

QUANTUM SYSTEM IDENTIFICATION  
WITH LIMITED RESOURCES

DANIEL BURGARTH & KAZUYA YUASA  
(ABERYSTWYTH) (WASEDA)

NOTTINGHAM, 25/6/12

# OUTLINE

# OUTLINE

\* MOTIVATION

# OUTLINE

\* MOTIVATION

\* IDENTIFIABILITY WITH LIMITED RESOURCES

# OUTLINE

\* MOTIVATION

\* IDENTIFIABILITY WITH LIMITED RESOURCES

\* TOPOLOGICAL KNOWLEDGE

# OUTLINE

\* MOTIVATION

\* IDENTIFIABILITY WITH LIMITED RESOURCES

\* TOPOLOGICAL KNOWLEDGE

→ INFECTION

# OUTLINE

- \* MOTIVATION
- \* IDENTIFIABILITY WITH LIMITED RESOURCES
- \* TOPOLOGICAL KNOWLEDGE
  - INFECTION
- \* INDIRECT ESTIMATION & CONTROL

# OUTLINE

- \* MOTIVATION
- \* IDENTIFIABILITY WITH LIMITED RESOURCES
- \* TOPOLOGICAL KNOWLEDGE
  - INFECTION
- \* INDIRECT ESTIMATION & CONTROL
- \* OUTLOOK & CONCLUSIONS



# MOTIVATION

\* HI FI QUANTUM DEVICES REQUIRE ACCURATE MODELS

# MOTIVATION

- \* HI FI QUANTUM DEVICES REQUIRE ACCURATE MODELS
- \* STANDARD METHODS REQUIRE A COMPLETE SET OF MEASUREMENTS

# MOTIVATION

- \* HI FI QUANTUM DEVICES REQUIRE ACCURATE MODELS
- \* STANDARD METHODS REQUIRE A COMPLETE SET OF MEASUREMENTS
- \* WHAT IF THE AVAILABLE MEASUREMENTS ARE LIMITED ?

# MOTIVATION

- \* HI FI QUANTUM DEVICES REQUIRE ACCURATE MODELS
- \* STANDARD METHODS REQUIRE A COMPLETE SET OF MEASUREMENTS
- \* WHAT IF THE AVAILABLE MEASUREMENTS ARE LIMITED ?
- \* GIVEN AN EXPERIMENTAL SETUP, WHICH SYSTEMS CAN BE DISTINGUISHED IN PRINCIPLE ?

# MOTIVATION

- \* HI FI QUANTUM DEVICES REQUIRE ACCURATE MODELS
- \* STANDARD METHODS REQUIRE A COMPLETE SET OF MEASUREMENTS
- \* WHAT IF THE AVAILABLE MEASUREMENTS ARE LIMITED ?
- \* GIVEN AN EXPERIMENTAL SETUP, WHICH SYSTEMS CAN BE DISTINGUISHED IN PRINCIPLE ?
- \* ANALAGOUS TO REACHABLE SET ("WHAT CAN I DO?"), NO PROTOCOL SPECIFIED

# MOTIVATION

- \* HI FI QUANTUM DEVICES REQUIRE ACCURATE MODELS
  - \* STANDARD METHODS REQUIRE A COMPLETE SET OF MEASUREMENTS
  - \* WHAT IF THE AVAILABLE MEASUREMENTS ARE LIMITED ?
  - \* GIVEN AN EXPERIMENTAL SETUP, WHICH SYSTEMS CAN BE DISTINGUISHED IN PRINCIPLE ?
  - \* ANALAGOUS TO REACHABLE SET ("WHAT CAN I DO?"), NO PROTOCOL SPECIFIED
- GENERIC FRAMEWORK : ULTIMATE LIMIT OF PROTOCOLS, GUIDANCE TO "MISSING PARTS"

SETUP

SETUP (ANALOGOUS TO SONTAG)



SETUP (ANALOGOUS TO SONTAG)

\* FINITE DIMENSIONAL UNITARY SYSTEM

SETUP (ANALOGOUS TO SONTAG)

\* FINITE DIMENSIONAL UNITARY SYSTEM

SETUP (ANALOGOUS TO SONTAG)

\* FINITE DIMENSIONAL UNITARY SYSTEM

\* CHARACTERIZED BY

SETUP (ANALOGOUS TO SONTAG)

\* FINITE DIMENSIONAL UNITARY SYSTEM

\* CHARACTERIZED BY

INITIAL STATE  $s_0$

# SETUP (ANALOGOUS TO SONTAG)

\* FINITE DIMENSIONAL UNITARY SYSTEM

\* CHARACTERIZED BY

INITIAL STATE  $s_0$

HAMILTONIAN  $H_0$

# SETUP (ANALOGOUS TO SONTAG)

\* FINITE DIMENSIONAL UNITARY SYSTEM

\* CHARACTERIZED BY

INITIAL STATE  $\rho_0$

HAMILTONIAN  $H_0$

THINGS WE CAN MEASURE  $M_\ell$

# SETUP (ANALOGOUS TO SONTAG)

\* FINITE DIMENSIONAL UNITARY SYSTEM

\* CHARACTERIZED BY

INITIAL STATE  $s_0$

HAMILTONIAN  $H_0$

THINGS WE CAN MEASURE  $M_\ell$

FIELDS WE CAN APPLY  $H_k$

SETUP (ANALOGOUS TO SONTAG)

\* FINITE DIMENSIONAL UNITARY SYSTEM

\* CHARACTERIZED BY

INITIAL STATE	$s_0$	}	$\sigma$
HAMILTONIAN	$H_0$		
THINGS WE CAN MEASURE	$M_l$		
FIELDS WE CAN APPLY	$H_k$		



# SETUP (ANALOGOUS TO SONTAG)

\* FINITE DIMENSIONAL UNITARY SYSTEM

\* CHARACTERIZED BY

INITIAL STATE	$s_0$	}	$\sigma$
HAMILTONIAN	$H_0$		
THINGS WE CAN MEASURE	$M_l$		
FIELDS WE CAN APPLY	$H_k$		

\* ASSUME  $\infty$  MANY COPIES OF SYSTEM

# SETUP (ANALOGOUS TO SONTAG)

\* FINITE DIMENSIONAL UNITARY SYSTEM

\* CHARACTERIZED BY

INITIAL STATE	$s_0$	}	$\sigma$
HAMILTONIAN	$H_0$		
THINGS WE CAN MEASURE	$M_l$		
FIELDS WE CAN APPLY	$H_k$		

\* ASSUME  $\infty$  MANY COPIES OF SYSTEM

\* WHICH SYSTEMS  $\hat{\sigma}$  ARE INDISTINGUISHABLE?

"INDISTINGUISHABLE" ∴

"INDISTINGUISHABLE":

\* WHATEVER WE DO, MEASURE SAME

"INDISTINGUISHABLE":

\* WHATEVER WE DO, MEASURE SAME

PULSES

$$f_k(t) \rightarrow H(t) = H_0 + \sum f_k(t) H_k \rightarrow g(t) \rightarrow \langle M_e(t) \rangle$$

"INDISTINGUISHABLE":

\* WHATEVER WE DO, MEASURE SAME

PULSES

$$f_k(t) \rightarrow H(t) = H_0 + \sum f_k(t) H_k \rightarrow g(t) \rightarrow \langle M_e(t) \rangle$$

"INDISTINGUISHABLE":

\* WHATEVER WE DO, MEASURE SAME

PULSES

$$f_k(t) \rightarrow H(t) = H_0 + \sum f_k(t) H_k \rightarrow g(t) \rightarrow \langle M_e(t) \rangle$$

\* INDISTINGUISHABLE:  $\langle M_e(t) \rangle = \langle \hat{M}_e(t) \rangle \quad \forall t$   
FOR IDENTICAL PULSES

"INDISTINGUISHABLE":

\* WHATEVER WE DO, MEASURE SAME

PULSES

$$f_k(t) \rightarrow H(t) = H_0 + \sum f_k(t) H_k \rightarrow g(t) \rightarrow \langle M_e(t) \rangle$$

\* INDISTINGUISHABLE:  $\langle M_e(t) \rangle = \langle \hat{M}_e(t) \rangle \quad \forall t$   
FOR IDENTICAL PULSES

\* UNITARILY RELATED SYSTEMS ARE INDISTINGUISHABLE  
 $W \hat{O} W^\dagger = O \quad (W \hat{S}_0 W^\dagger = S_0, W \hat{H}_0 W^\dagger = H_0, \dots)$



"INDISTINGUISHABLE":

\* WHATEVER WE DO, MEASURE SAME

PULSES

$$f_k(t) \rightarrow H(t) = H_0 + \sum f_k(t) H_k \rightarrow g(t) \rightarrow \langle M_e(t) \rangle$$

\* INDISTINGUISHABLE:  $\langle M_e(t) \rangle = \langle \hat{M}_e(t) \rangle \quad \forall t$   
FOR IDENTICAL PULSES

\* UNITARILY RELATED SYSTEMS ARE INDISTINGUISHABLE

$$W \hat{O} W^\dagger = O \quad (W \hat{S}_0 W^\dagger = S_0, W \hat{H}_0 W^\dagger = H_0, \dots)$$

("ANONYMOUS TRANSLATOR")

\* BUT NOT ALL INDISTINGUISHABLE SYSTEMS ARE UNITARILY RELATED

\* BUT NOT ALL INDISTINGUISHABLE SYSTEMS ARE UNITARILY RELATED

\* ALL PARTS OF HILBERT SPACE MUST BE REACHED BY PULSES

\* BUT NOT ALL INDISTINGUISHABLE SYSTEMS ARE UNITARILY RELATED

\* ALL PARTS OF HILBERT SPACE MUST BE REACHED BY PULSES

THEOREM: IF  $\sigma$  AND  $\hat{\sigma}$  CONTROLLABLE,

INDISTINGUISHABLE  $\Leftrightarrow$  UNITARILY RELATED

(DB & K. YUASA, PRL '12)

\* BUT NOT ALL INDISTINGUISHABLE SYSTEMS ARE UNITARILY RELATED

\* ALL PARTS OF HILBERT SPACE MUST BE REACHED BY PULSES

THEOREM: IF  $\sigma$  AND  $\hat{\sigma}$  CONTROLLABLE,

INDISTINGUISHABLE  $\Leftrightarrow$  UNITARILY RELATED

(DB & K. YUASA, PRL '12)

→ CONTROLLABLE:  $L = \langle H_0, H_1, \dots, H_k \rangle_{[i,j]} = su(d)$

# ESSENTIALS FROM PROOF

## ESSENTIALS FROM PROOF

\* FORMULATE ALL IN LIOVILLE SPACE :

## ESSENTIALS FROM PROOF

\* FORMULATE ALL IN LIOVILLE SPACE :

$$g_0 \rightarrow |g_0)$$



## ESSENTIALS FROM PROOF

\* FORMULATE ALL IN LIOVILLE SPACE :

$$g_0 \rightarrow |g_0\rangle$$

$$\text{tr}(M_e \cdot) \rightarrow (M_e|$$

## ESSENTIALS FROM PROOF

\* FORMULATE ALL IN LIOVILLE SPACE :

$$g_0 \rightarrow |g_0\rangle$$

$$\text{tr}(M_e \cdot) \rightarrow (M_e |$$

$$i[H_k, \cdot] \rightarrow \mathcal{L}_k$$

## ESSENTIALS FROM PROOF

\* FORMULATE ALL IN LIOVILLE SPACE :

$$g_0 \rightarrow |g_0\rangle$$

$$\text{tr}(M_e \cdot) \rightarrow (M_e |$$

$$i[H_{\kappa}, \cdot] \rightarrow \mathcal{L}_{\kappa}$$

\* FORMULATE INDISTINGUISHABILITY ALGEBRAICALLY

$$(M_e | \mathcal{L}_{\kappa_1} \mathcal{L}_{\kappa_2} \cdots \mathcal{L}_{\kappa_j} | g_i) = (\hat{M}_e | \hat{\mathcal{L}}_{\kappa_1} \hat{\mathcal{L}}_{\kappa_2} \cdots \hat{\mathcal{L}}_{\kappa_j} | \hat{g}_i)$$

## ESSENTIALS FROM PROOF

\* FORMULATE ALL IN LIOVILLE SPACE :

$$g_0 \rightarrow |g_0\rangle$$

$$\text{tr}(M_e \cdot) \rightarrow (M_e |$$

$$i[H_k, \cdot] \rightarrow \mathcal{L}_k$$

\* FORMULATE INDISTINGUISHABILITY ALGEBRAICALLY

\* CONSTRUCT SIMILARITY TRANSFORM  $\mathcal{L}_k = T \hat{\mathcal{L}}_k T^{-1}$

## ESSENTIALS FROM PROOF

\* FORMULATE ALL IN LIOVILLE SPACE :

$$g_0 \rightarrow |g_0\rangle$$

$$\text{tr}(M_e \cdot) \rightarrow (M_e |$$

$$i[H_k, \cdot] \rightarrow \mathcal{L}_k$$

\* FORMULATE INDISTINGUISHABILITY ALGEBRAICALLY

\* CONSTRUCT SIMILARITY TRANSFORM  $\mathcal{L}_k = T \hat{\mathcal{L}}_k T^{-1}$

\* GO BACK TO MILBERT SPACE

## ESSENTIALS FROM PROOF

\* FORMULATE ALL IN LIOVILLE SPACE :

$$g_0 \rightarrow |g_0\rangle$$

$$\text{tr}(M_e \cdot) \rightarrow (M_e |$$

$$i[H_k, \cdot] \rightarrow \mathcal{L}_k$$

\* FORMULATE INDISTINGUISHABILITY ALGEBRAICALLY

\* CONSTRUCT SIMILARITY TRANSFORM  $\mathcal{L}_k = T \hat{\mathcal{L}}_k T^{-1}$

\* GO BACK TO MILBERT SPACE ( $\mathcal{L}_k = -i[H_k, \cdot]$ )

## TAKING PRE-KNOWLEDGE INTO ACCOUNT

\* TYPICALLY, COMPONENTS OF

$$\sigma = (s_0, H_0, H_k, M_e) \quad \text{ARE KNOWN :}$$

## TAKING PRE-KNOWLEDGE INTO ACCOUNT

\* TYPICALLY, COMPONENTS OF

$$\sigma = (S_0, H_0, H_k, M_e) \quad \text{ARE KNOWN :}$$

→  $M_e$  (MEASUREMENTS)



## TAKING PRE-KNOWLEDGE INTO ACCOUNT

\* TYPICALLY, COMPONENTS OF

$$\sigma = (S_0, H_0, H_k, M_e) \quad \text{ARE KNOWN :}$$

→  $M_e$  (MEASUREMENTS)

→  $H_k$  (CONTROL)

## TAKING PRE-KNOWLEDGE INTO ACCOUNT

\* TYPICALLY, COMPONENTS OF

$$\sigma = (S_0, H_0, H_k, M_e) \quad \text{ARE KNOWN :}$$

→  $M_e$  (MEASUREMENTS)

→  $H_k$  (CONTROL)

X KNOWN →  $X = W X W^+$

## TAKING PRE-KNOWLEDGE INTO ACCOUNT

\* TYPICALLY, COMPONENTS OF

$$\sigma = (S_0, H_0, H_k, M_e) \quad \text{ARE KNOWN :}$$

→  $M_e$  (MEASUREMENTS)

→  $H_k$  (CONTROL)

$$X \text{ KNOWN} \quad \rightarrow \quad X = W X W^+ \quad \leadsto \quad [X, W] = 0$$

## TAKING PRE-KNOWLEDGE INTO ACCOUNT

\* TYPICALLY, COMPONENTS OF

$$\sigma = (S_0, H_0, H_k, M_e) \quad \text{ARE KNOWN:}$$

→  $M_e$  (MEASUREMENTS)

→  $H_k$  (CONTROL)

$$X \text{ KNOWN} \quad \rightarrow \quad X = W X W^+ \quad \leadsto \quad [X, W] = 0$$

→ EACH KNOWN  $X$  RESTRICTS THE POSSIBLE  $W$ 'S

$$\leadsto X \text{ KNOWN, } Y \text{ KNOWN} \Rightarrow [w, [x, y]] = 0$$

$$\leadsto X \text{ KNOWN, } Y \text{ KNOWN} \Rightarrow [W, [X, Y]] = 0$$

$$\leadsto [W, L_{\text{KNOW}}] = 0$$

$$\leadsto X \text{ KNOWN, } Y \text{ KNOWN} \Rightarrow [W, [X, Y]] = 0$$

$$\leadsto [W, L_{\text{KNOW}}] = 0$$

WITH  $L_{\text{KNOW}} = \langle i X_1, \dots, \rangle_{[i, \cdot]} X_i \text{ KNOWN}$

$$\leadsto X \text{ KNOWN}, Y \text{ KNOWN} \Rightarrow [W, [X, Y]] = 0$$

$$\leadsto [W, L_{\text{KNOW}}] = 0$$

WITH  $L_{\text{KNOW}} = \langle i X_1, \dots, \rangle_{[.,.]} \quad X_i \text{ KNOWN}$

EG  $\langle i S_0, i H_7, i M_2 \rangle_{[.,.]}$



$$\leadsto X \text{ KNOWN, } Y \text{ KNOWN} \Rightarrow [W, [X, Y]] = 0$$

$$\leadsto [W, L_{\text{KNOW}}] = 0$$

WITH  $L_{\text{KNOW}} = \langle i X_1, \dots, \rangle_{[.,.]} X_i \text{ KNOWN}$

EG  $\langle i S_0, i H_7, i M_2 \rangle_{[.,.]} \quad \text{WEIRD!}$

$$\leadsto X \text{ KNOWN, } Y \text{ KNOWN} \Rightarrow [W, [X, Y]] = 0$$

$$\leadsto [W, L_{\text{KNOW}}] = 0$$

WITH  $L_{\text{KNOW}} = \langle iX_1, \dots, \rangle_{[.,.]} X_i \text{ KNOWN}$

EG  $\langle iS_0, iH_7, iM_2 \rangle_{[.,.]} \quad \text{WEIRD!}$

$$L_{\text{CONTROL}} = \text{SU}(n) :$$

$$\leadsto X \text{ KNOWN, } Y \text{ KNOWN} \Rightarrow [W, [X, Y]] = 0$$

$$\leadsto [W, L_{\text{KNOW}}] = 0$$

WITH  $L_{\text{KNOW}} = \langle i X_1, \dots, \rangle_{[c, \cdot]} X_i \text{ KNOWN}$

EG  $\langle i \mathcal{S}_0, i \mathcal{H}_7, i \mathcal{M}_2 \rangle_{[c, \cdot]}$  WEIRD!

$$L_{\text{CONTROL}} = \text{SU}(n) :$$

$$\{L_{\text{KNOW}}\}' = \{c \cdot 1\} \Leftrightarrow \text{IDENTIFIABLE}$$

$$\leadsto X \text{ KNOWN, } Y \text{ KNOWN} \Rightarrow [W, [X, Y]] = 0$$

$$\leadsto [W, L_{\text{KNOW}}] = 0$$

WITH  $L_{\text{KNOW}} = \langle i X_1, \dots, \rangle_{[.,.]} X_i \text{ KNOWN}$

EG  $\langle i S_0, i H_7, i M_2 \rangle_{[.,.]} \quad \text{WEIRD!}$

$$L_{\text{CONTROL}} = \text{SU}(n) :$$

$$\{L_{\text{KNOW}}\}' = \{c \cdot 1\} \Leftrightarrow \text{IDENTIFIABLE}$$

$\rightarrow$  ALMOST EVERYTHING IDENTIFIABLE WITH FEW MEASUREMENTS.

## OTHER TYPES OF PRE-KNOWLEDGE

\* X KNOWN APPROXIMATELY

## OTHER TYPES OF PRE-KNOWLEDGE

\* X KNOWN APPROXIMATELY

\* X CONSISTS OF TWO-BODY INTERACTIONS

## OTHER TYPES OF PRE-KNOWLEDGE

- \* X KNOWN APPROXIMATELY
- \* X CONSISTS OF TWO-BODY INTERACTIONS
- \* X HAS CERTAIN SYMMETRY

## OTHER TYPES OF PRE-KNOWLEDGE

\* X KNOWN APPROXIMATELY

\* X CONSISTS OF TWO-BODY INTERACTIONS

\* X HAS CERTAIN SYMMETRY





## OTHER TYPES OF PRE-KNOWLEDGE

- \* X KNOWN APPROXIMATELY
- \* X CONSISTS OF TWO-BODY INTERACTIONS
- \* X HAS CERTAIN SYMMETRY
- \* X HAS CERTAIN TOPOLOGY



?

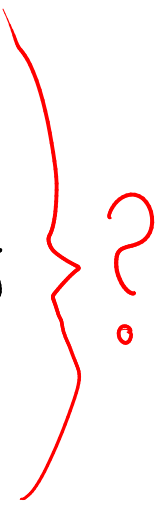
## OTHER TYPES OF PRE-KNOWLEDGE

\* X KNOWN APPROXIMATELY

\* X CONSISTS OF TWO-BODY INTERACTIONS

\* X HAS CERTAIN SYMMETRY

\* X HAS CERTAIN TOPOLOGY



## OTHER TYPES OF PRE-KNOWLEDGE

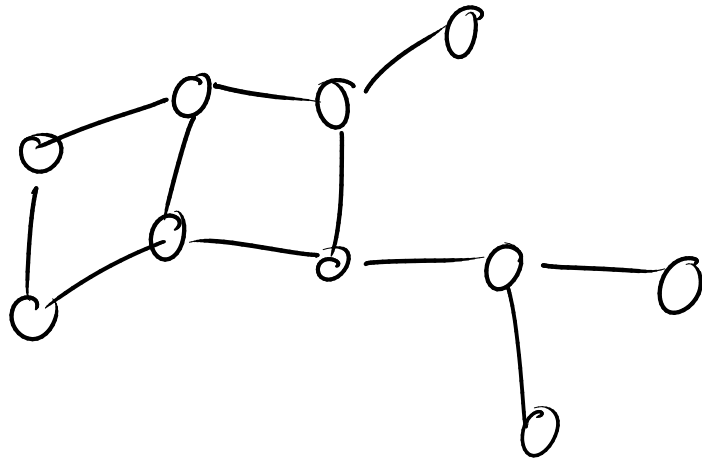
- \* X KNOWN APPROXIMATELY
- \* X CONSISTS OF TWO-BODY INTERACTIONS
- \* X HAS CERTAIN SYMMETRY
- \* X HAS CERTAIN TOPOLOGY



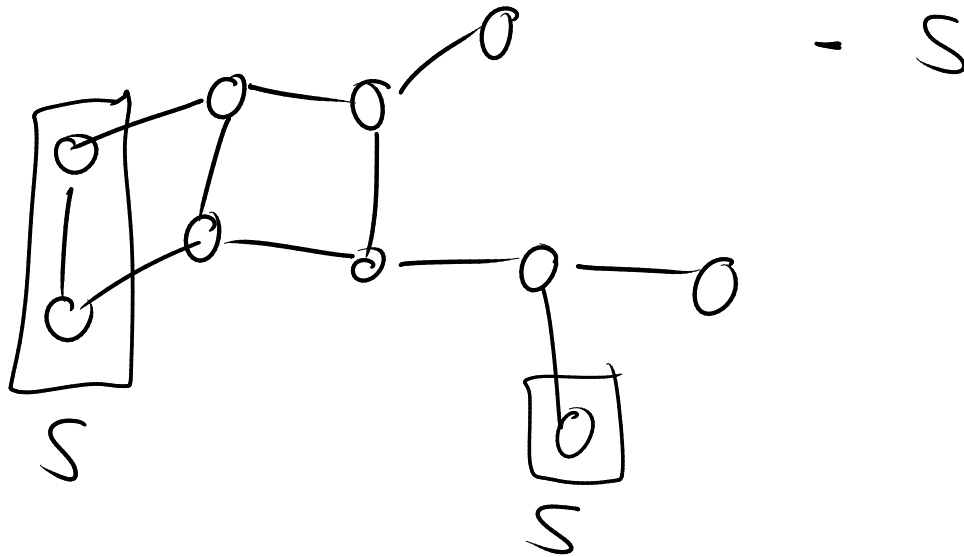
INTERMEZZO

# GRAPH INFECTION

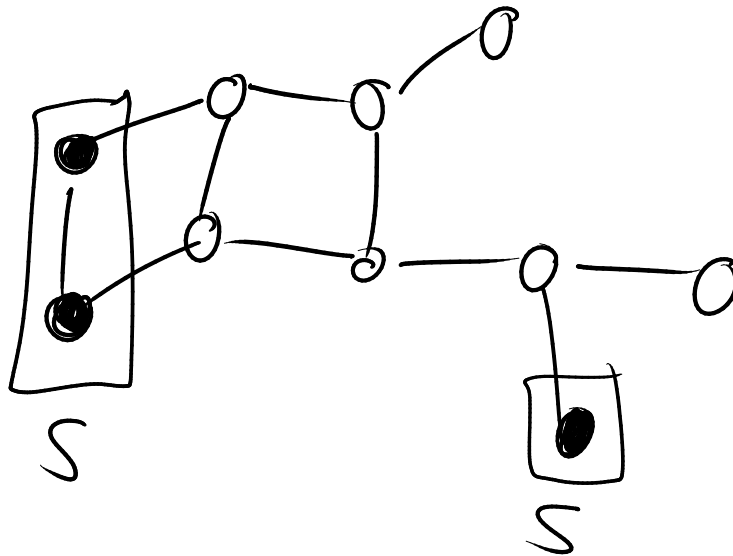
# GRAPH INFECTION



# GRAPH INFECTION

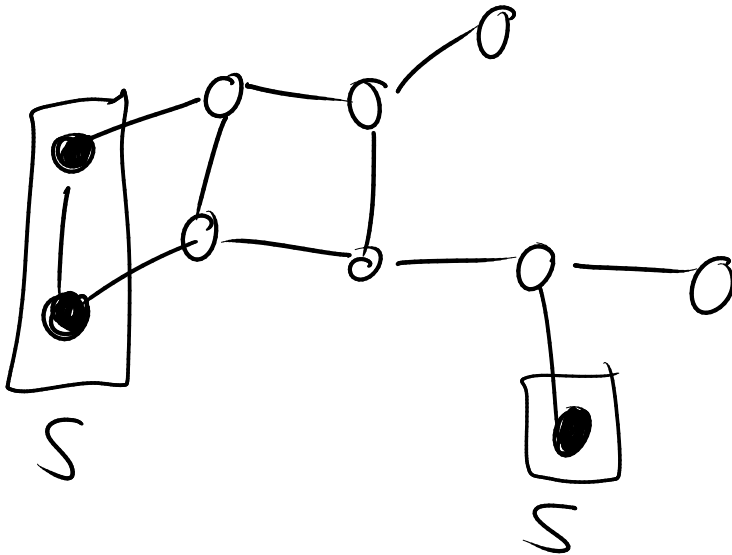


# GRAPH INFECTION



- S INFECTED

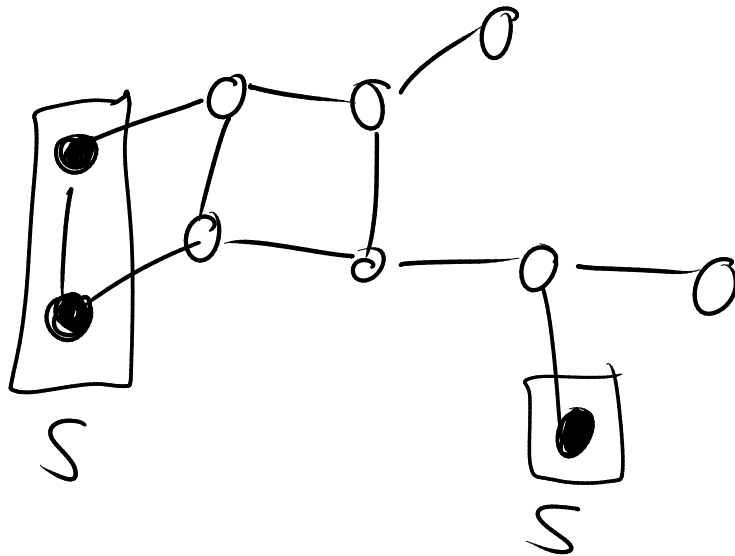
# GRAPH INFECTION



- S INFECTED
- ONCE INFECTED, REMAINS

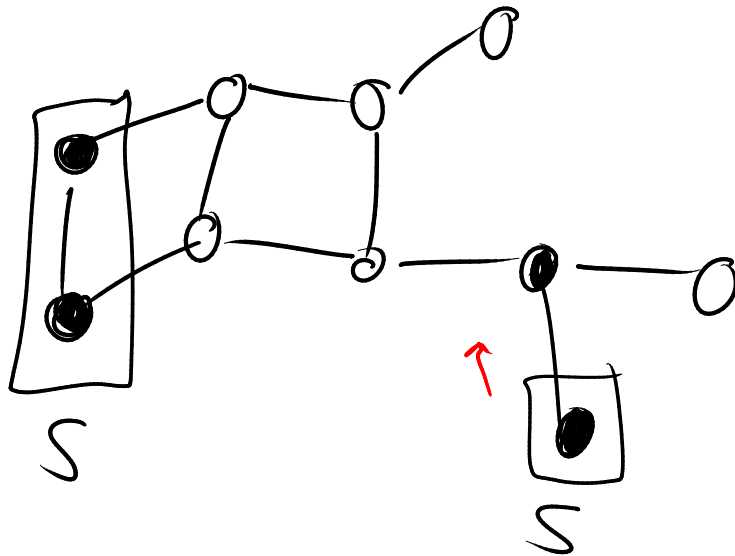


# GRAPH INFECTION



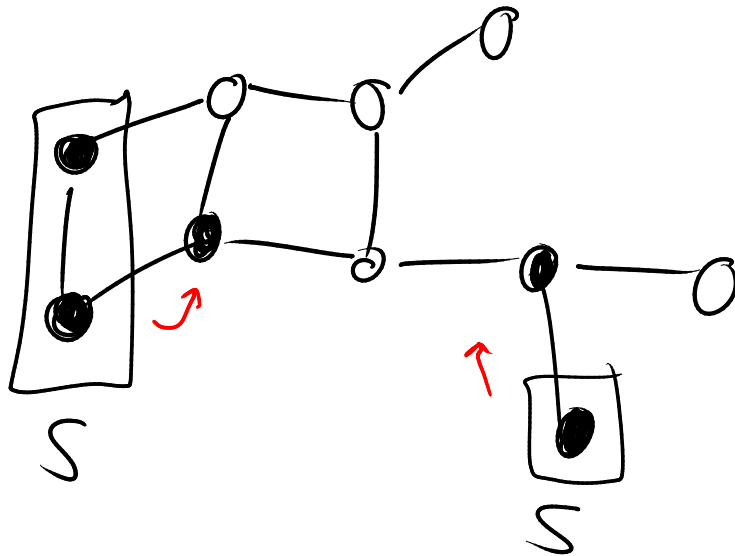
- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

# GRAPH INFECTION



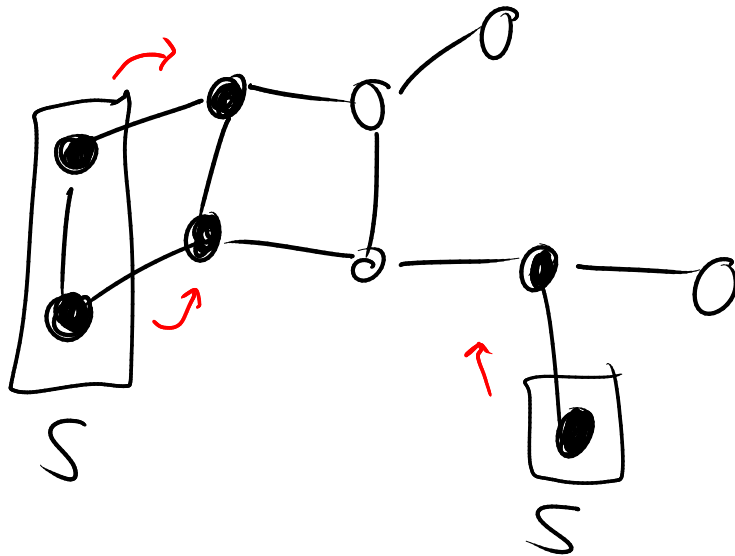
- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

# GRAPH INFECTION



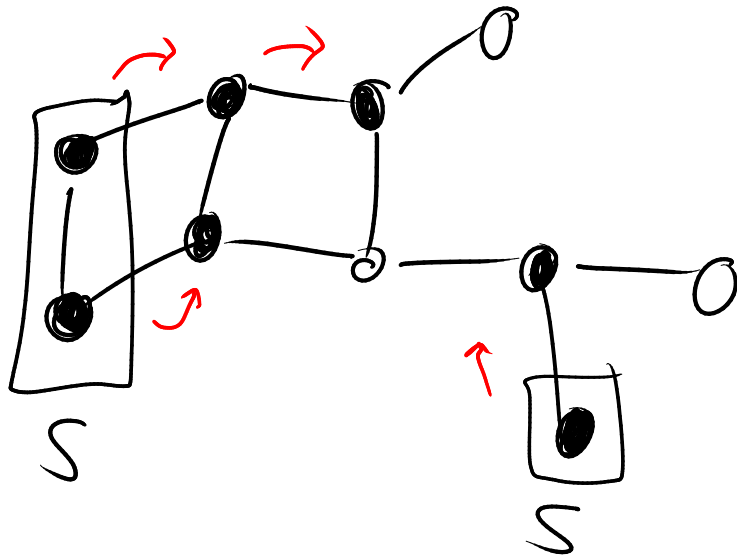
- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

# GRAPH INFECTION



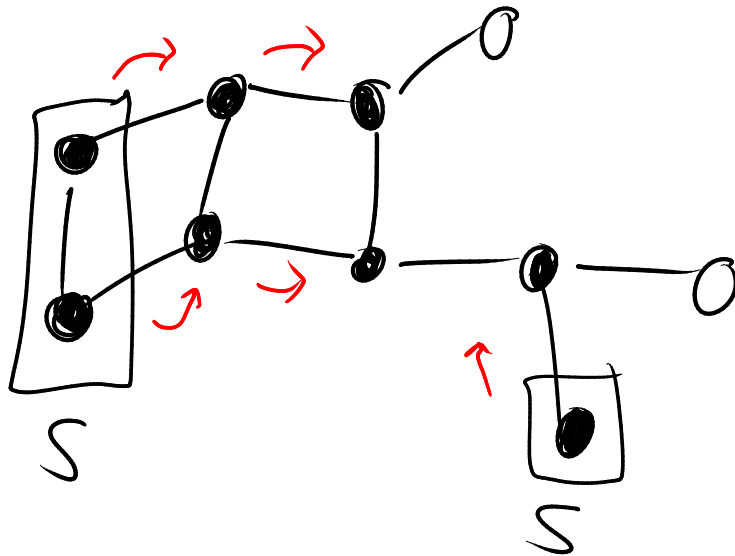
- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

# GRAPH INFECTION



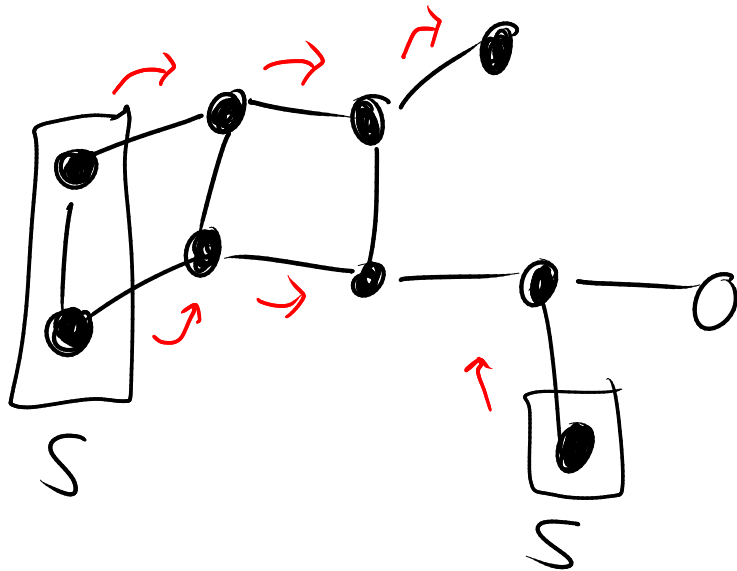
- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

# GRAPH INFECTION



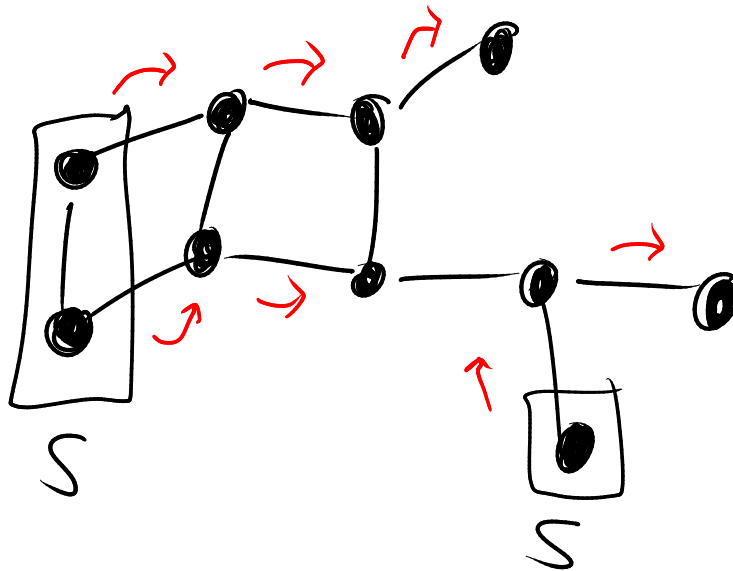
- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

# GRAPH INFECTION



- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

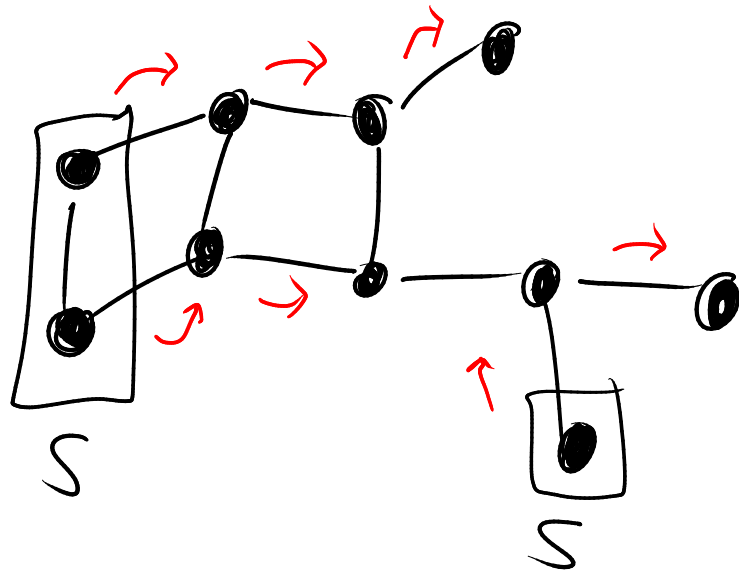
# GRAPH INFECTION



- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR



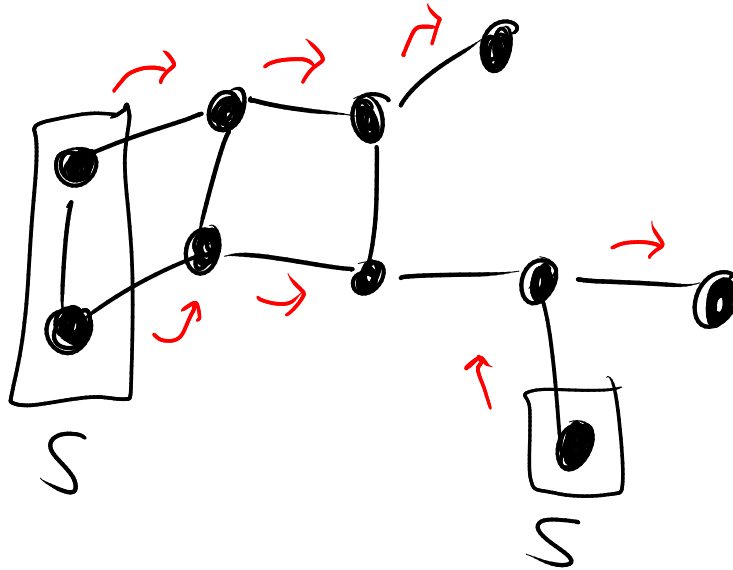
# GRAPH INFECTION



- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

\* IF ALL END UP INFECTED, CALL S INFECTING

# GRAPH INFECTION

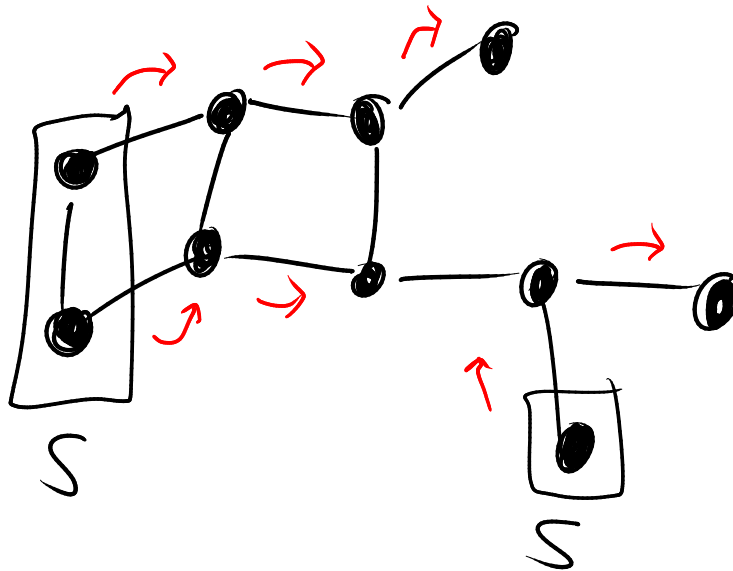


- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

\* IF ALL END UP INFECTED, CALL S INFECTING

\* TYPICALLY "SURFACE" IS INFECTING IF SPARSE

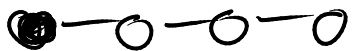
# GRAPH INFECTION



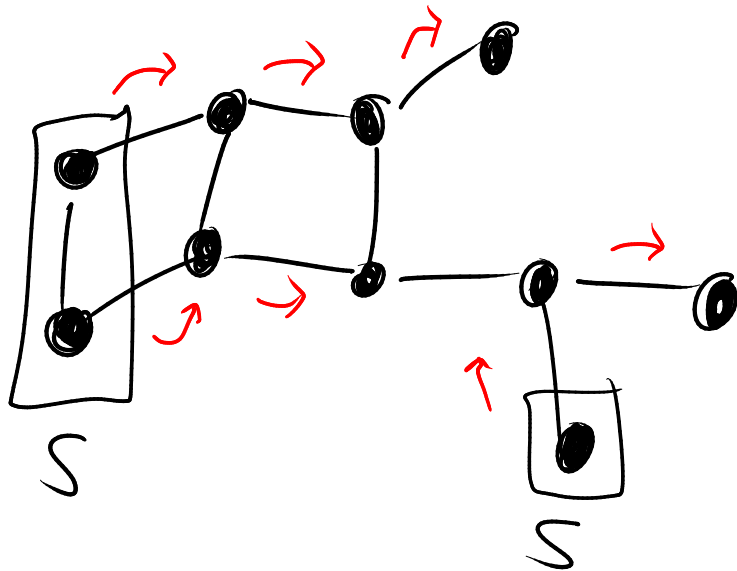
- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

\* IF ALL END UP INFECTED, CALL S INFECTING

\* TYPICALLY "SURFACE" IS INFECTING IF SPARSE



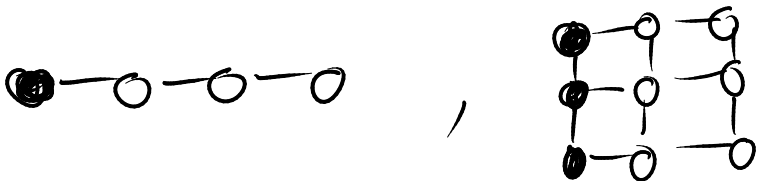
# GRAPH INFECTION



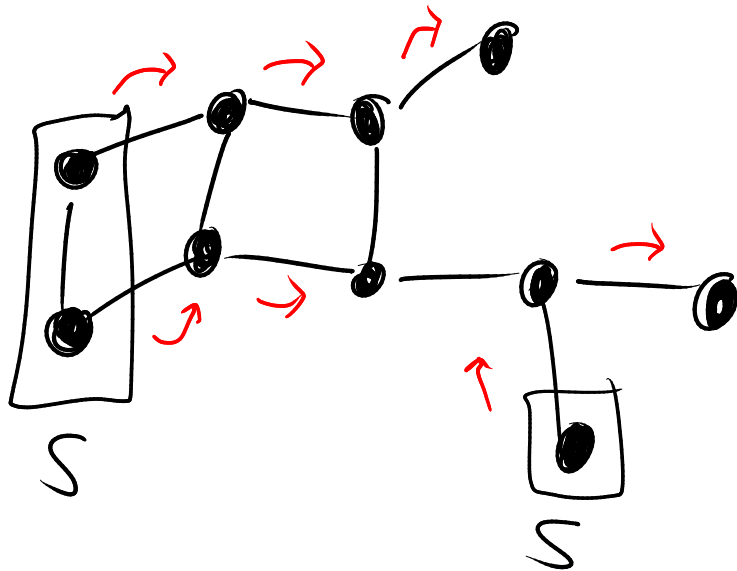
- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

\* IF ALL END UP INFECTED, CALL S INFECTING

\* TYPICALLY "SURFACE" IS INFECTING IF SPARSE



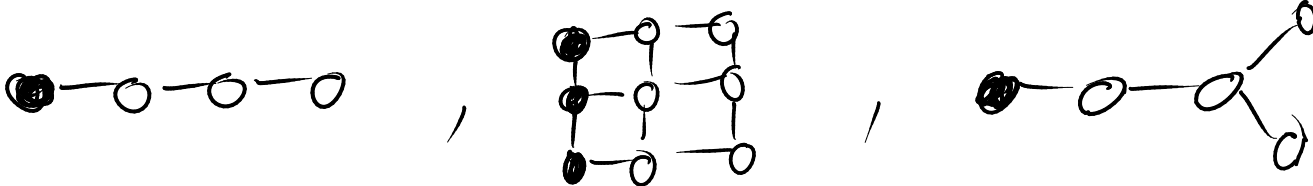
# GRAPH INFECTION



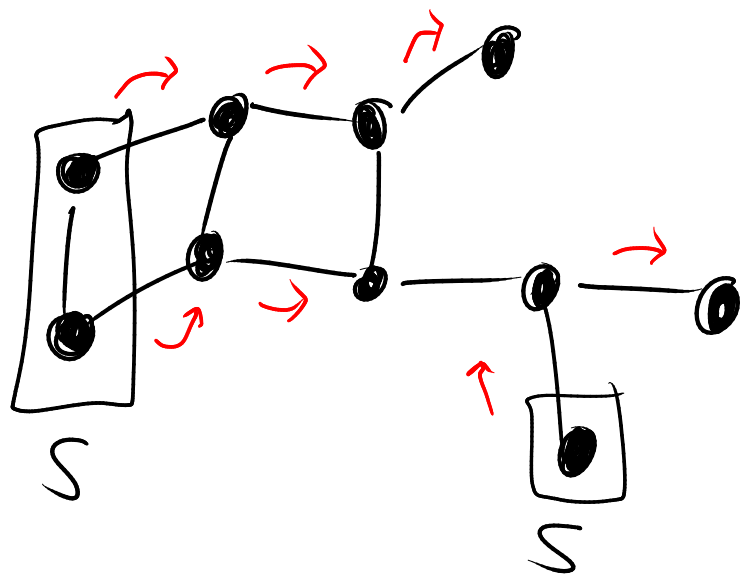
- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

\* IF ALL END UP INFECTED, CALL S INFECTING

\* TYPICALLY "SURFACE" IS INFECTING IF SPARSE



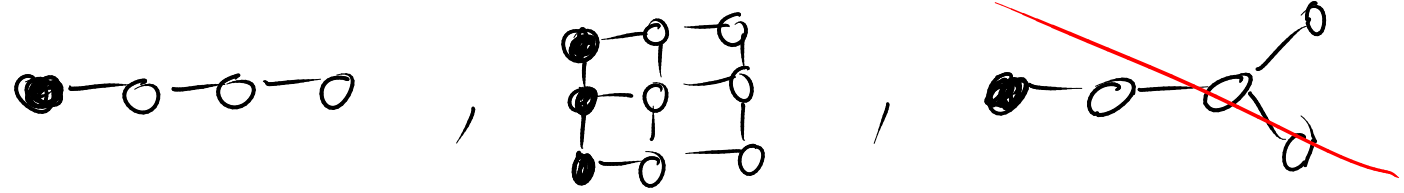
# GRAPH INFECTION



- S INFECTED
- ONCE INFECTED, REMAINS
- SPREADS TO UNIQUE HEALTHY NEIGHBOUR

\* IF ALL END UP INFECTED, CALL S INFECTING

\* TYPICALLY "SURFACE" IS INFECTING IF SPARSE



## KNOWLEDGE OF TOPOLOGY

$$H_0 = \sum_{n,m} c_{nm} |\eta X_m|$$

## KNOWLEDGE OF TOPOLOGY

$$H_0 = \sum_{n,m} c_{nm} |n X_m|$$

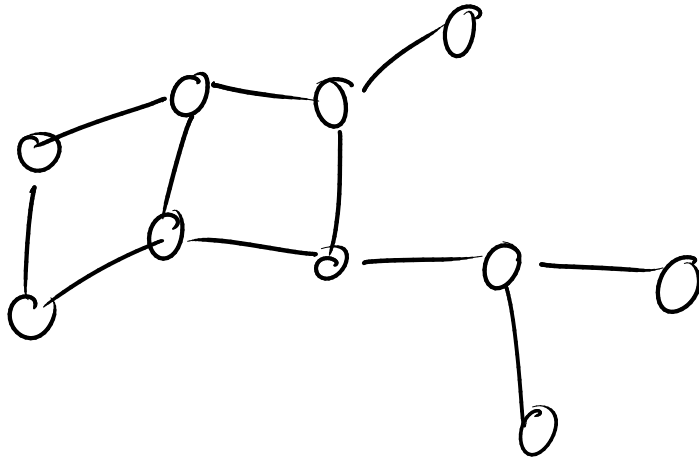
$c_{nm} \neq 0 \Rightarrow$  EDGE OF GRAPH



# KNOWLEDGE OF TOPOLOGY

$$H_0 = \sum_{n,m} c_{nm} |n X_m|$$

$c_{nm} \neq 0 \Rightarrow$  EDGE OF GRAPH

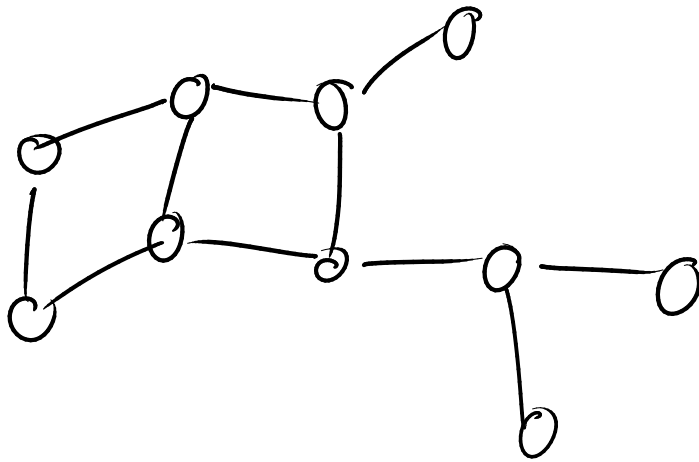


# KNOWLEDGE OF TOPOLOGY

$$H_0 = \sum_{n,m} c_{nm} |\ln X_m|$$

$c_{nm} \neq 0 \Rightarrow$  EDGE OF GRAPH

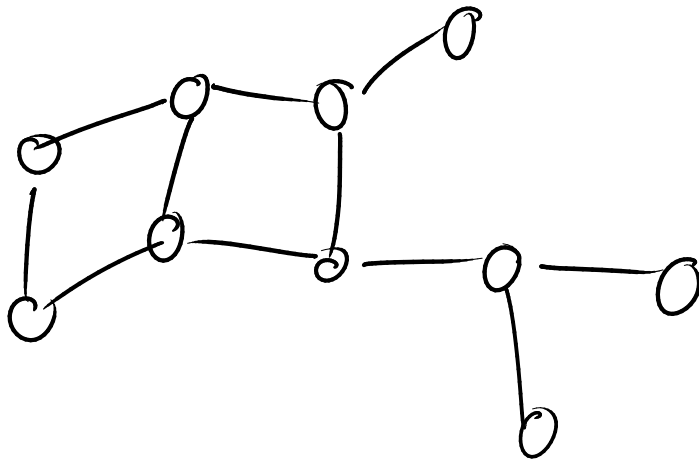
ASSUME  $g(H_0)$  KNOWN



# KNOWLEDGE OF TOPOLOGY

$$H_0 = \sum_{n,m} c_{nm} |n X_m|$$

$c_{nm} \neq 0 \Rightarrow$  EDGE OF GRAPH

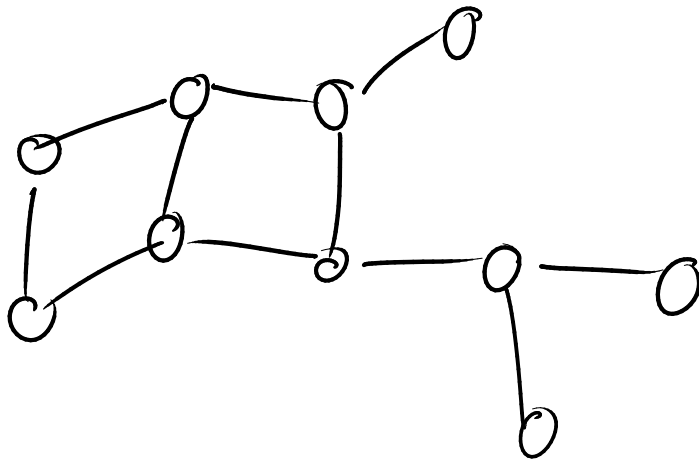


ASSUME  $\mathcal{F}(H_0)$  KNOWN  
(= NON-ZERO PATTERN)

## KNOWLEDGE OF TOPOLOGY

$$H_0 = \sum_{n,m} c_{nm} |n X_m|$$

$c_{nm} \neq 0 \Rightarrow$  EDGE OF GRAPH



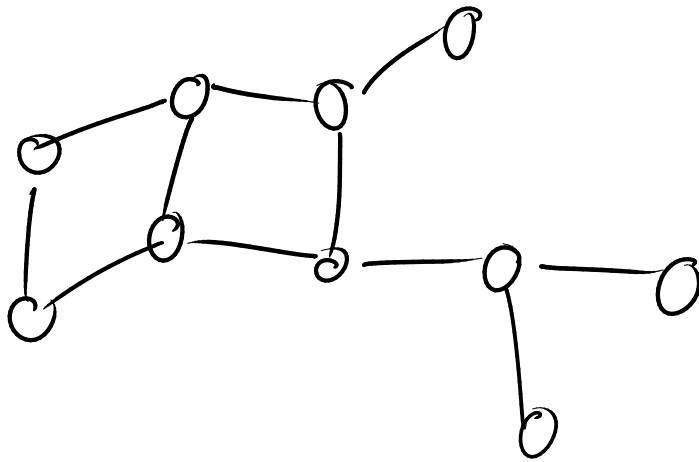
ASSUME  $g(H_0)$  KNOWN  
(= NON-ZERO PATTERN)

$$\Rightarrow g(H_0) = g(\hat{H}_0)$$

## KNOWLEDGE OF TOPOLOGY

$$H_0 = \sum_{n,m} c_{nm} |n X_m|$$

$c_{nm} \neq 0 \Rightarrow$  EDGE OF GRAPH



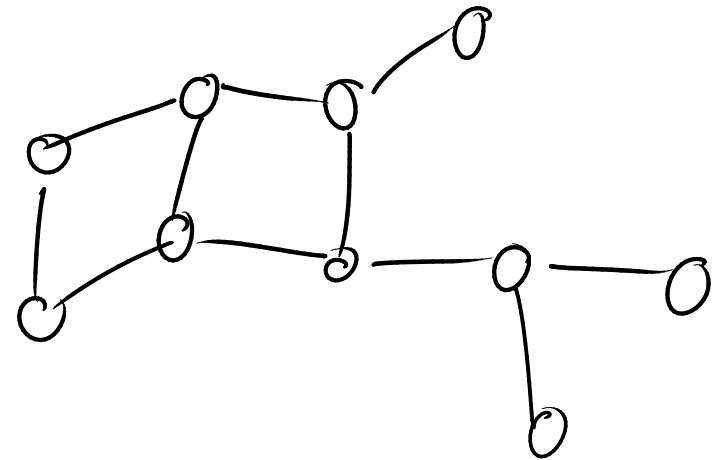
ASSUME  $g(H_0)$  KNOWN  
(= NON-ZERO PATTERN)

$$\Rightarrow g(H_0) = g(\hat{H}_0)$$

$$\Rightarrow \hat{H}_0 = \sum_{n,m} \hat{c}_{nm} |n X_m|$$

\* TO APPLY THEOREM, LET'S INTRODUCE CONTROLS :

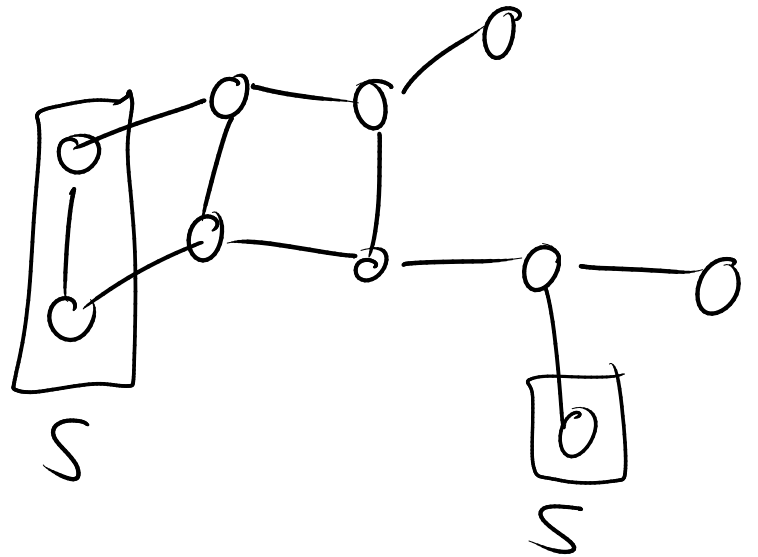
$$H(t) = H_0 + \sum_{\kappa} F_{\kappa}(t) H_{\kappa}$$



\* TO APPLY THEOREM, LET'S INTRODUCE CONTROLS :

$$H(t) = H_0 + \sum_k F_k(t) H_k$$

$$H_k = |k \times k| \quad , \quad k \in S$$

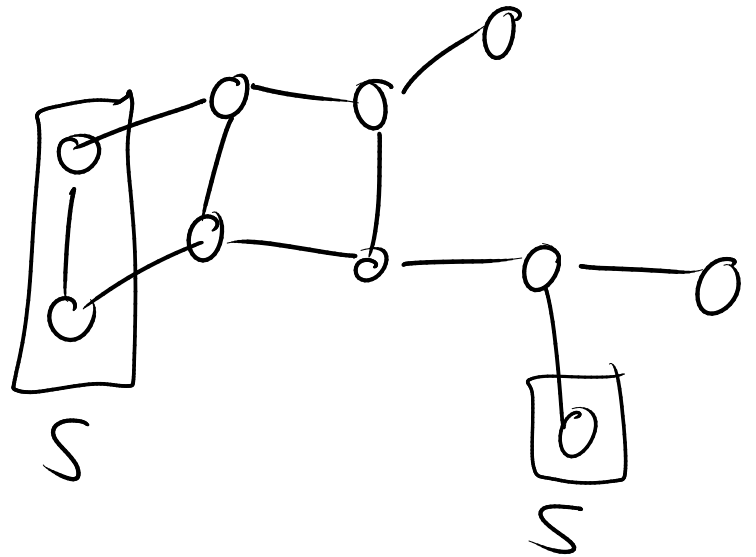


\* TO APPLY THEOREM, LET'S INTRODUCE CONTROLS:

$$H(t) = H_0 + \sum_k F_k(t) H_k$$

$$H_k = |k \times k|, \quad k \in S$$

\* S INFECTING





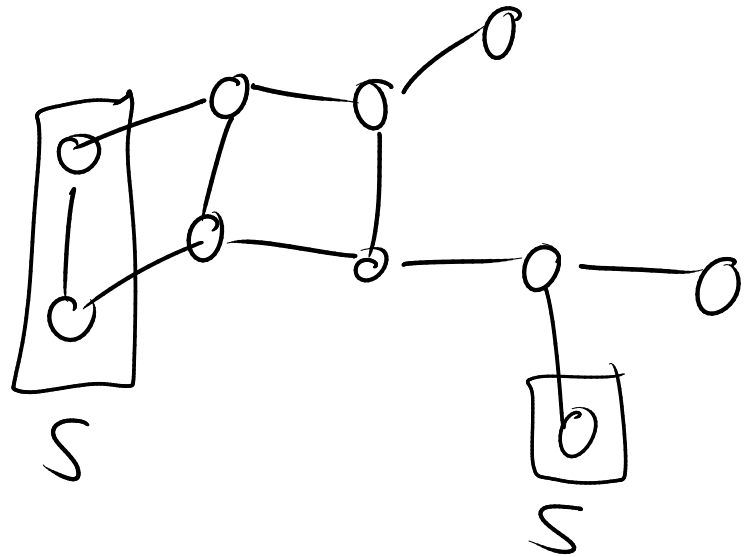
\* TO APPLY THEOREM, LET'S INTRODUCE CONTROLS:

$$H(t) = H_0 + \sum_k F_k(t) H_k$$

$$H_k = |k \times k|, \quad k \in S$$

\* S INFECTING

\* ASSUME CONTROLS KNOWN



\* TO APPLY THEOREM, LET'S INTRODUCE CONTROLS:

$$H(t) = H_0 + \sum_k F_k(t) H_k$$

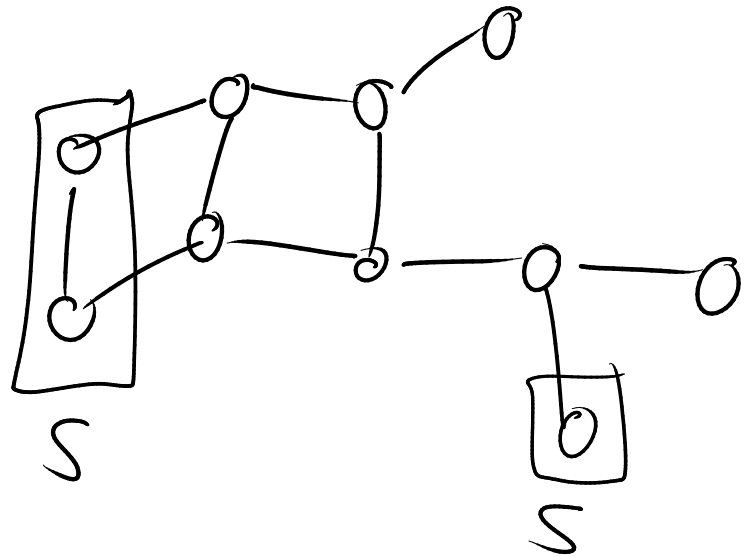
$$H_k = |k \times k|, \quad k \in S$$

\* S INFECTING

\* ASSUME CONTROLS KNOWN

\* TAKE ONE OBSERVABLE

M



\* TO APPLY THEOREM, LET'S INTRODUCE CONTROLS:

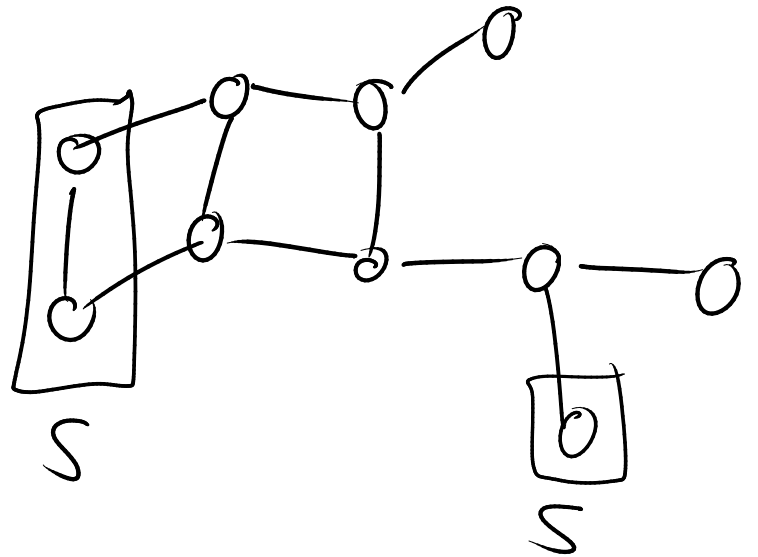
$$H(t) = H_0 + \sum_k F_k(t) H_k$$

$$H_k = |k \times k|, \quad k \in S$$

\* S INFECTING

\* ASSUME CONTROLS KNOWN

\* TAKE ONE OBSERVABLE  
M (POSSIBLY UNKNOWN)



IF  $S$  INFECTS  $g$  THEN  $\sigma$  AND  $\hat{\sigma}$  CONTROLLABLE,

AND RELATED THROUGH  $W = \text{DIAGONAL}$

IF  $S$  INFECTS  $\mathcal{G}$  THEN  $\sigma$  AND  $\hat{\sigma}$  CONTROLLABLE,

AND RELATED THROUGH  $W = \text{DIAGONAL}$

\*  $W = \text{DIAGONAL}$  IS  $|n\rangle \rightarrow e^{i\phi_n} |n\rangle$

IF  $S$  INFECTS  $\mathcal{G}$  THEN  $\sigma$  AND  $\hat{\sigma}$  CONTROLLABLE,

AND RELATED THROUGH  $W = \text{DIAGONAL}$

\*  $W = \text{DIAGONAL}$  IS  $|n\rangle \rightarrow e^{i\phi_n}|n\rangle$

\*  $M$  IS ESTIMATED!

IF  $S$  INFECTS  $\mathcal{G}$  THEN  $\sigma$  AND  $\hat{\sigma}$  CONTROLLABLE,

AND RELATED THROUGH  $W = \text{DIAGONAL}$

\*  $W = \text{DIAGONAL}$  IS  $|n\rangle \rightarrow e^{i\phi_n} |n\rangle$

\*  $M$  IS ESTIMATED!

\* "INDIRECT" ESTIMATION VIA SURFACE ( $\sim$  ULTRASOUND)

IF  $S$  INFECTS  $\mathcal{G}$  THEN  $\sigma$  AND  $\hat{\sigma}$  CONTROLLABLE,

AND RELATED THROUGH  $W = \text{DIAGONAL}$

\*  $W = \text{DIAGONAL}$  IS  $|n\rangle \rightarrow e^{i\phi_n} |n\rangle$

\*  $M$  IS ESTIMATED!

\* "INDIRECT" ESTIMATION VIA SURFACE ( $\sim$  ULTRASOUND)

\* IN PREVIOUS WORK: EXPLICIT & EFFICIENT PROTOCOL



IF  $S$  INFECTS  $\mathcal{G}$  THEN  $\sigma$  AND  $\hat{\sigma}$  CONTROLLABLE,

AND RELATED THROUGH  $W = \text{DIAGONAL}$

\*  $W = \text{DIAGONAL}$  IS  $|n\rangle \rightarrow e^{i\phi_n} |n\rangle$

\*  $M$  IS ESTIMATED!

\* "INDIRECT" ESTIMATION VIA SURFACE ( $\sim$  ULTRASOUND)

\* IN PREVIOUS WORK: EXPLICIT & EFFICIENT PROTOCOL

\* GET FOR FREE: INDIRECT CONTROL

IF  $S$  INFECTS  $g$  THEN  $\sigma$  AND  $\hat{\sigma}$  CONTROLLABLE,

AND RELATED THROUGH  $W = \text{DIAGONAL}$

\*  $W = \text{DIAGONAL}$  IS  $|n\rangle \rightarrow e^{i\phi_n} |n\rangle$

\*  $M$  IS ESTIMATED!

\* "INDIRECT" ESTIMATION VIA SURFACE ( $\sim$  ULTRASOUND)

\* IN PREVIOUS WORK: EXPLICIT & EFFICIENT PROTOCOL

\* GET FOR FREE: INDIRECT CONTROL

\* EASY SUFFICIENT CRITERION: INFECTION

## CONCLUSIONS

\* IF SYSTEM CONTROLLABLE, EASY CHARACTERIZATION  
HOW WELL IT CAN BE ESTIMATED,

## CONCLUSIONS

\* IF SYSTEM CONTROLLABLE, EASY CHARACTERIZATION  
HOW WELL IT CAN BE ESTIMATED, UP TO UNITARY  $W$

## CONCLUSIONS

- \* IF SYSTEM CONTROLLABLE, EASY CHARACTERIZATION  
HOW WELL IT CAN BE ESTIMATED, UP TO UNITARY  $W$
- \* THE MORE WE KNOW/ASSUME, THE EASIER :

## CONCLUSIONS

\* IF SYSTEM CONTROLLABLE, EASY CHARACTERIZATION  
HOW WELL IT CAN BE ESTIMATED, UP TO UNITARY  $W$

\* THE MORE WE KNOW/ASSUME, THE EASIER :  $[X, W] = 0$

## CONCLUSIONS

- \* IF SYSTEM CONTROLLABLE, EASY CHARACTERIZATION  
HOW WELL IT CAN BE ESTIMATED, UP TO UNITARY  $W$
- \* THE MORE WE KNOW/ASSUME, THE EASIER :  $[X, W]=0$
- \* SPARSE SYSTEMS CAN BE ESTIMATED &  
CONTROLLED FROM SURFACE

## CONCLUSIONS

- \* IF SYSTEM CONTROLLABLE, EASY CHARACTERIZATION  
HOW WELL IT CAN BE ESTIMATED, UP TO UNITARY  $W$
- \* THE MORE WE KNOW/ASSUME, THE EASIER :  $[X, W]=0$
- \* SPARSE SYSTEMS CAN BE ESTIMATED &  
CONTROLLED FROM SURFACE
- \* RECENT NMR EXPERIMENTS



## CONCLUSIONS

- \* IF SYSTEM CONTROLLABLE, EASY CHARACTERIZATION  
HOW WELL IT CAN BE ESTIMATED, UP TO UNITARY  $W$
- \* THE MORE WE KNOW/ASSUME, THE EASIER :  $[X, W]=0$
- \* SPARSE SYSTEMS CAN BE ESTIMATED &  
CONTROLLED FROM SURFACE
- \* RECENT NMR EXPERIMENTS
- \* OPEN SYSTEMS ?

## CONCLUSIONS

- \* IF SYSTEM CONTROLLABLE, EASY CHARACTERIZATION  
HOW WELL IT CAN BE ESTIMATED, UP TO UNITARY  $W$
- \* THE MORE WE KNOW/ASSUME, THE EASIER :  $[X, W]=0$
- \* SPARSE SYSTEMS CAN BE ESTIMATED &  
CONTROLLED FROM SURFACE
- \* RECENT NMR EXPERIMENTS
- \* OPEN SYSTEMS ? EFFICIENCY ?

## CONCLUSIONS

- \* IF SYSTEM CONTROLLABLE, EASY CHARACTERIZATION  
HOW WELL IT CAN BE ESTIMATED, UP TO UNITARY  $W$
- \* THE MORE WE KNOW/ASSUME, THE EASIER :  $[X, W]=0$
- \* SPARSE SYSTEMS CAN BE ESTIMATED &  
CONTROLLED FROM SURFACE
- \* RECENT NMR EXPERIMENTS
- \* OPEN SYSTEMS ? EFFICIENCY ?  $L_{\text{CONTROL}} \neq \text{SU}(n)$  ?