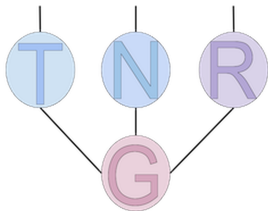


AI and TN - a love affair

Bram Vanhecke

University of Vienna

28 Nov 2023



Collaborators



Overview

¹<https://arxiv.org/abs/2208.08713>

²<https://arxiv.org/abs/2311.11894>

- Using MPS for active inference planning¹
 - What is Active inference
 - How MPS can help

¹<https://arxiv.org/abs/2208.08713>

²<https://arxiv.org/abs/2311.11894>

- Using MPS for active inference planning¹
 - What is Active inference
 - How MPS can help
- AD for PEPS optimization²
 - What is PEPS
 - How AD can help

¹<https://arxiv.org/abs/2208.08713>

²<https://arxiv.org/abs/2311.11894>

Active Inference

(solutions to) Belief updating

Action selection (and Bayesian model averaging)

$$u_t = \min_{\mathbf{a}} \mathbf{a}_{t+1} \cdot \mathcal{E}_{t+1}^u$$

$$\mathcal{E}_{t+1}^u = \ln \mathbf{A} \mathbf{s}_{t+1} - \ln \mathbf{A} \mathbf{B}(u) \mathbf{s}_t$$

$$\mathbf{s}_t = \sum_{\pi} \pi_{\pi} \cdot \mathbf{s}_t^{\pi}$$

State estimation (planning as inference)

$$\mathbf{s}_t^{\pi} = \sigma(\tilde{\mathbf{A}} \cdot \mathbf{o}_t + \tilde{\mathbf{B}}_{t-1}^{\pi} \cdot \mathbf{s}_{t-1}^{\pi} + \tilde{\mathbf{B}}_t^{\pi} \cdot \mathbf{s}_{t+1}^{\pi})$$

State estimation (habitual)

$$\mathbf{s}_t^{\pi} = \sigma(\tilde{\mathbf{A}} \cdot \mathbf{o}_t + \tilde{\mathbf{C}} \mathbf{s}_{t-1}^0 + \tilde{\mathbf{C}} \cdot \mathbf{s}_{t+1}^0)$$

Policy selection

$$\pi = \sigma(\tilde{\mathbf{E}} - \mathbf{F} - \gamma \cdot \mathbf{G})$$

$$F(\pi, \tau) = \mathbf{s}_t^{\pi} \cdot (\mathbf{s}_t^{\pi} - \tilde{\mathbf{A}} \cdot \mathbf{o}_t - \tilde{\mathbf{B}}_{t-1}^{\pi} \mathbf{s}_{t-1}^{\pi})$$

$$G(\pi, \tau) = \mathbf{o}_t^{\pi} \cdot (\tilde{\mathbf{o}}_t^{\pi} - \mathbf{U}_t) + \mathbf{s}_t^{\pi} \cdot \mathbf{H}$$

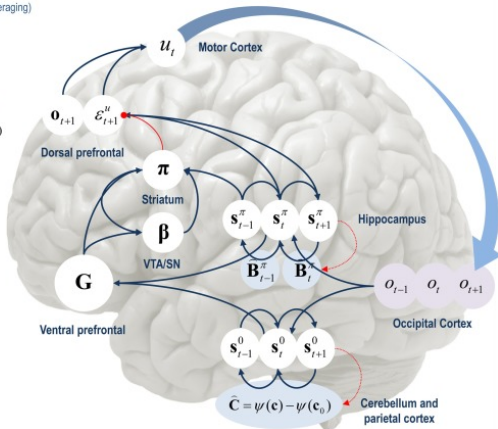
Precision (incentive salience)

$$\beta = \beta + (\pi - \pi_0) \cdot \mathbf{G}$$

Learning

$$\mathbf{c} = \mathbf{c} + \sum_{\pi} \mathbf{s}_t^{\pi} \otimes \mathbf{s}_{t-1}^{\pi}$$

Functional anatomy



Active Inference

Active Inference

- Models behavior of an agent

Active Inference

- Models behavior of an agent
- Agent makes observation (o) of- and actions (a) on the world

Active Inference

- Models behavior of an agent
- Agent makes observation (o) of- and actions (a) on the world
- Agent plans to minimize 'surprise'.

Active Inference

- Models behavior of an agent
- Agent makes observation (o) of- and actions (a) on the world
- Agent plans to minimize 'surprise'.
- Agent has an internal model of the world, with 'hidden states' (s)

Active Inference

- Models behavior of an agent
- Agent makes observation (o) of- and actions (a) on the world
- Agent plans to minimize 'surprise'.
- Agent has an internal model of the world, with 'hidden states' (s)
 - may be imperfect

Active Inference

- Models behavior of an agent
- Agent makes observation (o) of- and actions (a) on the world
- Agent plans to minimize 'surprise'.
- Agent has an internal model of the world, with 'hidden states' (s)
 - may be imperfect
 - should in principle be updated as time goes by

Active Inference

- Models behavior of an agent
- Agent makes observation (o) of- and actions (a) on the world
- Agent plans to minimize 'surprise'.
- Agent has an internal model of the world, with 'hidden states' (s)
 - may be imperfect
 - should in principle be updated as time goes by
 - where ML comes in

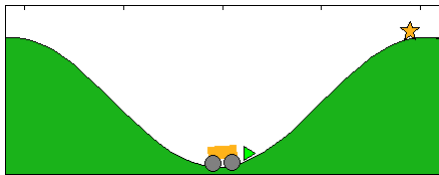
Active Inference

- Models behavior of an agent
- Agent makes observation (o) of- and actions (a) on the world
- Agent plans to minimize 'surprise'.
- Agent has an internal model of the world, with 'hidden states' (s)
 - may be imperfect
 - should in principle be updated as time goes by
 - where ML comes in
 - usually represented by a partially observable Markov decision process (POMDP)

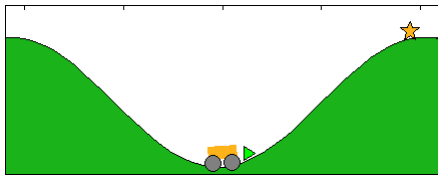
Active Inference

- Models behavior of an agent
- Agent makes observation (o) of- and actions (a) on the world
- Agent plans to minimize 'surprise'.
- Agent has an internal model of the world, with 'hidden states' (s)
 - may be imperfect
 - should in principle be updated as time goes by
 - where ML comes in
 - usually represented by a partially observable Markov decision process (POMDP)
 - the model may also be represented by a TN

Active Inference - Example - Mountain Car

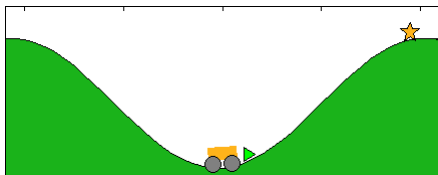


Active Inference - Example - Mountain Car



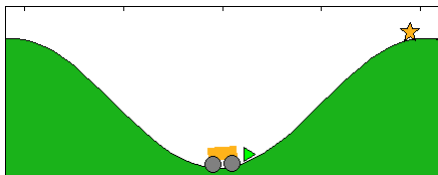
- o are observations of the location of the car

Active Inference - Example - Mountain Car



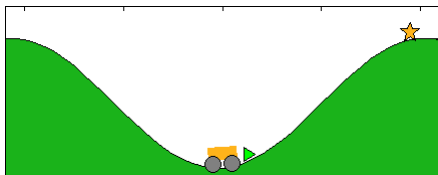
- o are observations of the location of the car
- a are push left or right actions

Active Inference - Example - Mountain Car



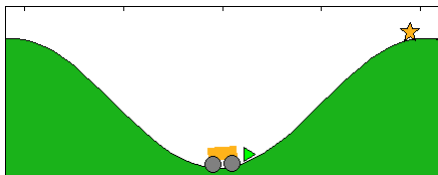
- o are observations of the location of the car
- a are push left or right actions
- The hidden state should be velocity v

Active Inference - Example - Mountain Car



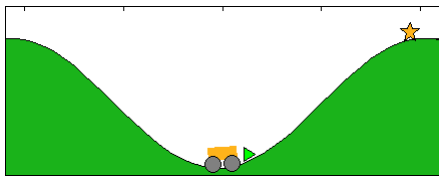
- o are observations of the location of the car
- a are push left or right actions
- The hidden state should be velocity v
- Agent is 'surprised' when the car is not at the star

Active Inference - Example - Mountain Car



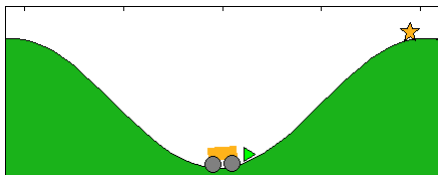
- o are observations of the location of the car
- a are push left or right actions
- The hidden state should be velocity v
- Agent is 'surprised' when the car is not at the star
 \implies the preferred distribution $P(o)$ is centered around the star.

Active Inference - Example - Mountain Car



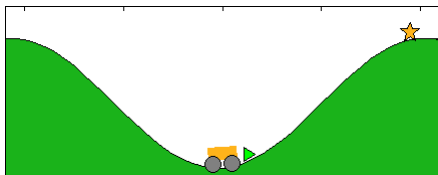
- o are observations of the location of the car
- a are push left or right actions
- The hidden state should be velocity v
- Agent is 'surprised' when the car is not at the star
 \implies the preferred distribution $P(o)$ is centered around the star.
- Expected surprisal is $< -\log P >_{a_1, a_2, \dots}$

Active Inference - Example - Mountain Car



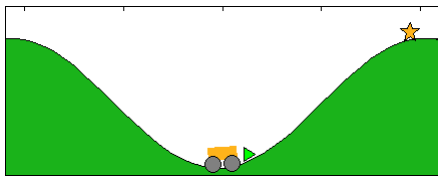
- o are observations of the location of the car
- a are push left or right actions
- The hidden state should be velocity v
- Agent is 'surprised' when the car is not at the star
 \implies the preferred distribution $P(o)$ is centered around the star.
- Expected surprisal is $< -\log P >_{a_1, a_2, \dots}$
-
- POMDP-based model: $f(o_{\text{old}}, a_{\text{old}}, v_{\text{old}}) = v_{\text{new}}$

Active Inference - Example - Mountain Car



- o are observations of the location of the car
- a are push left or right actions
- The hidden state should be velocity v
- Agent is 'surprised' when the car is not at the star
 \implies the preferred distribution $P(o)$ is centered around the star.
- Expected surprisal is $< -\log P >_{a_1, a_2, \dots}$
-
- POMDP-based model: $f(o_{\text{old}}, a_{\text{old}}, v_{\text{old}}) = v_{\text{new}}$
- TN approach considers the world described by a tensor $C(o_1, a_1, o_2, a_2, \dots)$

Active Inference - Example - Mountain Car



- o are observations of the location of the car
- a are push left or right actions
- The hidden state should be velocity v
- Agent is 'surprised' when the car is not at the star
 \implies the preferred distribution $P(o)$ is centered around the star.
- Expected surprisal is $< -\log P >_{a_1, a_2, \dots}$
-
- POMDP-based model: $f(o_{\text{old}}, a_{\text{old}}, v_{\text{old}}) = v_{\text{new}}$
- TN approach considers the world described by a tensor $C(o_1, a_1, o_2, a_2, \dots)$

TN preeliminaries

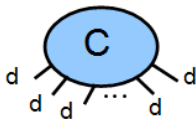
TN preliminaries

Big tensor C_{i_1, \dots, i_N}

Arbitrary tensor

($|i_k\rangle$ – local \mathcal{H} space of dim d):

$$|\psi\rangle = \sum_{i_1, \dots, i_N} C_{i_1, i_2, \dots, i_N} |i_1 i_2 \dots i_N\rangle$$



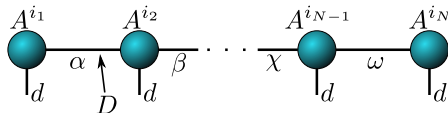
d^N parameters C_{i_1, \dots, i_N}

$\exp(N)$

Network of tensors

Matrix product state:

$$\sum_{i_1, \dots, i_N} \sum_{\{\alpha\beta\ldots\omega\}} A_{\alpha}^{i_1} A_{\alpha\beta}^{i_2} \dots A_{\chi\omega}^{i_{N-1}} A_{\omega}^{i_N} |i_1 i_2 \dots i_N\rangle$$

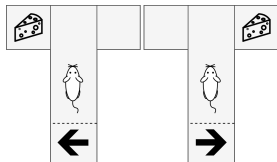


$\mathcal{O}(ND^2d)$ par. (D – dim of bond index)

$\text{poly}(N)$

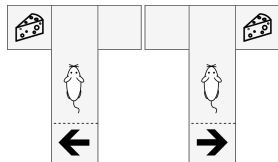
T-maze

T-maze



$$\Psi(\tilde{a}, \tilde{o}) = \begin{array}{ccc} & a_1 & a_2 \\ & | & | \\ T^{(1)} & - T^{(2)} & - T^{(3)} \\ & | & | \\ o_1 & o_2 & o_3 \end{array}, \quad (1)$$

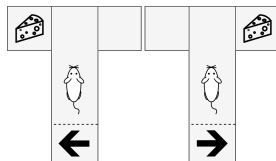
T-maze



$$\Psi(\tilde{a}, \tilde{o}) = \begin{array}{ccc} & a_1 & a_2 \\ & | & | \\ T^{(1)} & - T^{(2)} & - T^{(3)} \\ & | & | \\ o_1 & o_2 & o_3 \end{array}, \quad (1)$$

- Generate data set of consistent actions and observations

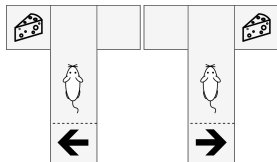
T-maze



$$\Psi(\tilde{a}, \tilde{o}) = \begin{array}{ccc} & a_1 & a_2 \\ & | & | \\ T^{(1)} & - T^{(2)} & - T^{(3)} \\ & | & | \\ o_1 & o_2 & o_3 \end{array}, \quad (1)$$

- Generate data set of consistent actions and observations
- Maximize the overlap of the MPS with this data set.

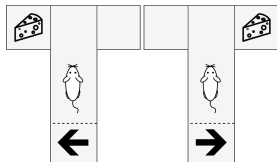
T-maze



$$\Psi(\tilde{a}, \tilde{o}) = \begin{array}{ccc} & a_1 & a_2 \\ & | & | \\ T^{(1)} & - T^{(2)} & - T^{(3)} \\ & | & | \\ o_1 & o_2 & o_3 \end{array}, \quad (1)$$

- Generate data set of consistent actions and observations
- Maximize the overlap of the MPS with this data set.
- Through two-site updates we can 'learn' the bond dimension dynamically.

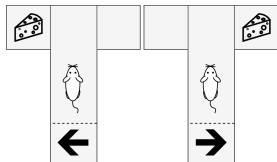
T-maze



$$\Psi(\tilde{a}, \tilde{o}) = \begin{array}{c} \begin{array}{ccc} a_1 & & a_2 \\ | & & | \\ T^{(1)} & - & T^{(2)} & - & T^{(3)} \\ | & & | & & | \\ o_1 & & o_2 & & o_3 \end{array} \end{array}, \quad (1)$$

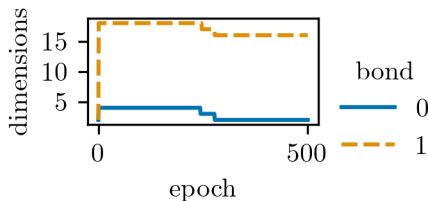
- Generate data set of consistent actions and observations
- Maximize the overlap of the MPS with this data set.
- Through two-site updates we can 'learn' the bond dimension dynamically.
- Well understood techniques from TN world

T-maze



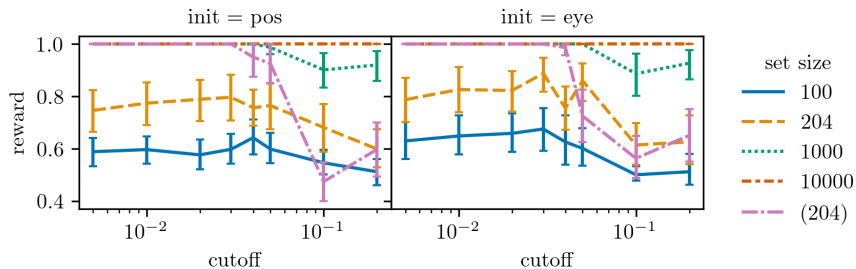
$$\Psi(\tilde{a}, \tilde{o}) = \begin{array}{c} \begin{array}{ccc} & a_1 & a_2 \\ & \downarrow & \downarrow \\ T^{(1)} & - T^{(2)} & - T^{(3)} \\ \uparrow & \uparrow & \uparrow \\ o_1 & o_2 & o_3 \end{array} \end{array}, \quad (1)$$

- Generate data set of consistent actions and observations
- Maximize the overlap of the MPS with this data set.
- Through two-site updates we can 'learn' the bond dimension dynamically.
- Well understood techniques from TN world



T-maze - Results

T-maze - Results



Outlook

Outlook

- More complicated models

Outlook

- More complicated models
- Infinite horizon

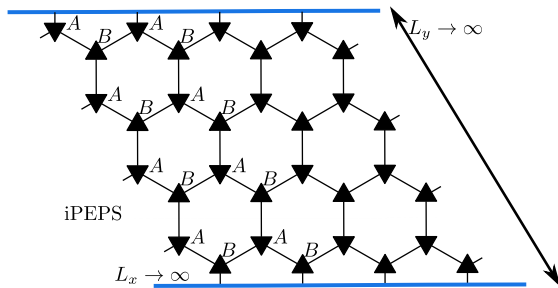
Outlook

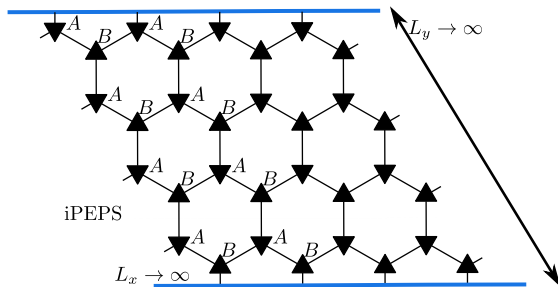
- More complicated models
- Infinite horizon
- Continuous variables

Outlook

- More complicated models
- Infinite horizon
- Continuous variables
- Planning with TN

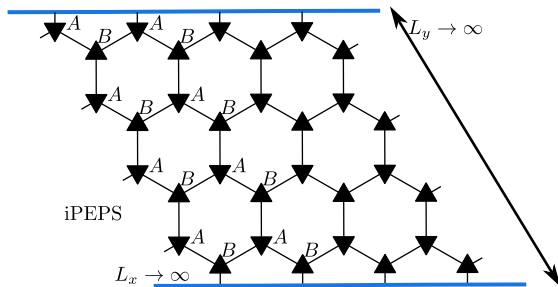
PEPS





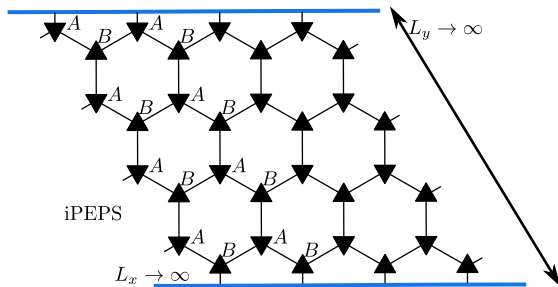
- Natural generalization of MPS to 2D

PEPS

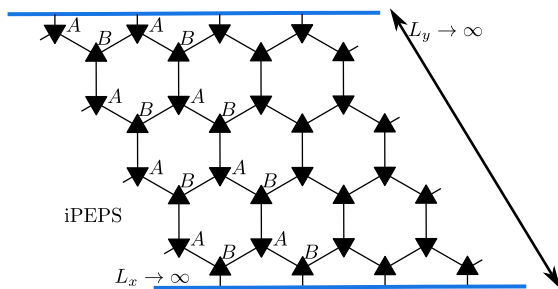


- Natural generalization of MPS to 2D
- Allows simulations in the thermodynamic limit

PEPS



- Natural generalization of MPS to 2D
- Allows simulations in the thermodynamic limit
- Captures strong correlations and exotic behavior

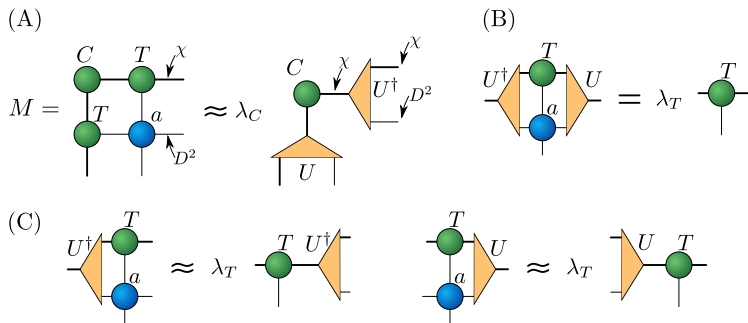


- Natural generalization of MPS to 2D
- Allows simulations in the thermodynamic limit
- Captures strong correlations and exotic behavior

Gapped \mathbb{Z}_2 vs gapless $U(1)$ SL in $S=1/2$ Kagome AF? H.J.Liao et al. PRL 118 (2017)

Contracting PEPS: Corner Transfer Matrix⁴

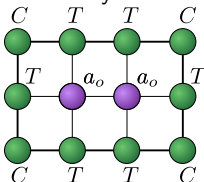
Contracting PEPS: Corner Transfer Matrix⁴



- Enables calculation with infinite TN
- Random initialization and iterated to convergence

Energy calculated approximately with CTM:

$$E \approx \tilde{E} = F(C, T, A, H) =$$



Energy gradient

Energy gradient

- Numerical gradients:

Energy gradient

- Numerical gradients:

- Finite difference: $\frac{\partial F}{\partial A_i} = \frac{F(A+\delta \cdot a_i) - F(A)}{\delta} + \mathcal{O}(\delta)$

expensive, erroneous

- Summation of terms with hole fixed and different Hamiltonian locations:

approximate, expensive for 'larger' Hamiltonians

P. Corboz, PRB 94, 035133 (2016),

L. Vanderstraeten, J. Haegeman, P. Corboz, and F. Verstraete, PRB 94, 155123 (2016)

- Summation of terms with Hamiltonian fixed and different hole locations:

almost like AD, but ignoring isometry contribution, memory expensive

S. P. G. Crone and P. Corboz, PRB 101, 115143 (2020)

Energy gradient

- Numerical gradients:

- Finite difference: $\frac{\partial F}{\partial A_i} = \frac{F(A+\delta \cdot a_i) - F(A)}{\delta} + \mathcal{O}(\delta)$

expensive, erroneous

- Summation of terms with hole fixed and different Hamiltonian locations:

approximate, expensive for 'larger' Hamiltonians

P. Corboz, PRB 94, 035133 (2016),

L. Vanderstraeten, J. Haegeman, P. Corboz, and F. Verstraete, PRB 94, 155123 (2016)

- Summation of terms with Hamiltonian fixed and different hole locations:

almost like AD, but ignoring isometry contribution, memory expensive

S. P. G. Crone and P. Corboz, PRB 101, 115143 (2020)

- Analytical gradients: Automatic/Algorithmic differentiation

memory expensive, can be problematic if treated as black box

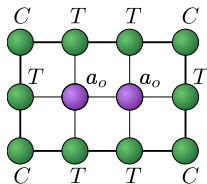
H-J. Liao, J-G. Liu, L. Wang, and T. Xiang, PRX 9, 031041 (2019)

J. Hasik, D. Poilblanc, F. Becca, SciPost Phys. 10, 012 (2021)

Energy gradient

Energy calculated approximately with CTM:

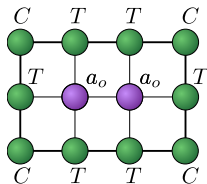
$$E \approx \tilde{E} = F(C_n, T_n, A, H) =$$



Energy gradient

Energy calculated approximately with CTM:

$$E \approx \tilde{E} = F(C_n, T_n, A, H) =$$

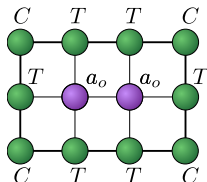


With $(C_k, T_k) \equiv x_k = f(x_{k-1}, A)$

Energy gradient

Energy calculated approximately with CTM:

$$E \approx \tilde{E} = F(C_n, T_n, A, H) =$$



With $(C_k, T_k) \equiv x_k = f(x_{k-1}, A)$ its gradient is:

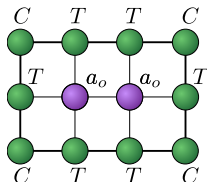
$$d\tilde{E} = \frac{\partial F}{\partial A} dA + \frac{\partial F}{\partial x_n} dx_n,$$

$$dx_n = \frac{\partial f}{\partial A} dA + \frac{\partial f}{\partial x_{n-1}} \left(\frac{\partial f}{\partial A} dA + \frac{\partial f}{\partial x_{n-2}} (\dots) \right),$$

Energy gradient

Energy calculated approximately with CTM:

$$E \approx \tilde{E} = F(C_n, T_n, A, H) =$$



With $(C_k, T_k) \equiv x_k = f(x_{k-1}, A)$ its gradient is:

$$d\tilde{E} = \frac{\partial F}{\partial A} dA + \frac{\partial F}{\partial x_n} dx_n,$$

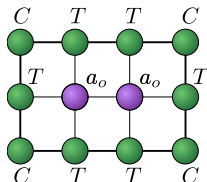
$$dx_n = \frac{\partial f}{\partial A} dA + \frac{\partial f}{\partial x_{n-1}} \left(\frac{\partial f}{\partial A} dA + \frac{\partial f}{\partial x_{n-2}} (\dots) \right),$$

Problems:

Energy gradient

Energy calculated approximately with CTM:

$$E \approx \tilde{E} = F(C_n, T_n, A, H) =$$



With $(C_k, T_k) \equiv x_k = f(x_{k-1}, A)$ its gradient is:

$$d\tilde{E} = \frac{\partial F}{\partial A} dA + \frac{\partial F}{\partial x_n} dx_n,$$

$$dx_n = \frac{\partial f}{\partial A} dA + \frac{\partial f}{\partial x_{n-1}} \left(\frac{\partial f}{\partial A} dA + \frac{\partial f}{\partial x_{n-2}} (\dots) \right),$$

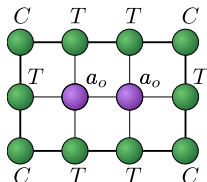
Problems:

- 1 costly in memory, need for many iterations

Energy gradient

Energy calculated approximately with CTM:

$$E \approx \tilde{E} = F(C_n, T_n, A, H) =$$



With $(C_k, T_k) \equiv x_k = f(x_{k-1}, A)$ its gradient is:

$$\begin{aligned} d\tilde{E} &= \frac{\partial F}{\partial A} dA + \frac{\partial F}{\partial x_n} dx_n, \\ dx_n &= \frac{\partial f}{\partial A} dA + \frac{\partial f}{\partial x_{n-1}} \left(\frac{\partial f}{\partial A} dA + \frac{\partial f}{\partial x_{n-2}} (\dots) \right), \end{aligned}$$

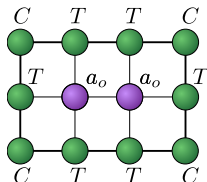
Problems:

- 1 costly in memory, need for many iterations
- 2 gradient of EIG (SVD) poorly conditioned in case of degenerate spectra

Energy gradient

Energy calculated approximately with CTM:

$$E \approx \tilde{E} = F(C_n, T_n, A, H) =$$



With $(C_k, T_k) \equiv x_k = f(x_{k-1}, A)$ its gradient is:

$$\begin{aligned} d\tilde{E} &= \frac{\partial F}{\partial A} dA + \frac{\partial F}{\partial x_n} dx_n, \\ dx_n &= \frac{\partial f}{\partial A} dA + \frac{\partial f}{\partial x_{n-1}} \left(\frac{\partial f}{\partial A} dA + \frac{\partial f}{\partial x_{n-2}} (\dots) \right), \end{aligned}$$

Problems:

- ❶ costly in memory, need for many iterations
- ❷ gradient of EIG (SVD) poorly conditioned in case of degenerate spectra
- ❸ **currently only approximate!**

Problem: Current derivative of EIG(SVD) is only approximate

Problem: Current derivative of EIG(SVD) is only approximate

Solution: Calculate exact

$$M = PCP^\dagger$$

Problem: Current derivative of EIG(SVD) is only approximate

Solution: Calculate exact

$$M = PCP^\dagger + \underline{P_\perp C_\perp P_\perp^\dagger}$$

Problem: Current derivative of EIG(SVD) is only approximate

Solution: Calculate exact

$$M = PCP^\dagger + \underline{P_\perp C_\perp P_\perp^\dagger}$$

With $PP^\dagger + P_\perp P_\perp^\dagger = \mathbb{I}$, leading to Sylvester equation for dP :

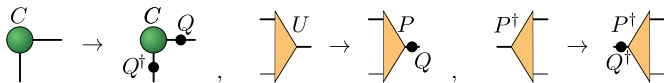
$$(\mathbb{I} - PP^\dagger)dMP = dPC - \underline{(\mathbb{I} - PP^\dagger)MdP}$$

Problem: divergencies in the gradient of $\text{EIG}(\text{SVD})$

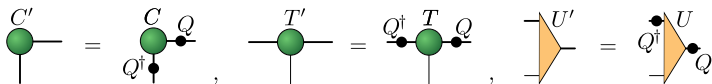
Problem: divergencies in the gradient of EIG(SVD)

Solution: Q-deformed CTM with $Q = \mathbb{I}$

(A) Q-deformation step



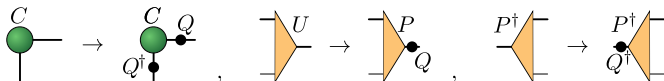
(B) Gauge transformation



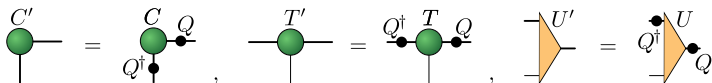
Problem: divergencies in the gradient of EIG(SVD)

Solution: Q-deformed CTM with $Q = \mathbb{I}$

(A) Q-deformation step



(B) Gauge transformation



regular CTM:

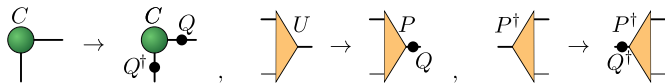
$$dC = \mathbb{I} \circ (P^\dagger dMP)$$

$$P^\dagger dP = F \circ (P^\dagger dMP), \quad F_{ij} = 1/(c_j - c_i)$$

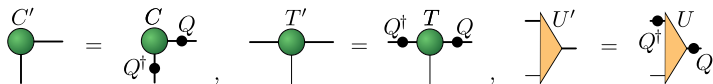
Problem: divergencies in the gradient of EIG(SVD)

Solution: Q-deformed CTM with $Q = \mathbb{I}$

(A) Q-deformation step



(B) Gauge transformation



regular CTM:

$$\begin{aligned} dC &= \mathbb{I} \circ (P^\dagger dMP) \\ P^\dagger dP &= F \circ (P^\dagger dMP), \quad F_{ij} = 1/(c_j - c_i) \end{aligned}$$

Q-deformed CTM:

$$\begin{aligned} dC &= P^\dagger dMP \\ P^\dagger dP &= 0 \end{aligned}$$

Problem: memory intensive, many iterations

Problem: memory intensive, many iterations

Solution: fixed point differentiation

Problem: memory intensive, many iterations

Solution: fixed point differentiation

if $x = f(A, x)$:

Problem: memory intensive, many iterations

Solution: fixed point differentiation

if $x = f(A, x)$:

$$dx = \sum_{k=0}^{\infty} \left(\frac{\partial f}{\partial x} \right)^k \frac{\partial f}{\partial A} dA = \left(1 - \frac{\partial f}{\partial x} \right)^{-1} \frac{\partial f}{\partial A} dA.$$

Problem: memory intensive, many iterations

Solution: fixed point differentiation

if $x = f(A, x)$:

$$dx = \sum_{k=0}^{\infty} \left(\frac{\partial f}{\partial x} \right)^k \frac{\partial f}{\partial A} dA = \left(1 - \frac{\partial f}{\partial x} \right)^{-1} \frac{\partial f}{\partial A} dA.$$

But: requires element-wise convergence $x = f(x, A)$

Problem: memory intensive, many iterations

Solution: fixed point differentiation

if $x = f(A, x)$:

$$dx = \sum_{k=0}^{\infty} \left(\frac{\partial f}{\partial x} \right)^k \frac{\partial f}{\partial A} dA = \left(1 - \frac{\partial f}{\partial x} \right)^{-1} \frac{\partial f}{\partial A} dA.$$

But: requires element-wise convergence $x = f(x, A)$

EIG(SVD) is not unique, so gauge fixing is required:

Problem: memory intensive, many iterations

Solution: fixed point differentiation

if $x = f(A, x)$:

$$dx = \sum_{k=0}^{\infty} \left(\frac{\partial f}{\partial x} \right)^k \frac{\partial f}{\partial A} dA = \left(1 - \frac{\partial f}{\partial x} \right)^{-1} \frac{\partial f}{\partial A} dA.$$

But: requires element-wise convergence $x = f(x, A)$

EIG(SVD) is not unique, so gauge fixing is required:

$$UCU^\dagger = (U\sigma)C(\sigma^\dagger U^\dagger) \Rightarrow \hat{T} \xrightarrow{f} \sigma^\dagger \hat{T} \sigma = T.$$

Comparison of gradients

Comparison of gradients

State: $|\Psi\rangle = |\varphi_{NN}^{\text{RVB}}\rangle + |\varphi_{\text{long}}^{\text{RVB}}\rangle + \beta|\varphi_3\rangle$, with $D = 3, \chi = 160$

Hamiltonian: $H = J_1 \sum_{i,j \in NN, \alpha} f(\alpha) S_i^\alpha S_j^\alpha + J_2 \sum_{i,j \in NNN} \vec{S}_i \cdot \vec{S}_j$

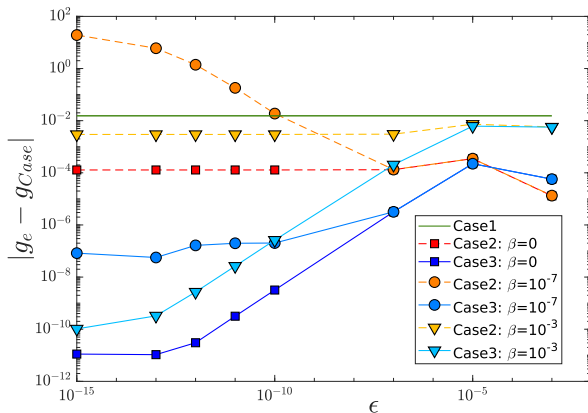
with $SU(2)$ symmetry breaking anisotropy $f([x, y, z]) = [-1, 1 + \beta, -1 + \beta]$

Comparison of gradients

State: $|\Psi\rangle = |\varphi_{NN}^{\text{RVB}}\rangle + |\varphi_{\text{long}}^{\text{RVB}}\rangle + \beta|\varphi_3\rangle$, with $D = 3, \chi = 160$

Hamiltonian: $H = J_1 \sum_{i,j \in NN, \alpha} f(\alpha) S_i^\alpha S_j^\alpha + J_2 \sum_{i,j \in NNN} \vec{S}_i \cdot \vec{S}_j$

with $SU(2)$ symmetry breaking anisotropy $f([x, y, z]) = [-1, 1 + \beta, -1 + \beta]$



$$F_{ij} \rightarrow \frac{c_j - c_i}{(c_j - c_i)^2 + \epsilon}$$

- our gradient g_e
- Case 1: $dP = 0$
- Case 2: current AD
- Case 3: using Sylvester equation for dP

Conclusions

Conclusions

We significantly improved the AD for PEPS optimization problems:

- stability
- accuracy

Conclusions

We significantly improved the AD for PEPS optimization problems:

- stability
- accuracy

PEPS libraries cannot yet be treated as blackbox like with DMRG

Conclusions

We significantly improved the AD for PEPS optimization problems:

- stability
- accuracy

PEPS libraries cannot yet be treated as blackbox like with DMRG

AD is a great tool if used carefully:

- reduces workcost
- eliminates bugs
- allows for more efficient algorithms

Conclusions

We significantly improved the AD for PEPS optimization problems:

- stability
- accuracy

PEPS libraries cannot yet be treated as blackbox like with DMRG

AD is a great tool if used carefully:

- reduces workcost
- eliminates bugs
- allows for more efficient algorithms
- may allow to reach higher bond dimensions D, χ and hence higher correlation lengths ξ , tackle challenging problems with bigger accuracy

Thank You