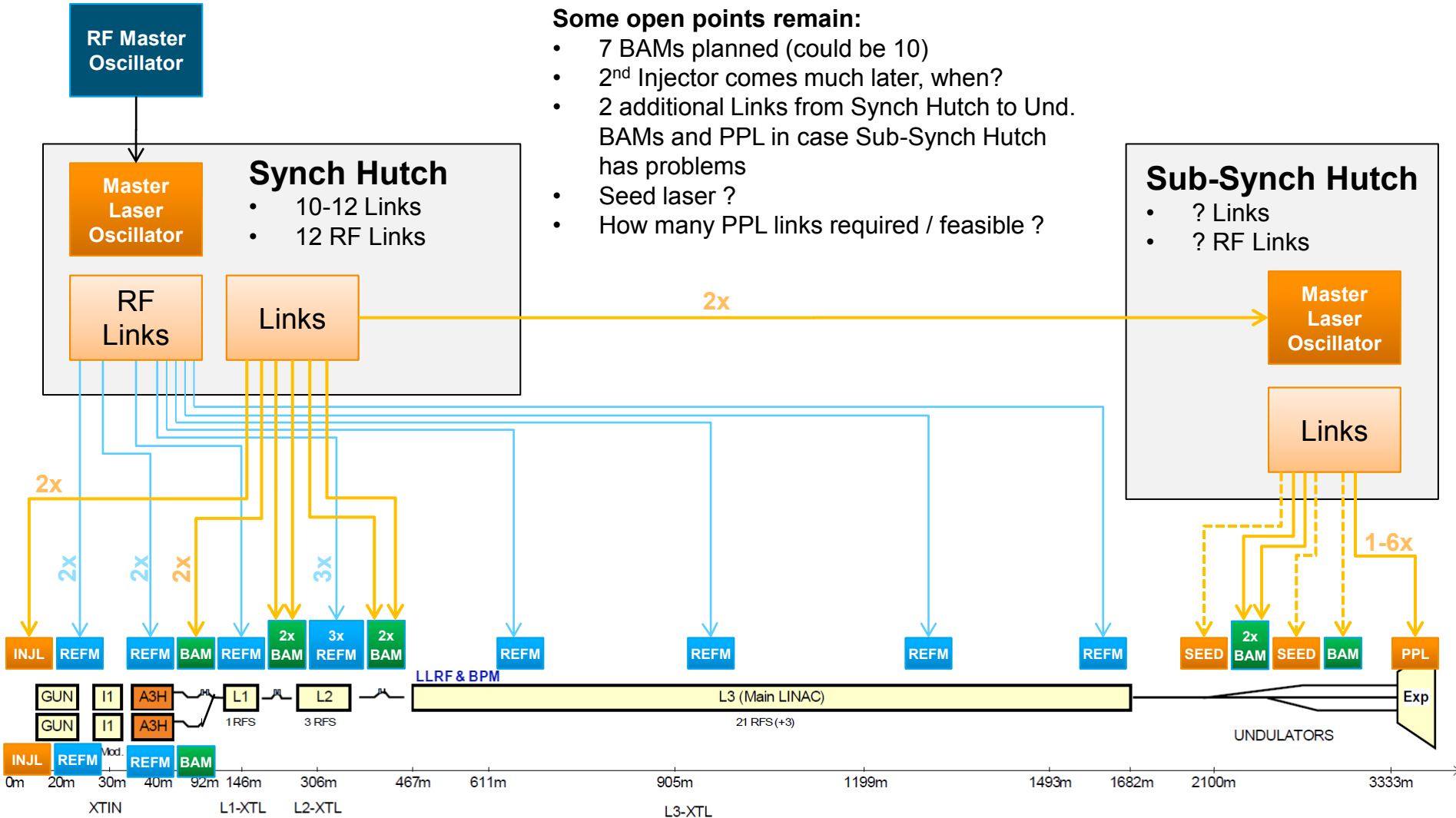


Principle Layout of the Synchronization System

The reference timing information is encoded in the precise repetition rate of an optical pulse train



Optical Links at the European XFEL



Link Setups - Interfaces to MTCA Units

> Signals per Link Box

- Inputs:
 - Piezo: ± 100 (± 85) V
 - Stepper Motor
- Outputs:
 - OXC Signal
 - Phase Detector
 - 2 x Power Monitor
 - 2 x Balanced Detector individual channels

Additionally: 2 x Laser Diode Driver with CAN-Bus interface

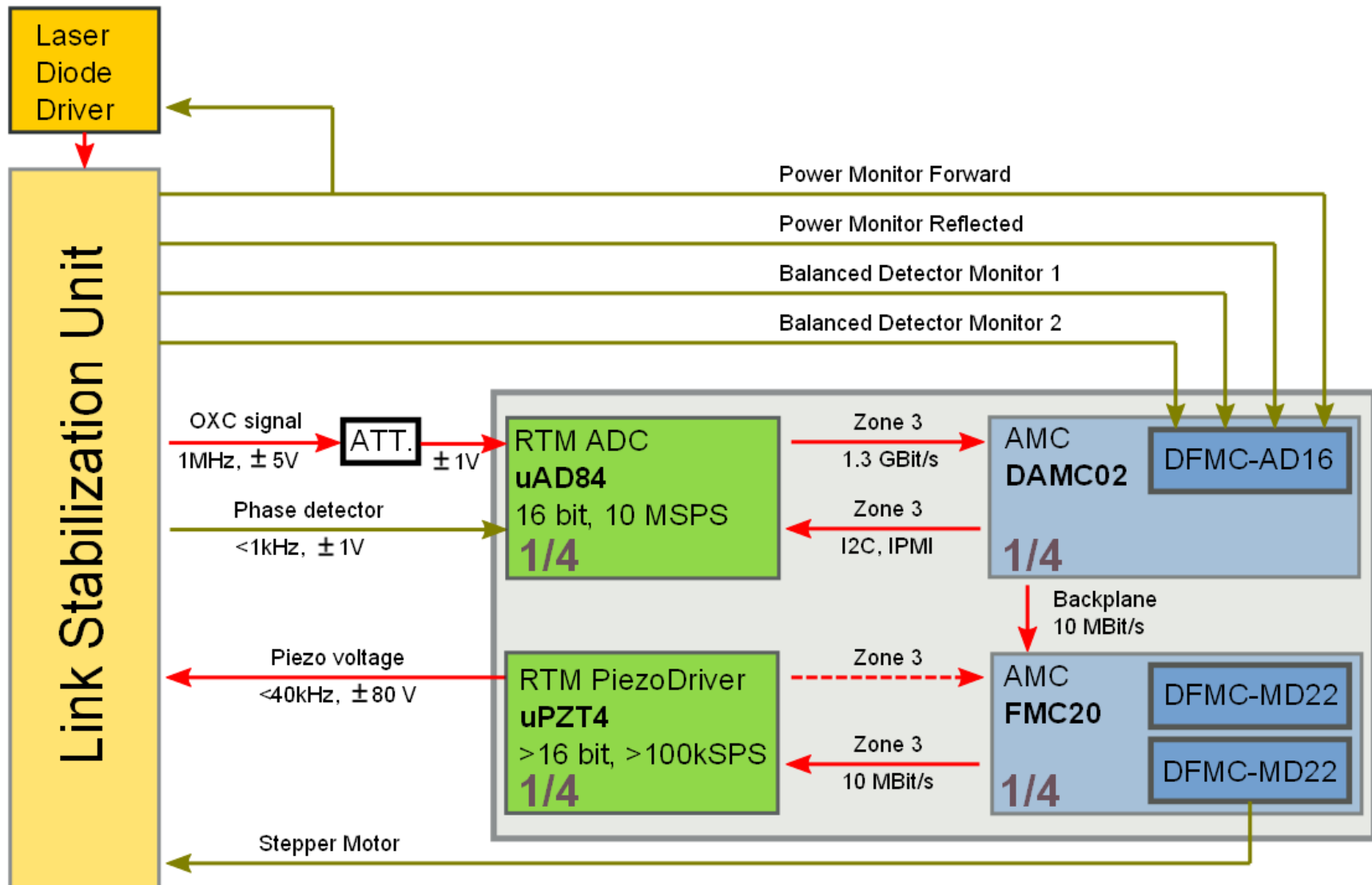
> Signals per 4 RF Links (in one box)

- Inputs:
 - 4 x Piezo: ± 100 (± 85) V
 - 8 x Stepper Motor
 - 8 x GPIO for SPI interface
 - (4 x GPIO for shutter)
- Outputs:
 - 4 x Phase Signal
 - 4 x Amplitude Signal
 - 8 x Power Monitor

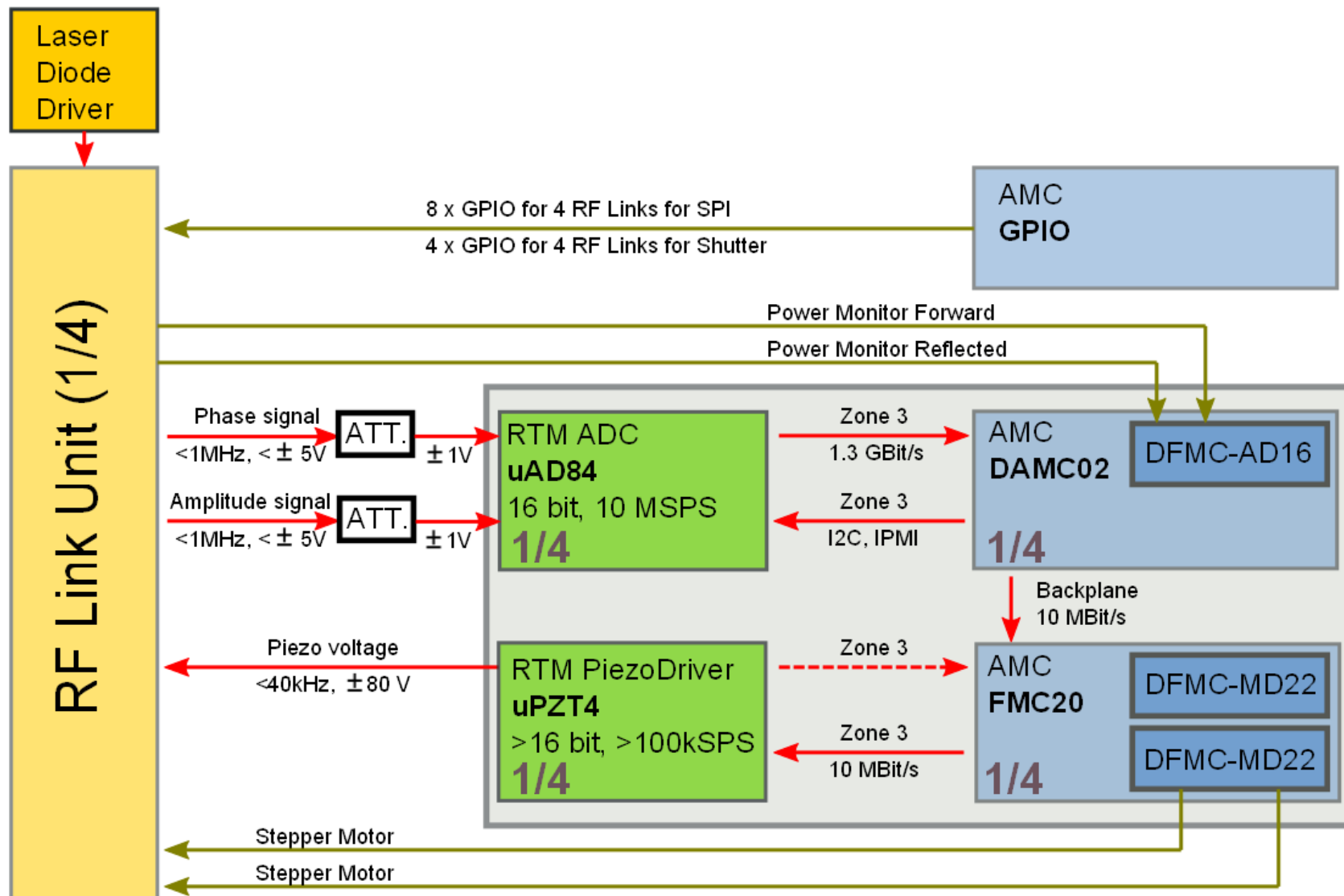
Additionally: 1 x Laser Diode Driver with CAN-Bus interface



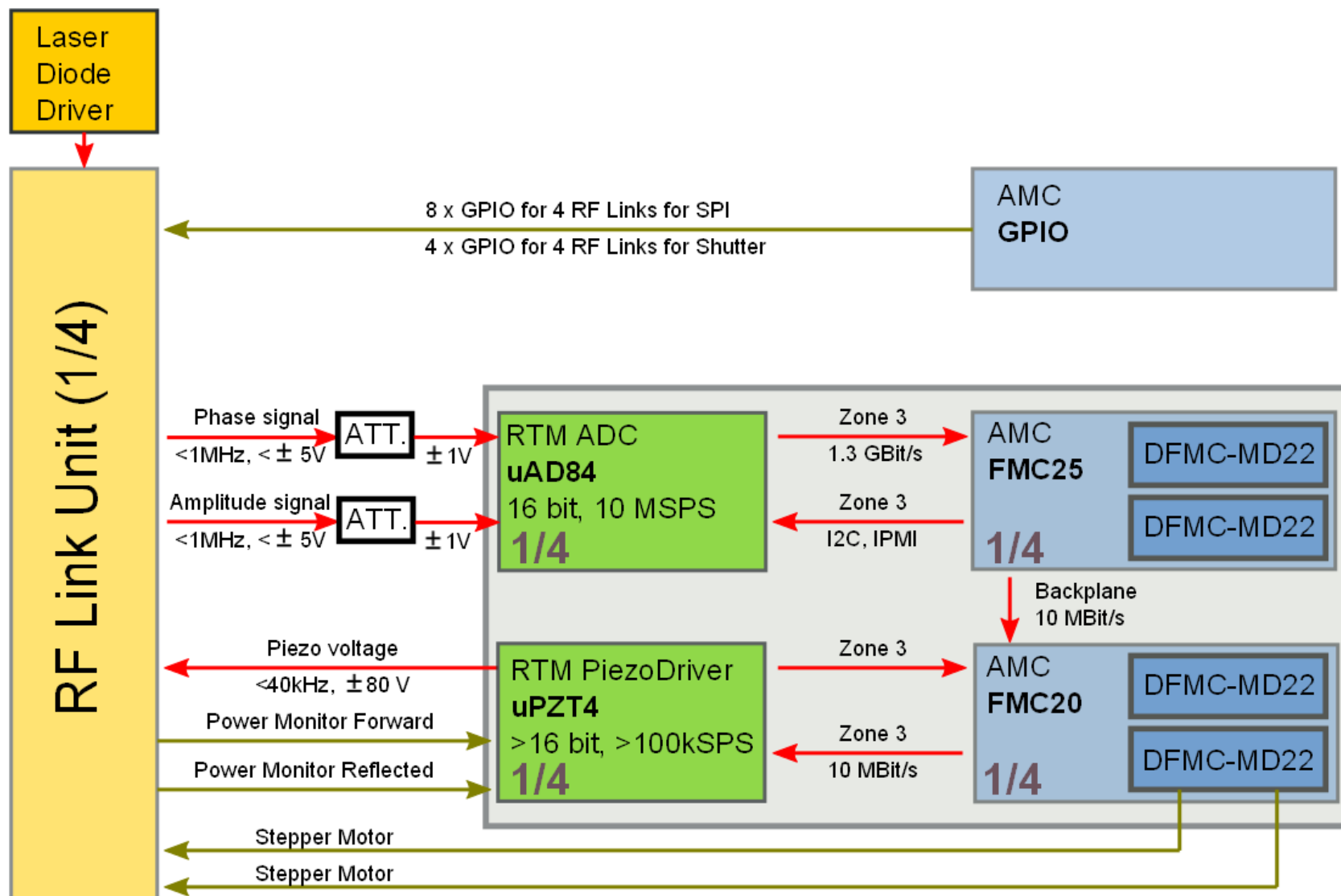
Link Setup – MTCA Signals



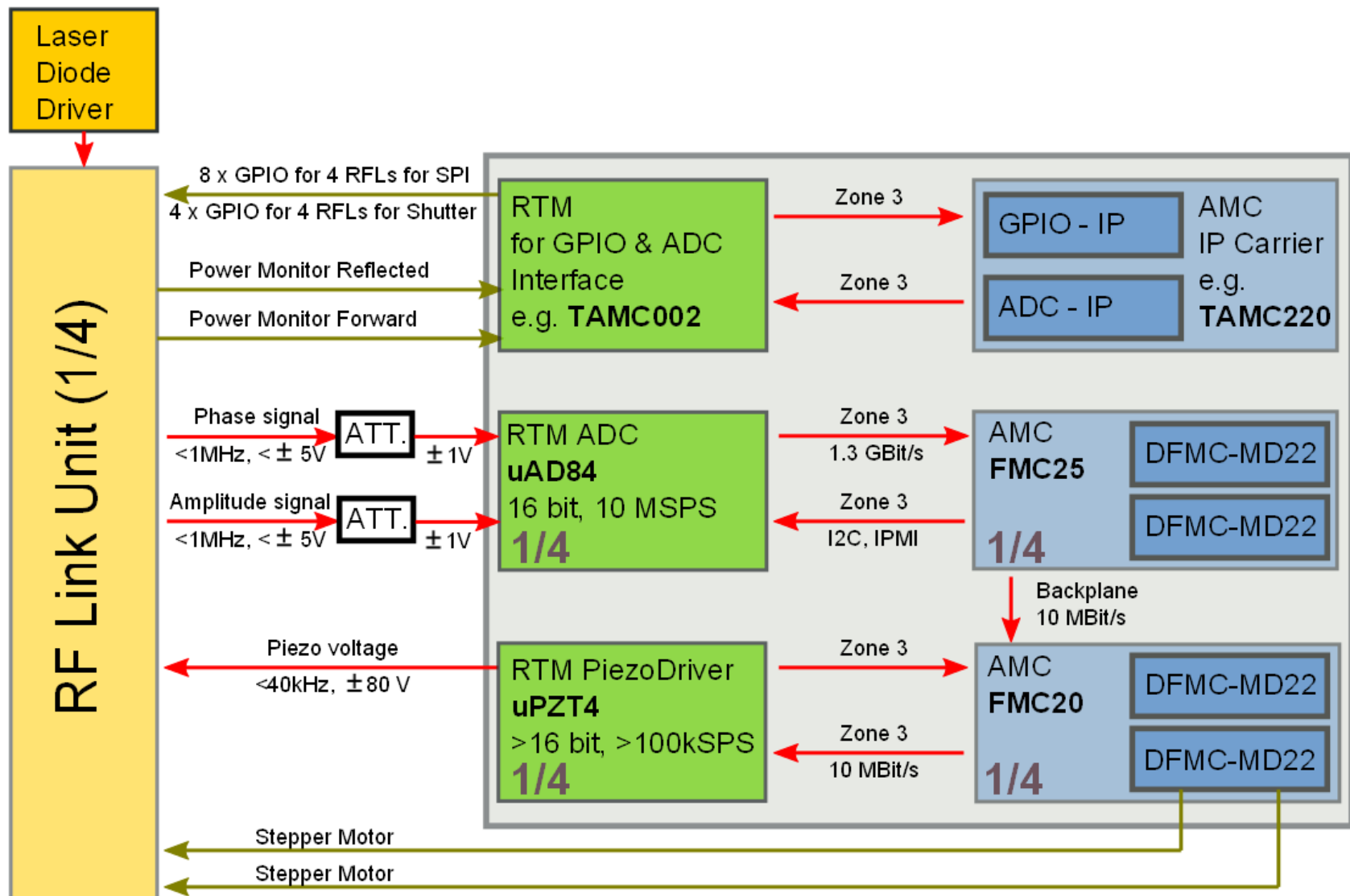
RF Link Setup – MTCA Signals



RF Link Setup – MTCA Signals – alternative configuration

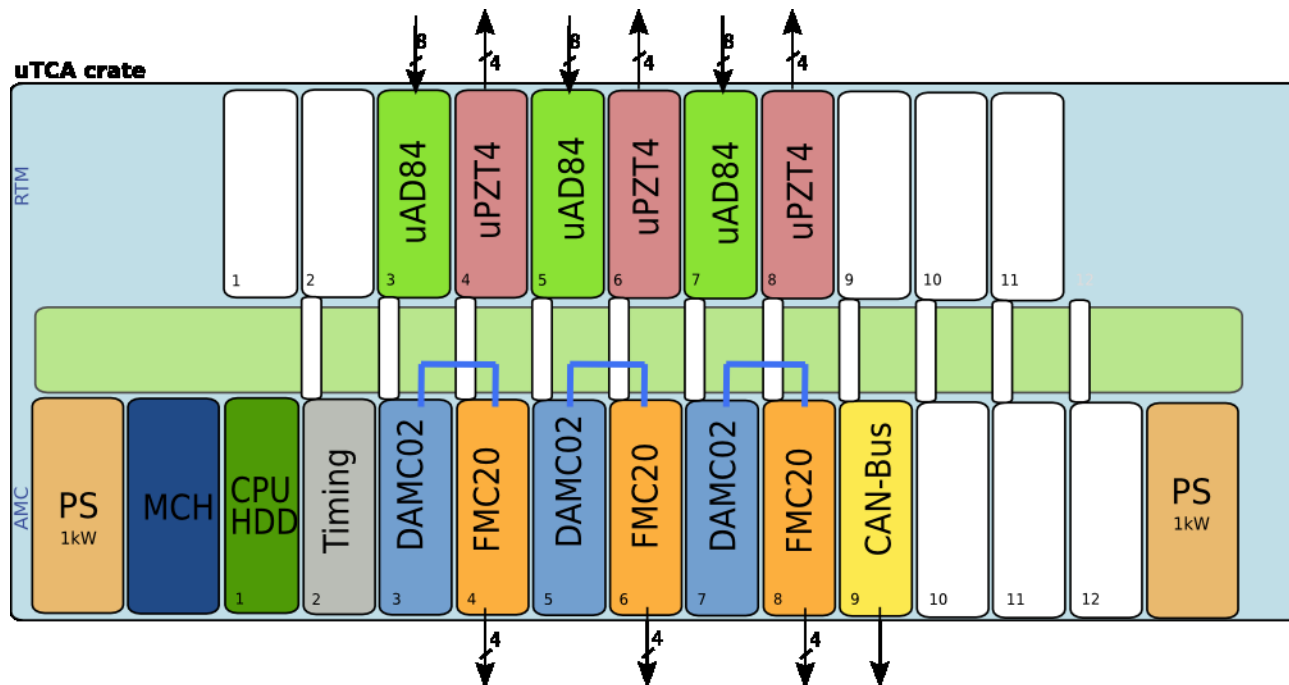


RF Link Setup – MTCA Signals – alternative 2



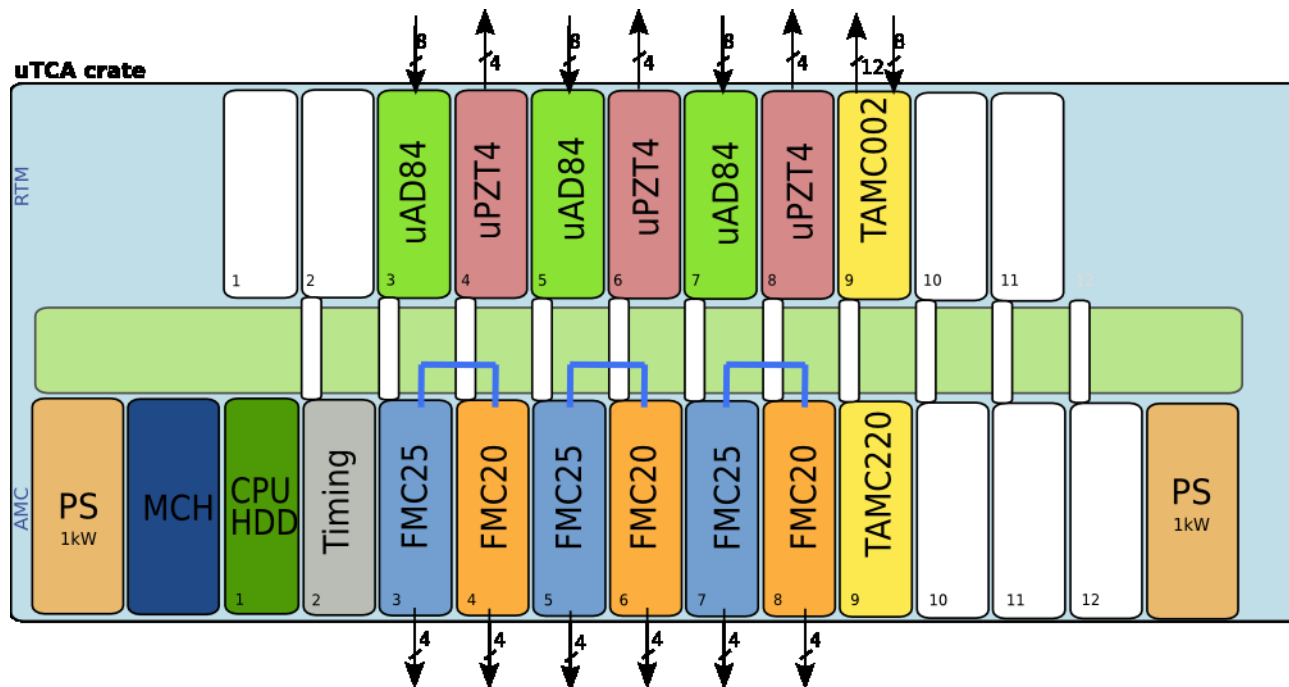
MTCA crate configuration

- On the optical table, 4 Links and 4 RF Links are grouped together
- uTCA hardware fits very well for controlling 4 Links with just 2 slots



MTCA crate configuration

- For the RF Links the situation is similar but a little more complicated due to the 2nd motor and the additional GPIO signals. With an TAMC board it could work...



Open Questions

> Crate

- Redundancy
- Cable Management
- PS 1 kW or 600 W?

> Piezo Driver

- Power supply extern or intern – RF backplane?
- Heat load
- Bandwidth → worst case: 5V / 100 nF / 40 kHz → 100 mA

> DAMC02 Communications

- Communication bandwidth sufficient?
- Latency
- Calculation power sufficient? (How many FIR coefficients?)

> Action plan

- Timeline: Availability of boards?
- Timeline: Software status?
- Test-system until Summer 2013



Thank You

