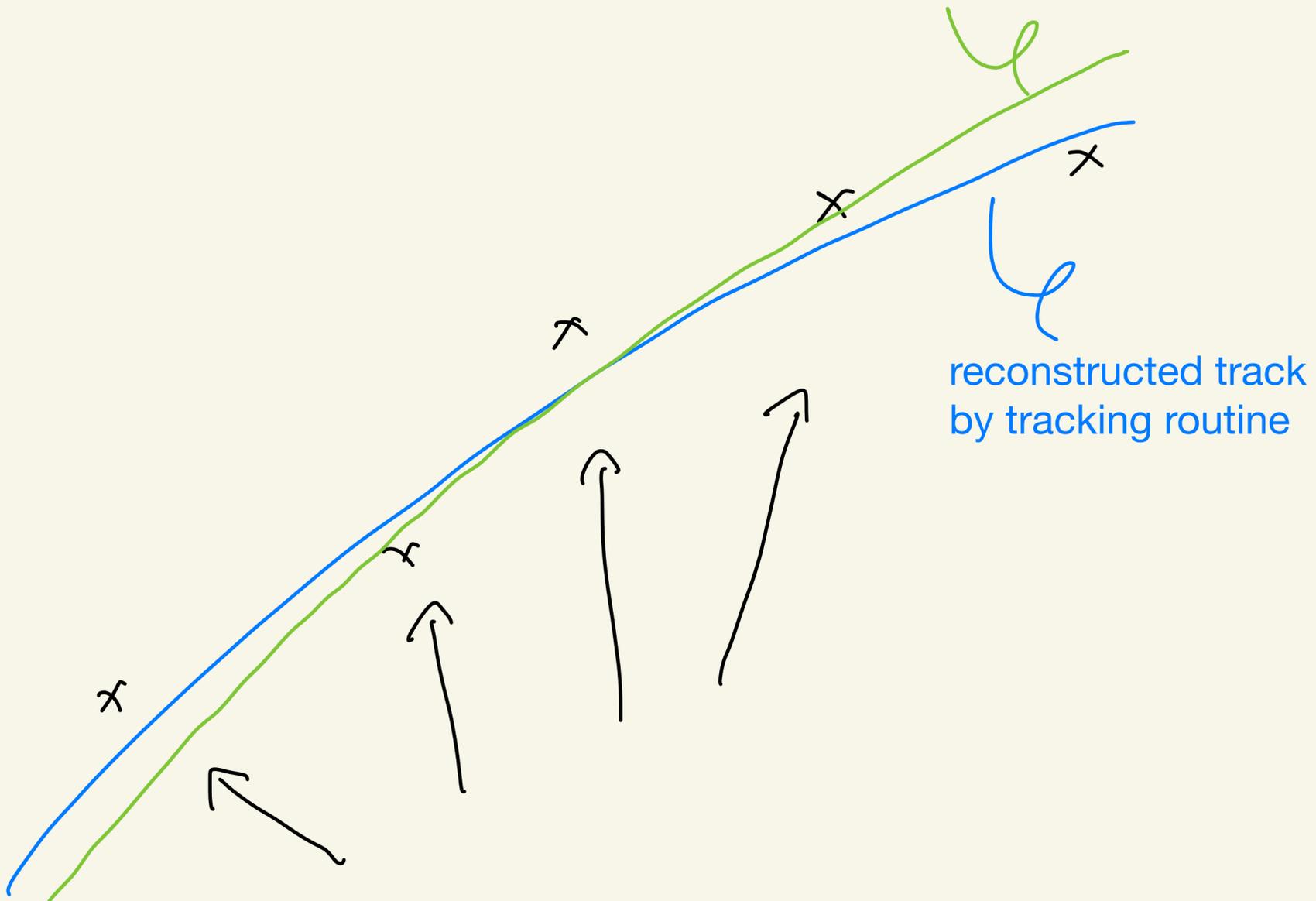


corrected track  
(pion, common vertex constrained)



calculate derivatives for each hit of the **corrected track** and passed them to Millepede minimization procedure

$$\frac{\partial(\text{residual})}{\partial(\text{alignment\&track parameters})}$$

