

From Parametricity to Conservation Laws, via Noether's Theorem

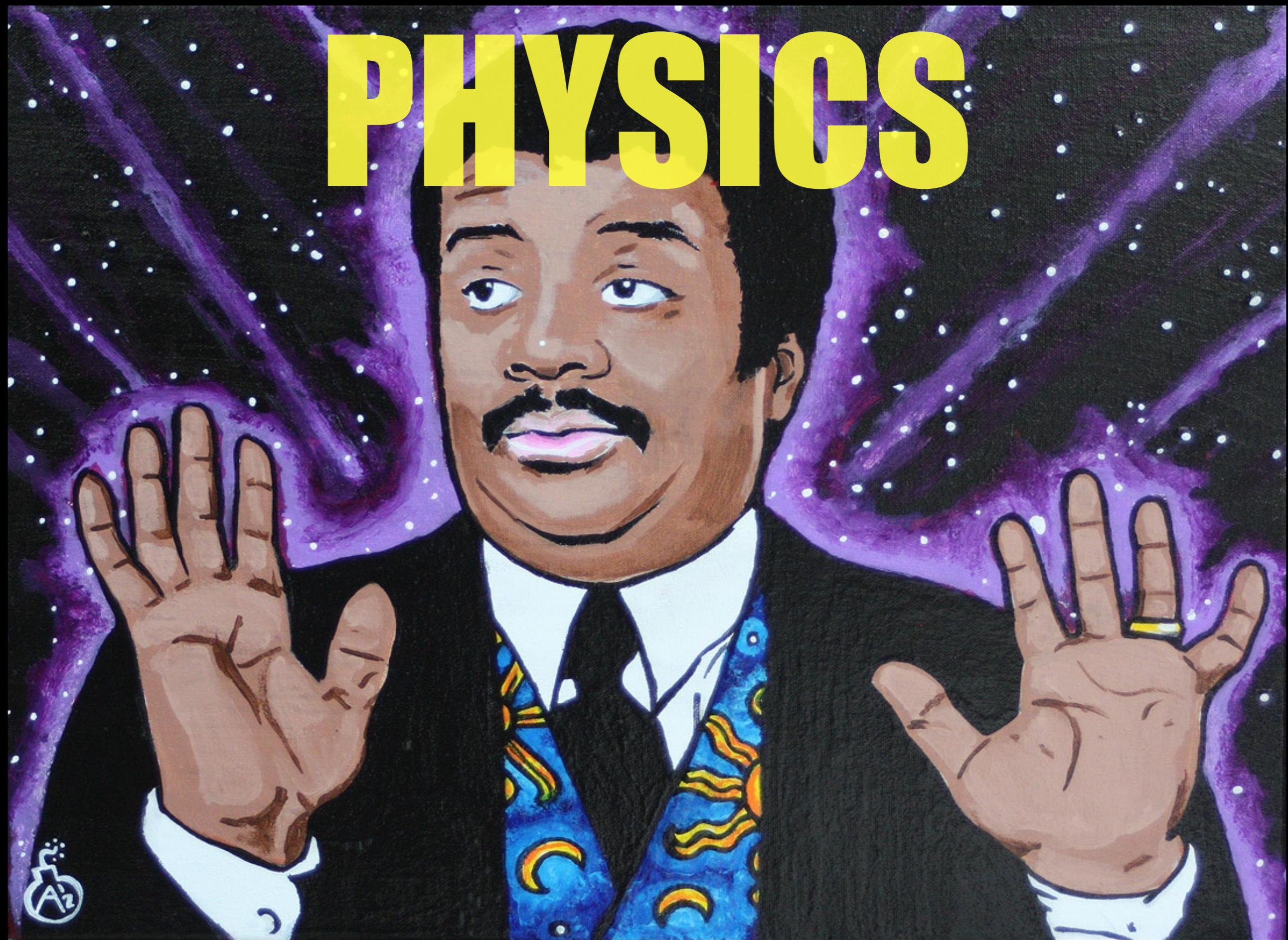
Written by Robert Atkey

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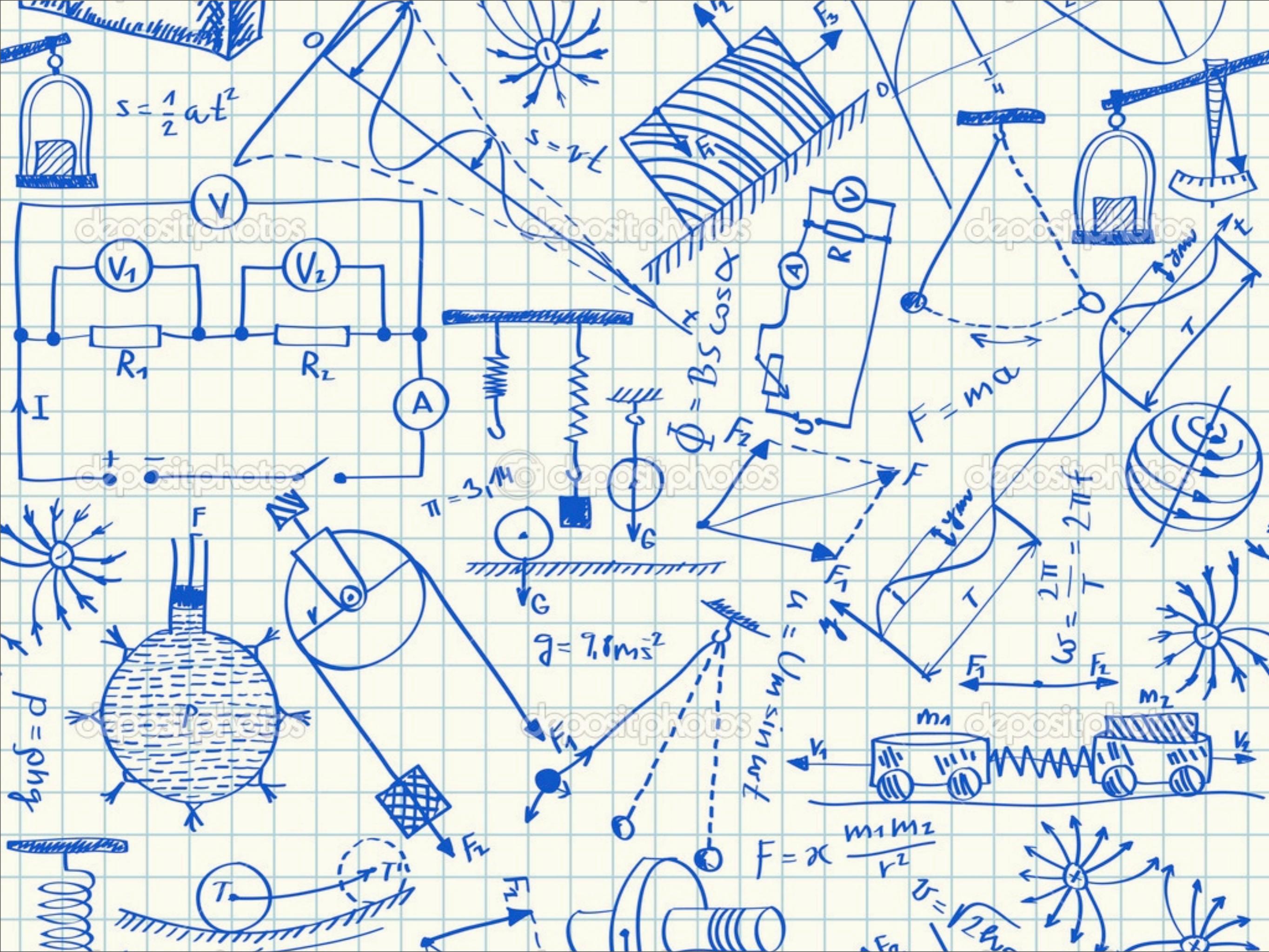
Presented by Ben Carriel & Ben Greenman

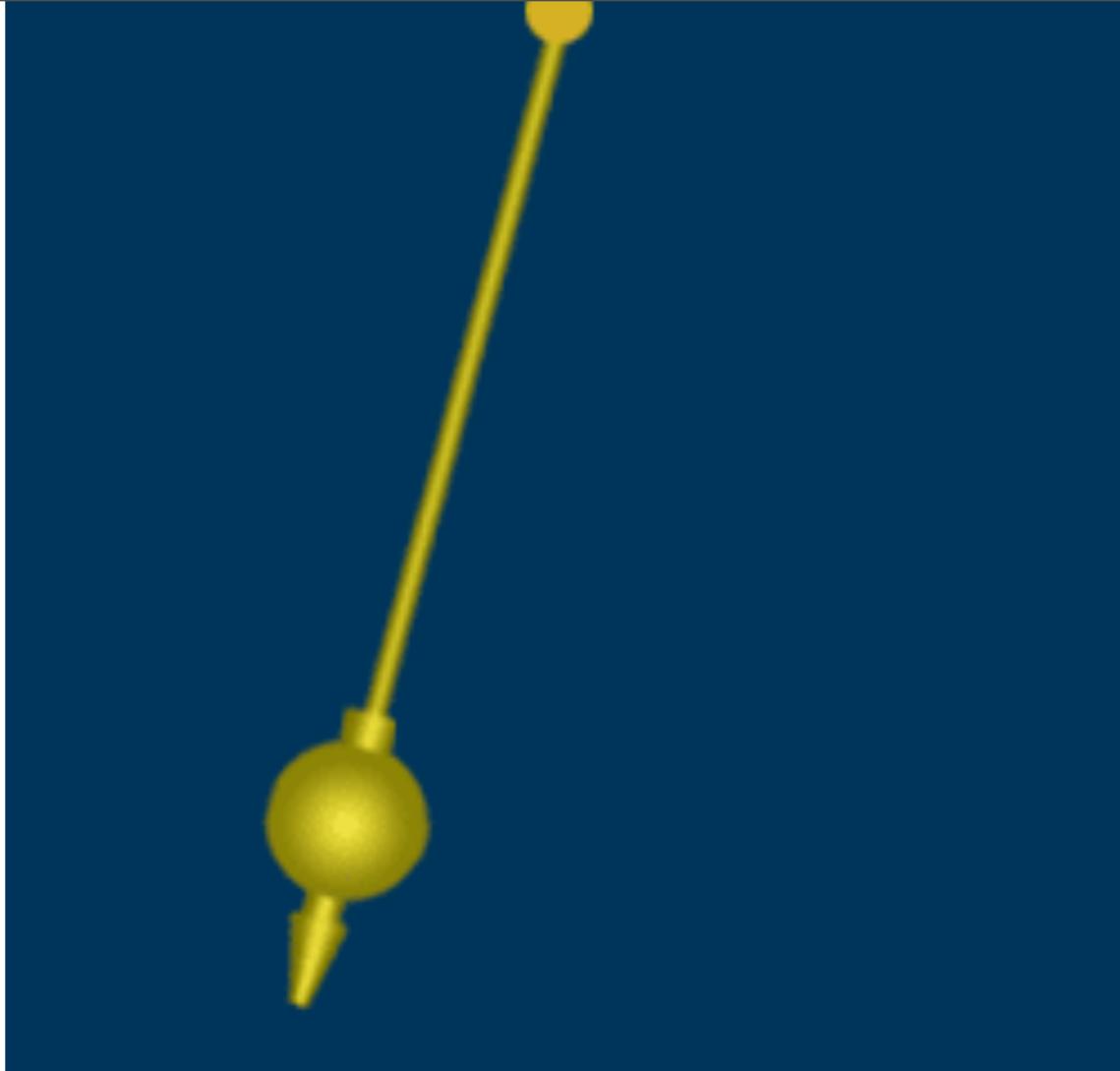
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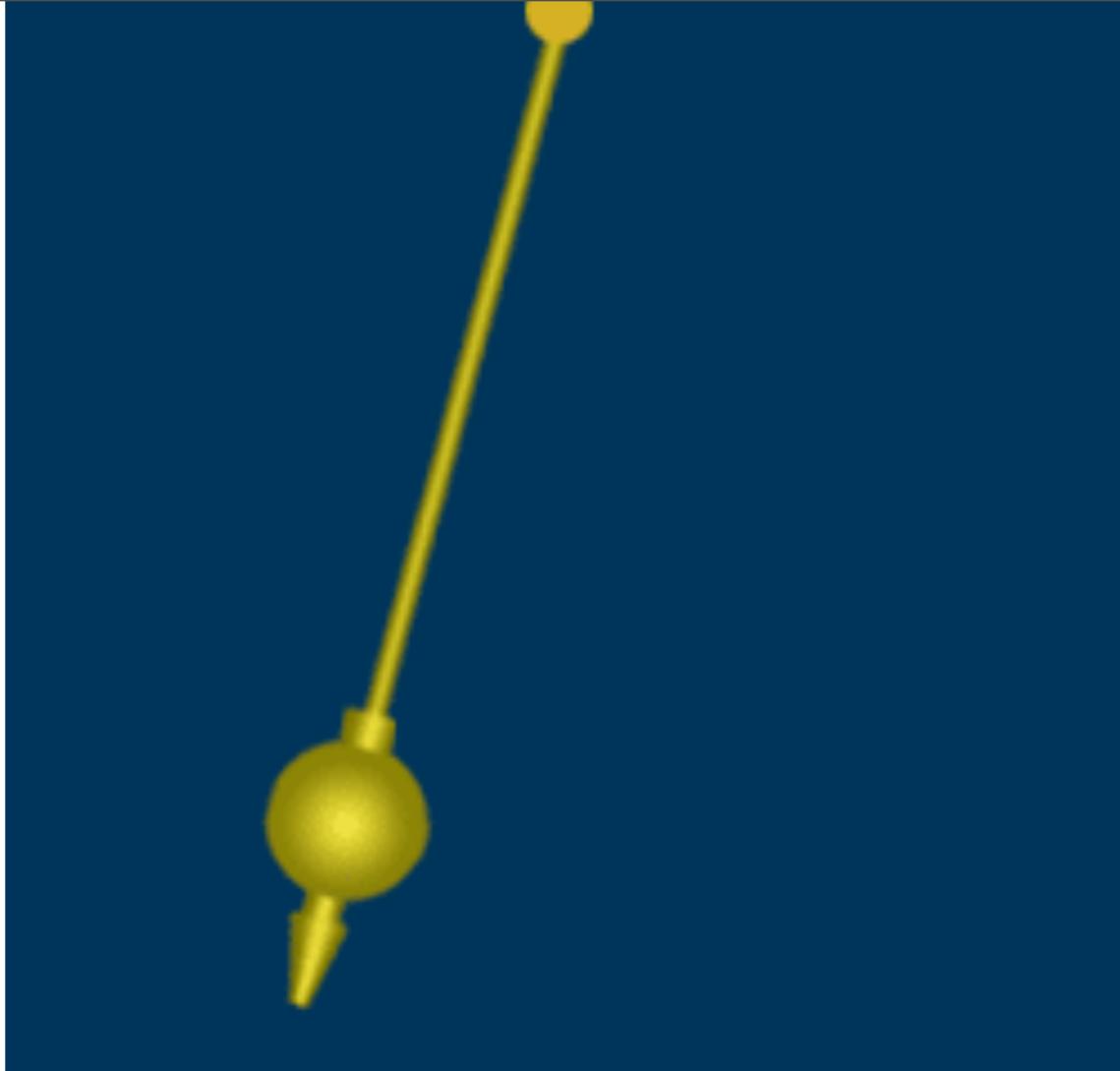
PHYSICS



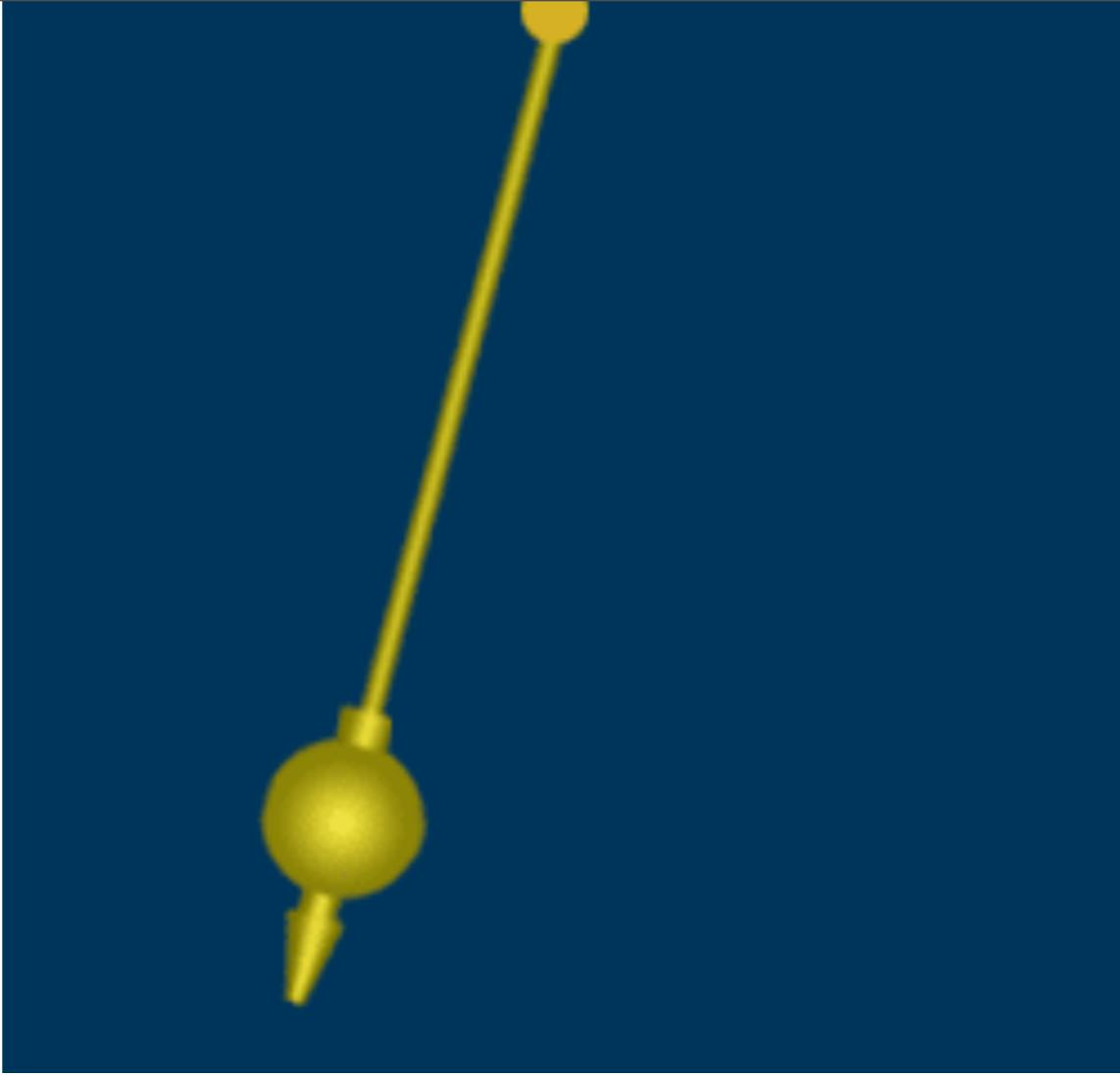
$$s = \frac{1}{2} a t^2$$







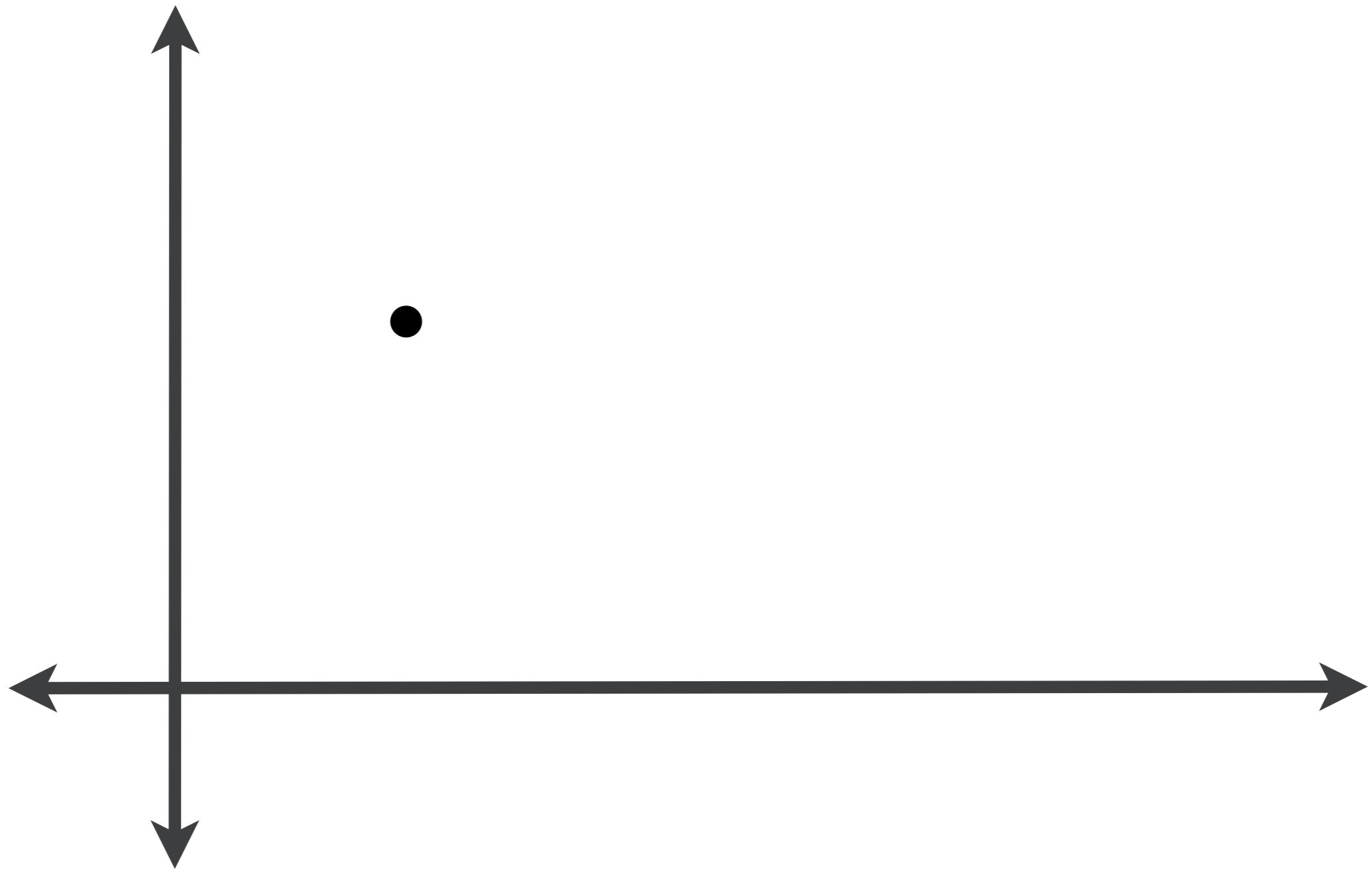
$$TE = mgh + \frac{1}{2}mv^2$$

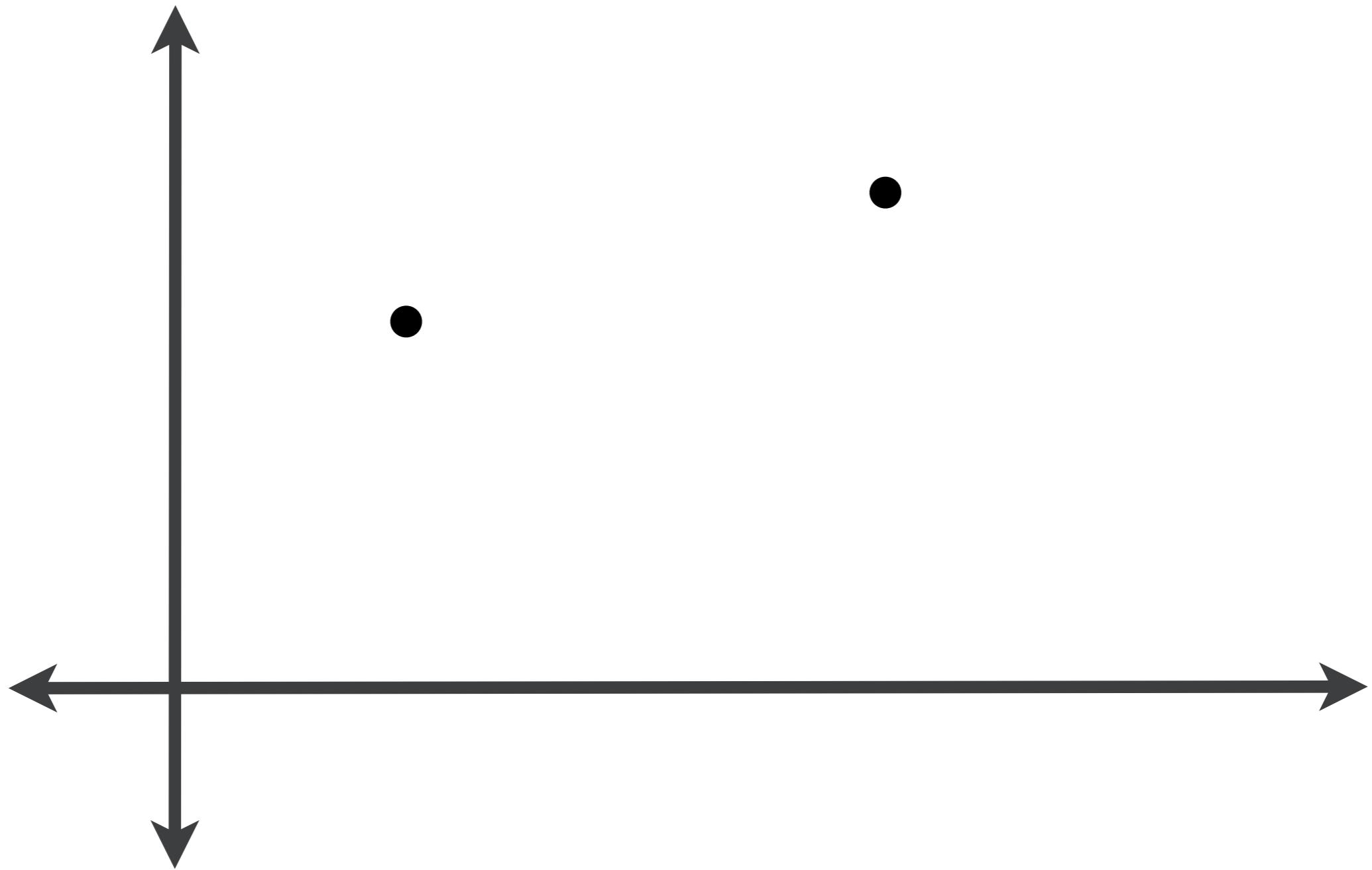


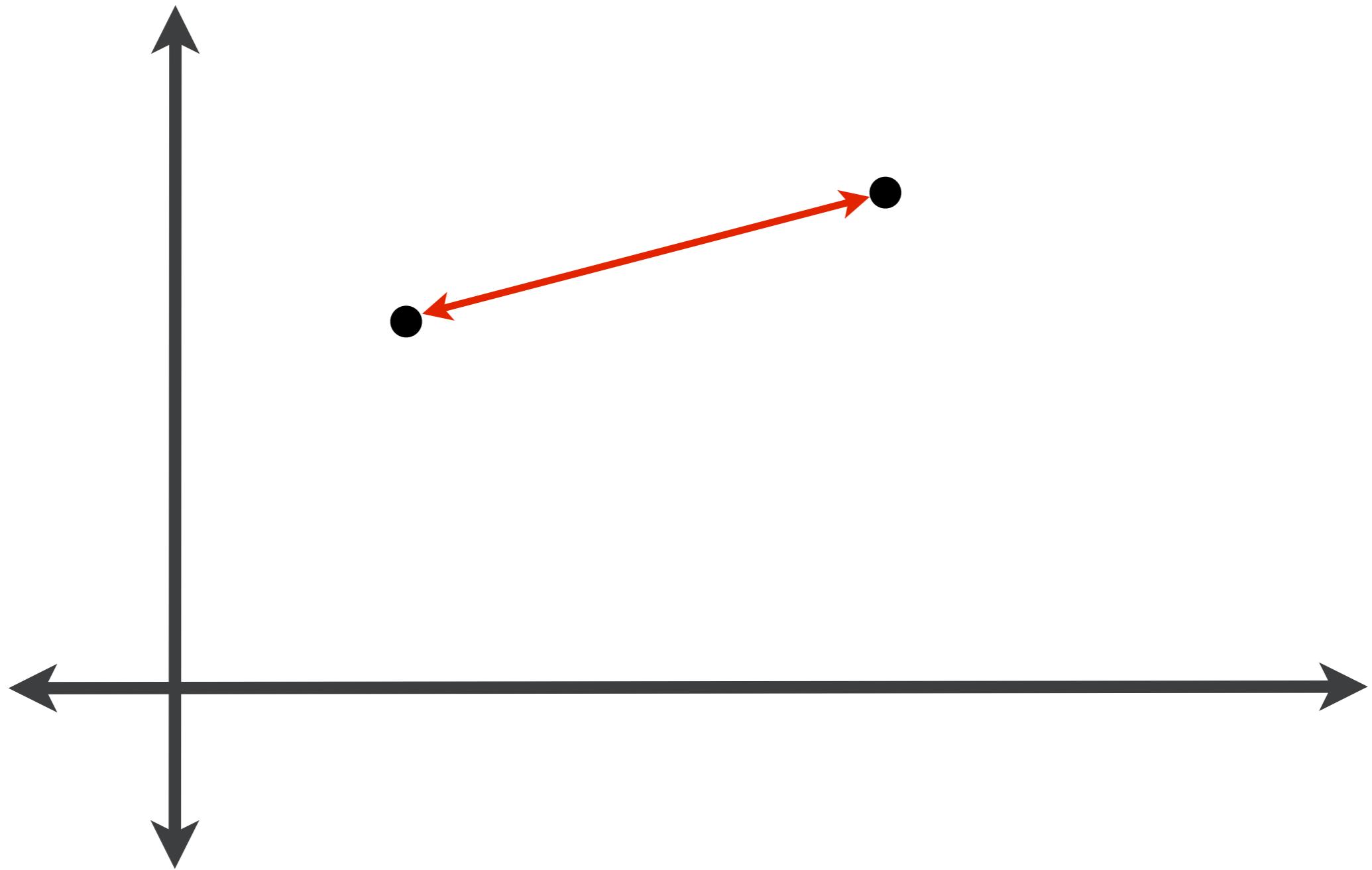
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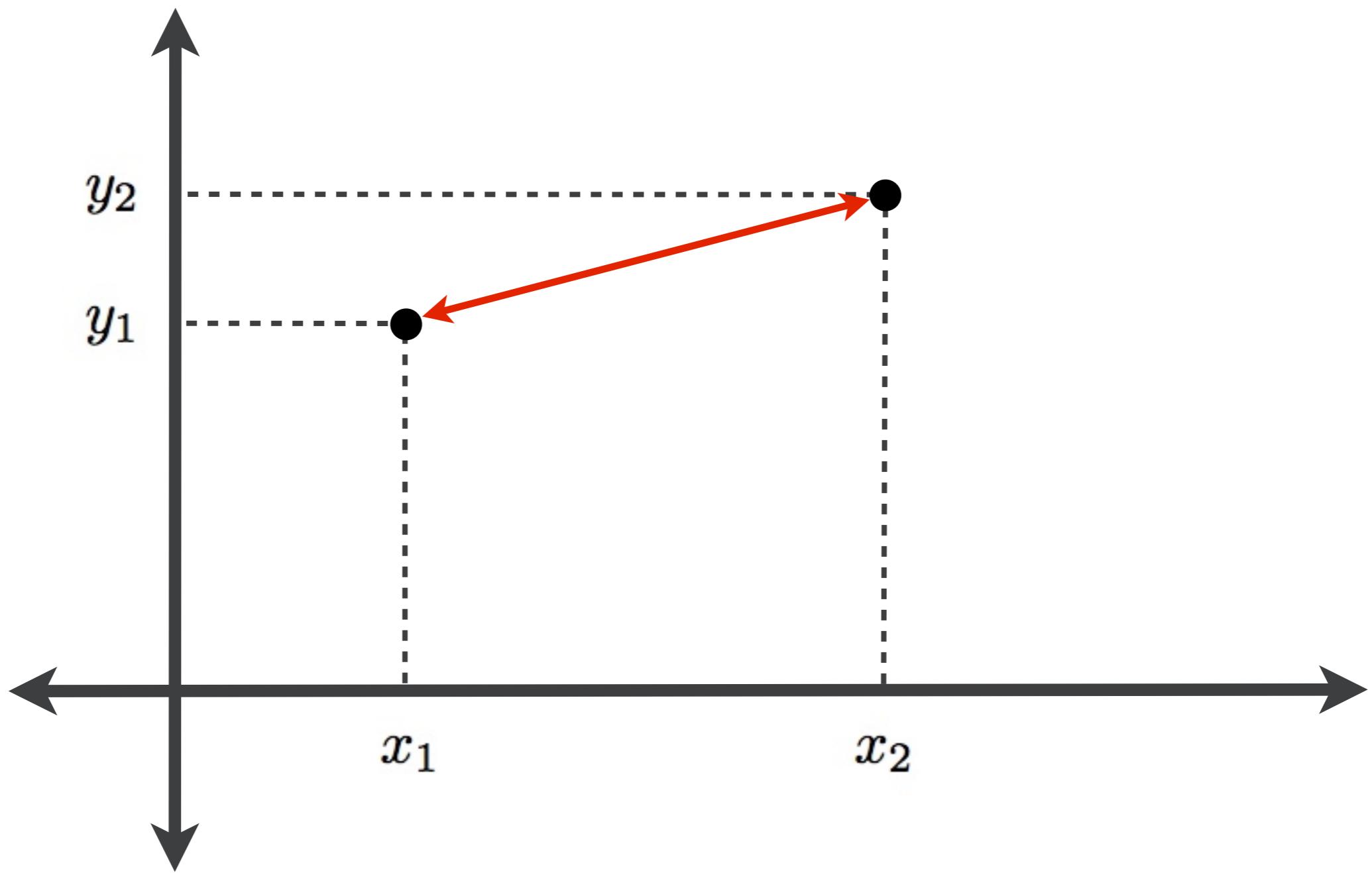
$$TE = PE + KE$$



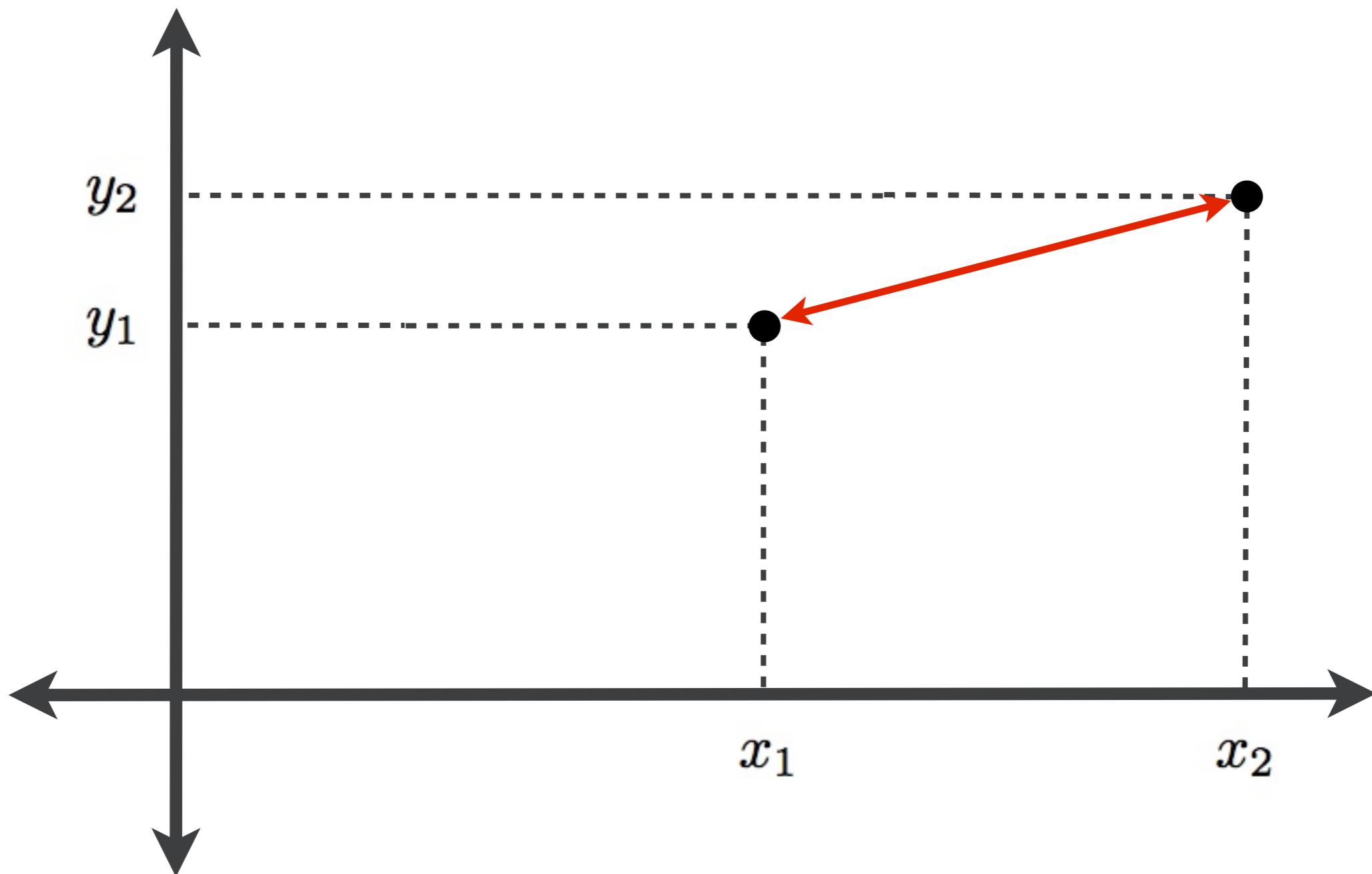




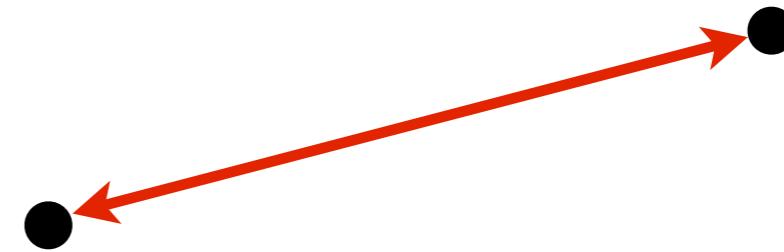


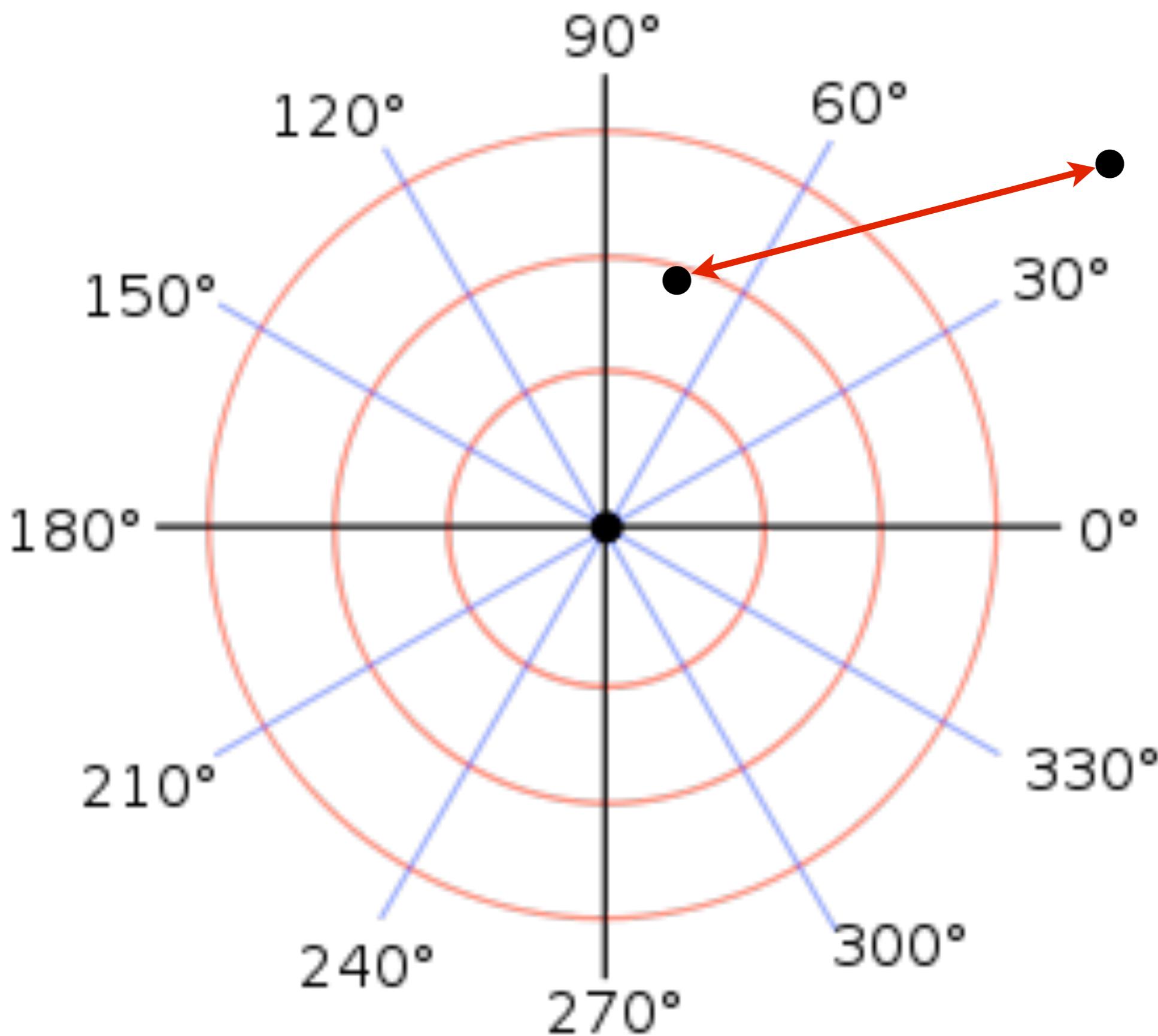


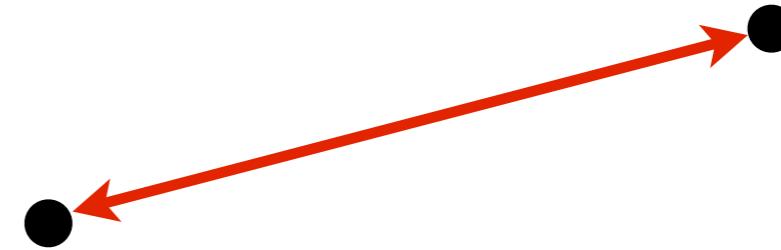
$$distance = \sqrt{(x_1 - x_2)^2 + (y_1 - y_2)^2}$$



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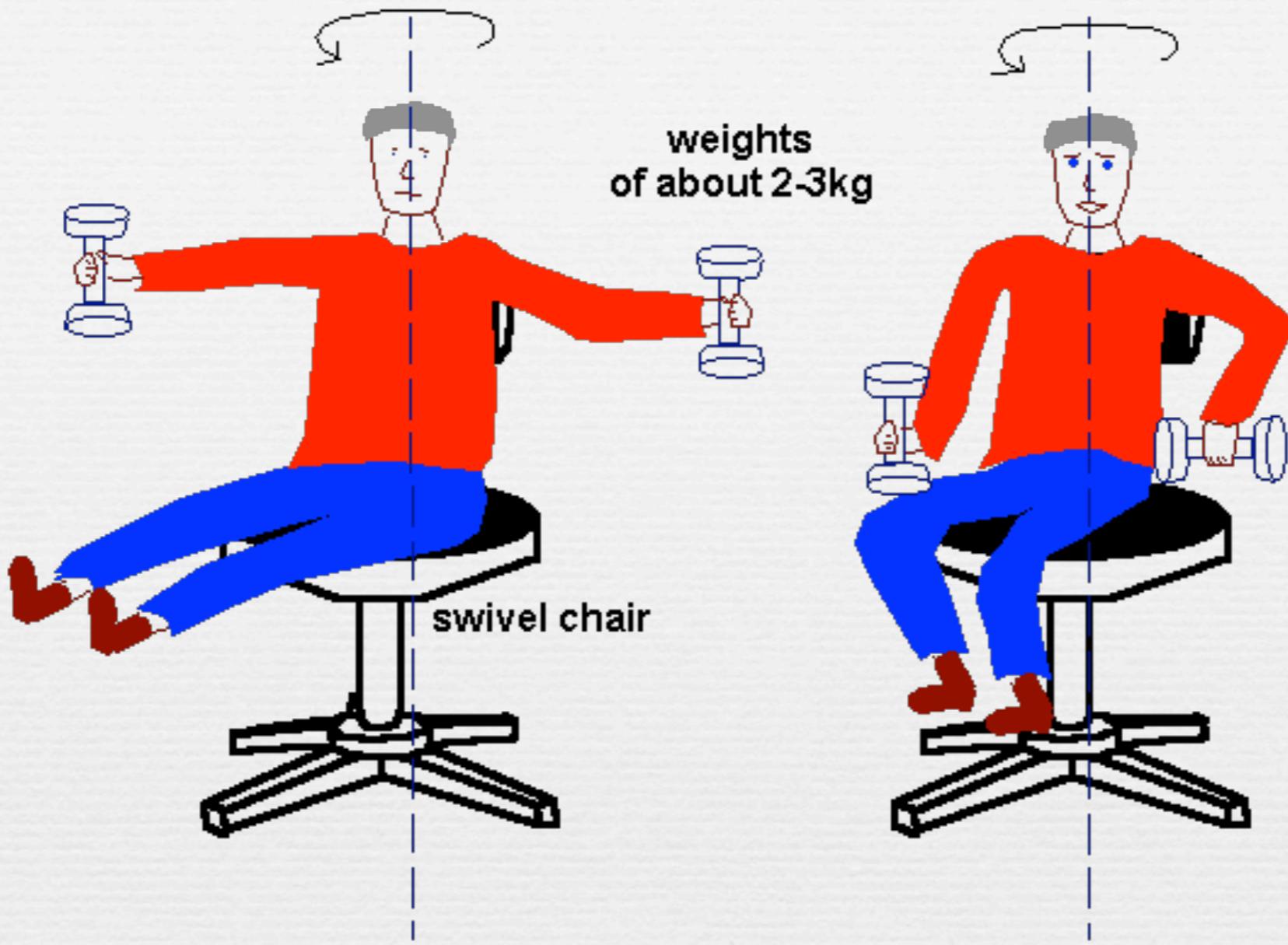






Distance is invariant under translation and change of coordinate representation.





initial angular velocity of about one
revolution every couple of seconds

final angular velocity of up to
two or three revolutions per second



Noether's Theorem

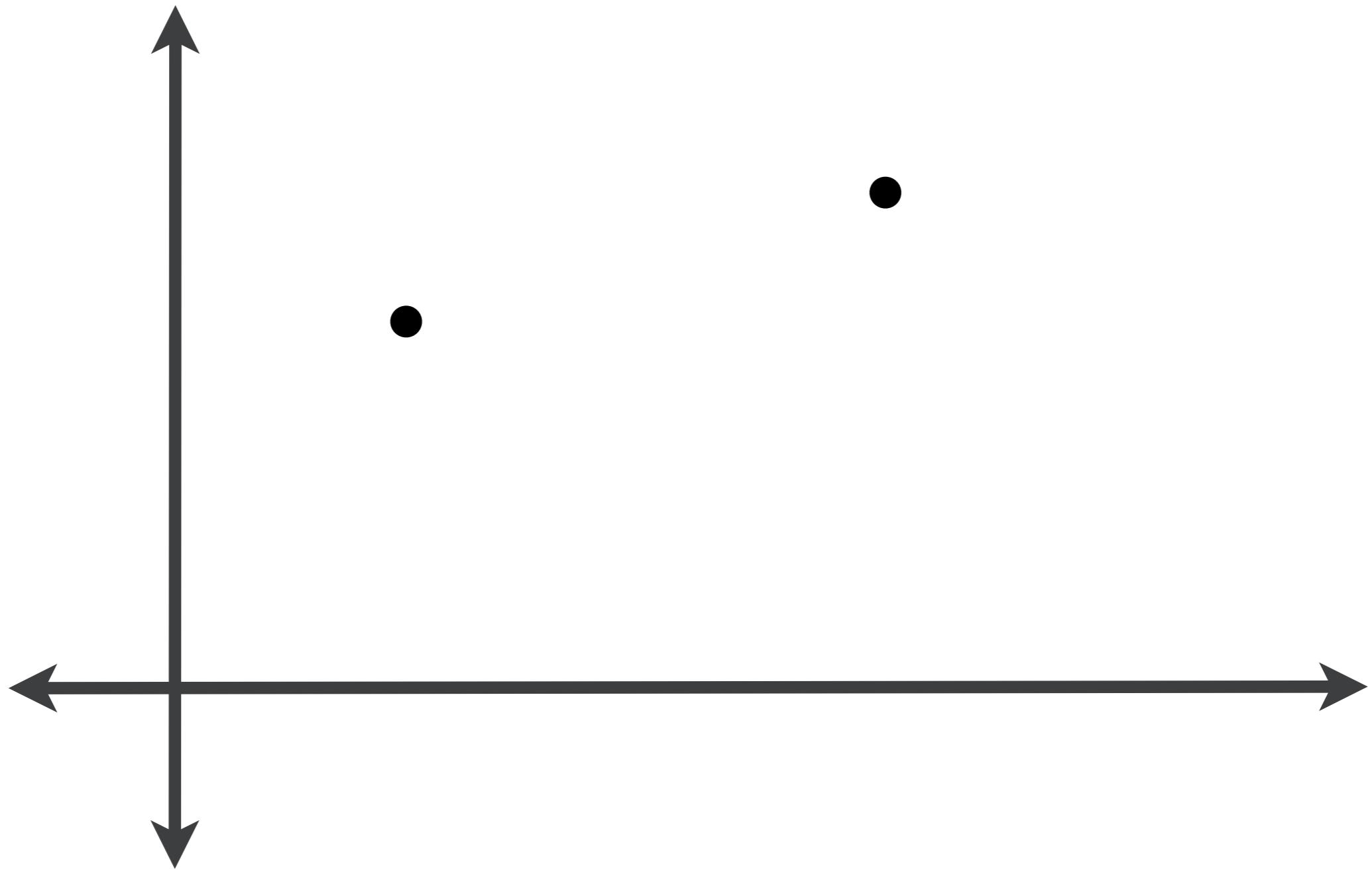


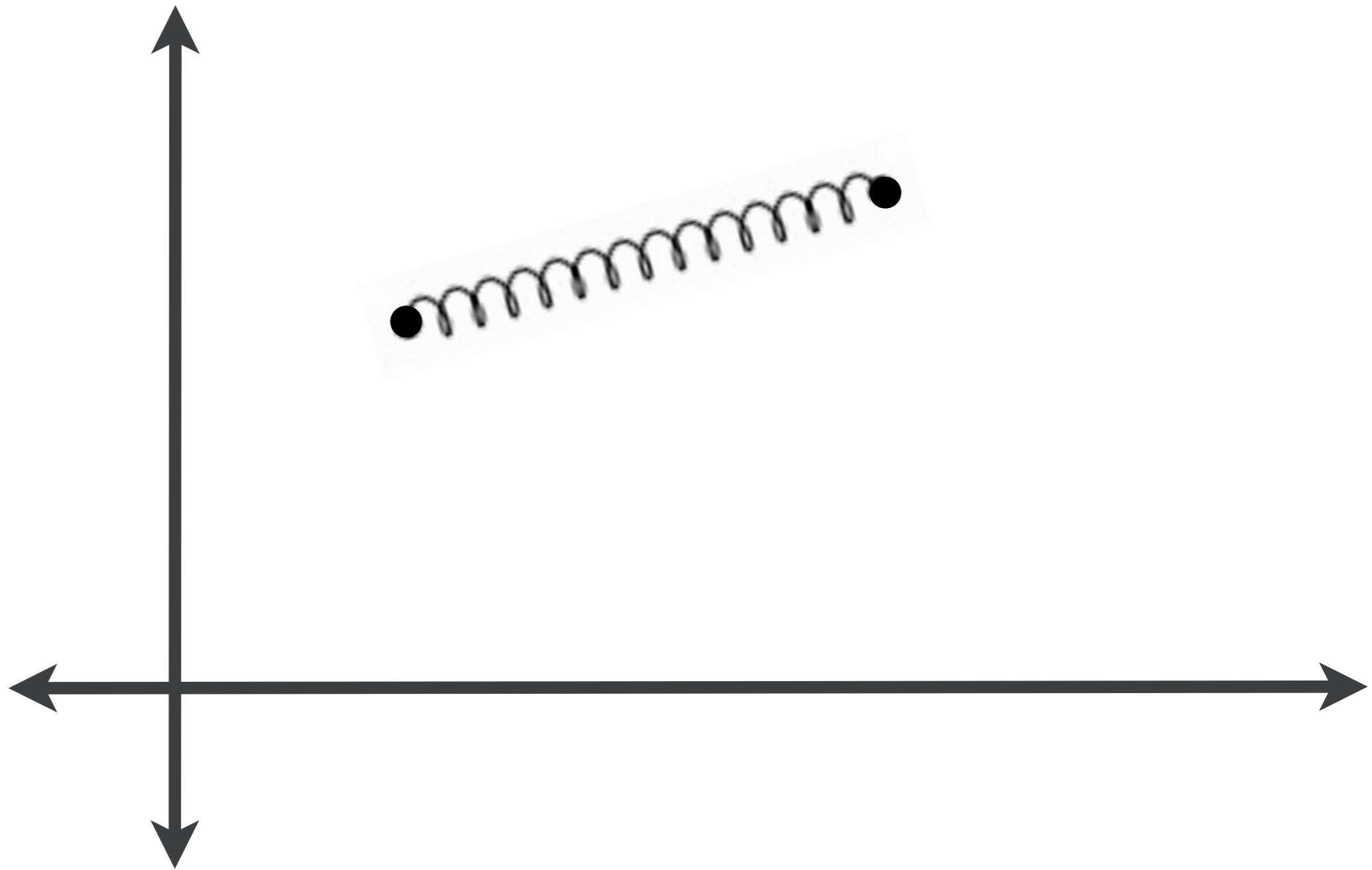
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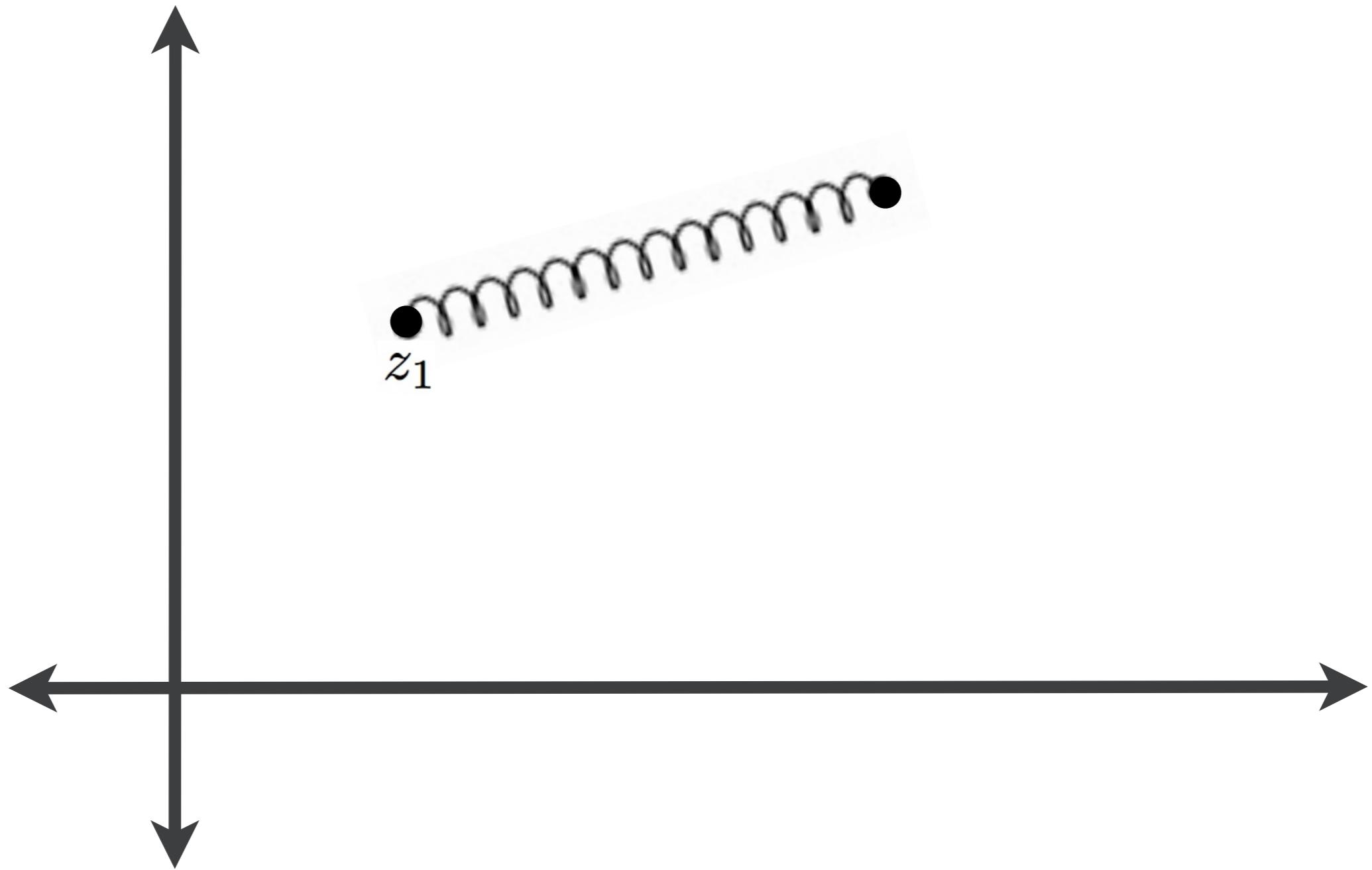
- ❖ (1915) "Any differentiable symmetry of the action of a physical system has a corresponding conservation law"

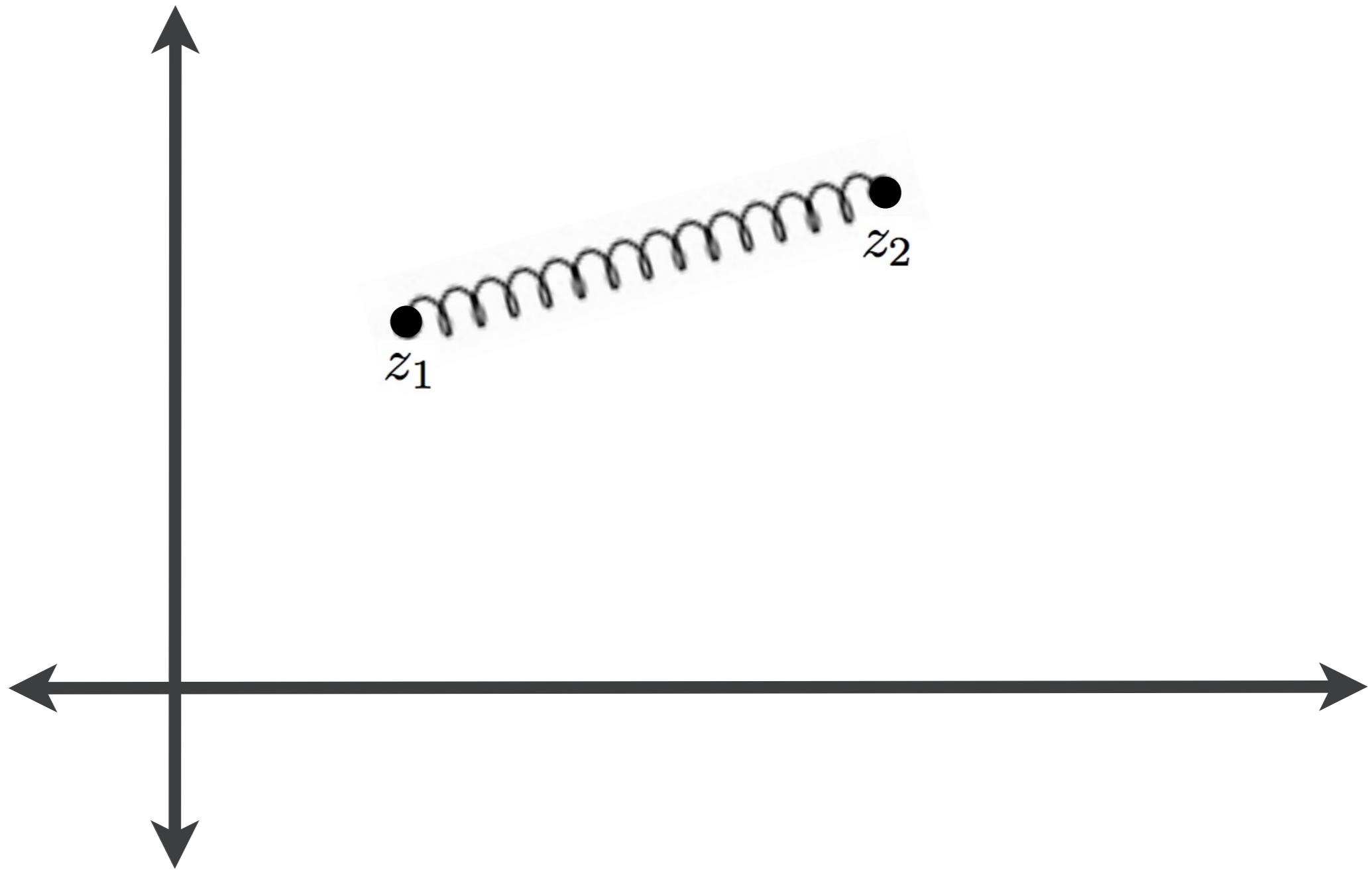


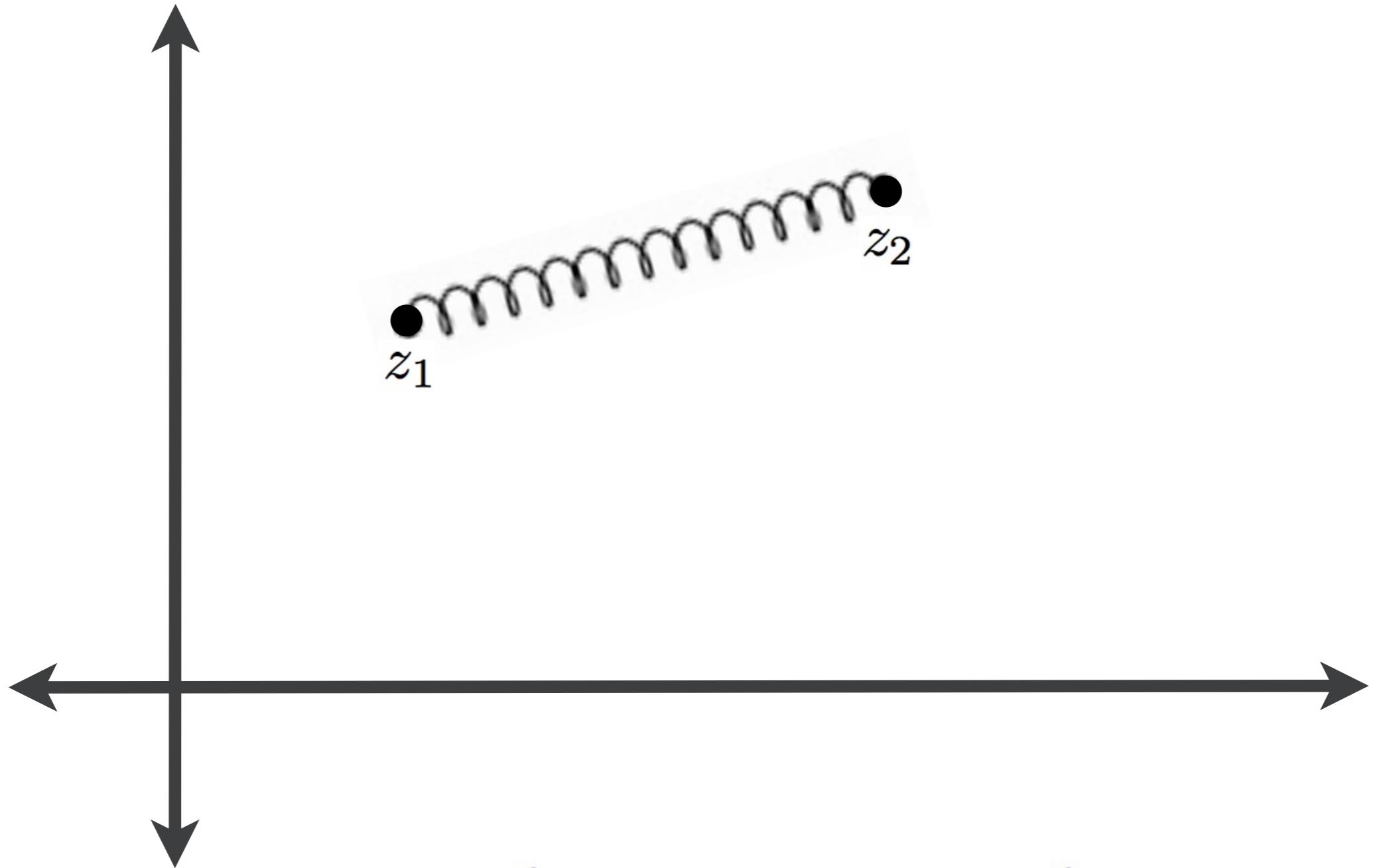
Quick Example











$$L(t, z_1, z_2, \dot{z}_1, \dot{z}_2) = \frac{1}{2}m(\dot{z}_1^2 + \dot{z}_2^2) - \frac{1}{2}k(z_1 - z_2)^2$$

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invariant under translation

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$$\forall d \in \mathbb{R}^2$$

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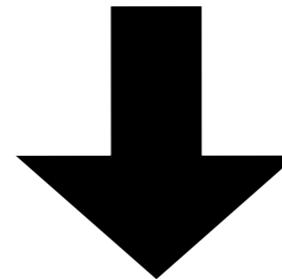
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$$\forall d \in \mathbb{R}^2 \quad L(t, z_1, z_2, \dot{z}_1, \dot{z}_2) = L(t, z_1 + d, z_2 + d, \dot{z}_1, \dot{z}_2)$$

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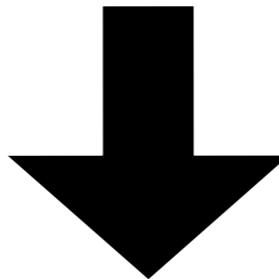
(Noether's Theorem)

$$\frac{d}{dt}m(\dot{x}_1 + \dot{x}_2) = 0$$

invariant under translation

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Conservation of Momentum

If the action

$$S[q; a; b] = \int_a^b L(t, q, \dot{q}) dt$$

is invariant under Φ_ϵ and Ψ_ϵ , then

$$\frac{d}{dt} \left(\sum_{i=1}^n \frac{\partial L}{\partial \dot{q}_i} \psi_i + \left(L - \sum_{i=1}^n \dot{q}_i \frac{\partial L}{\partial \dot{q}_i} \right) \phi \right) = 0$$

where $\phi = \frac{\partial \Phi}{\partial \epsilon} \Big|_{\epsilon=0}$ and $\psi = \frac{\partial \Psi}{\partial \epsilon} \Big|_{\epsilon=0}$

Pretty cool, right?



TYPES

$(\lambda x : \text{unit} . 42 : \text{int})$

τ

$\pi \triangleq \Lambda T1 . \Lambda T2 . \Lambda T3 .$

$\lambda v : T1 \times T2 \times T3 .$

$v[T1] (\lambda x : T1 . \lambda y :$

$\lambda f : (\text{int} \rightarrow \text{int}) \text{ ref} . \lambda n : \text{int} .$

$f := (\lambda acc : \text{int ref} . \lambda m : \text{int} .$

$\text{case } (n = m : \text{bool}) \text{ of}$

$(acc := (\text{mul !} acc m); acc) : \text{int}$

$(!f (acc := (\text{mul !} acc m); acc) (m+1)) : \text{int}$

$) (\text{ref l}) l) (\text{ref } \lambda x : \text{int} . x))$

Atkey (2014)

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- ❖ Define a type system for Lagrangian Mechanics.

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- ❖ Derive conservation laws as "free theorems" by parametricity.

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Reference:

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Theorem (Noether). Let $L(x, u, D_u^1, \dots, D_u^n)$, be a Lagrangian for $A \subseteq \mathbb{R}^n$, let $\varphi \in \text{Aut}(A)$ be a symmetry of A such that

$$\varphi(L) + LD^i(\xi) = D^i(B^i) \quad B^i \in A$$

Then the Euler-Lagrange equations admit a conservation law $\forall i. D^i(C^i) = 0$.

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"Give me a Lagrangian and a group action satisfying these constraints, I'll give you a conservation law."

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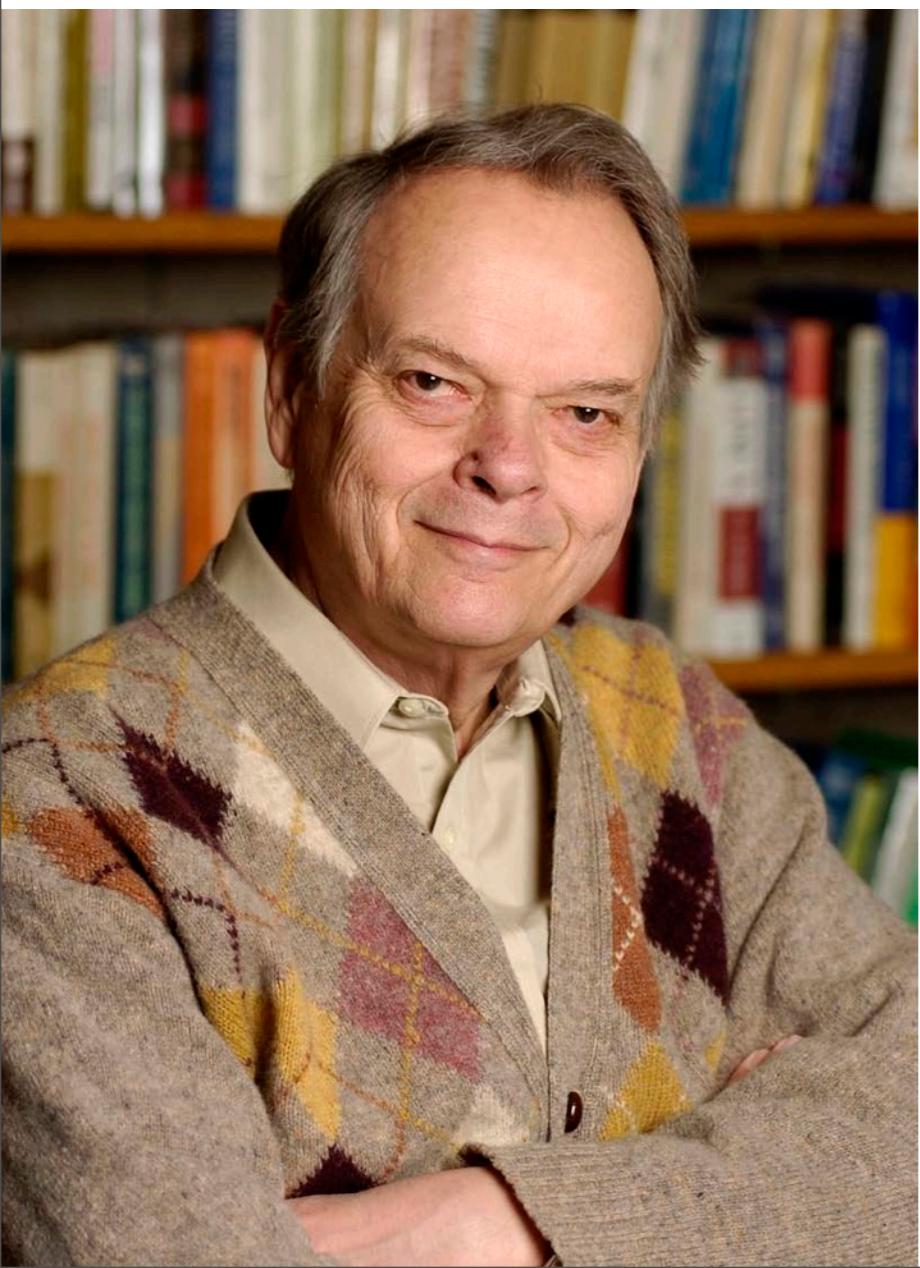
"Give me a Lagrangian and a group action satisfying these constraints, I'll give you a conservation law."

Key point: we need an automorphism (i.e. symmetry) to start with

What does this mean?



Reynolds:
types are
relations



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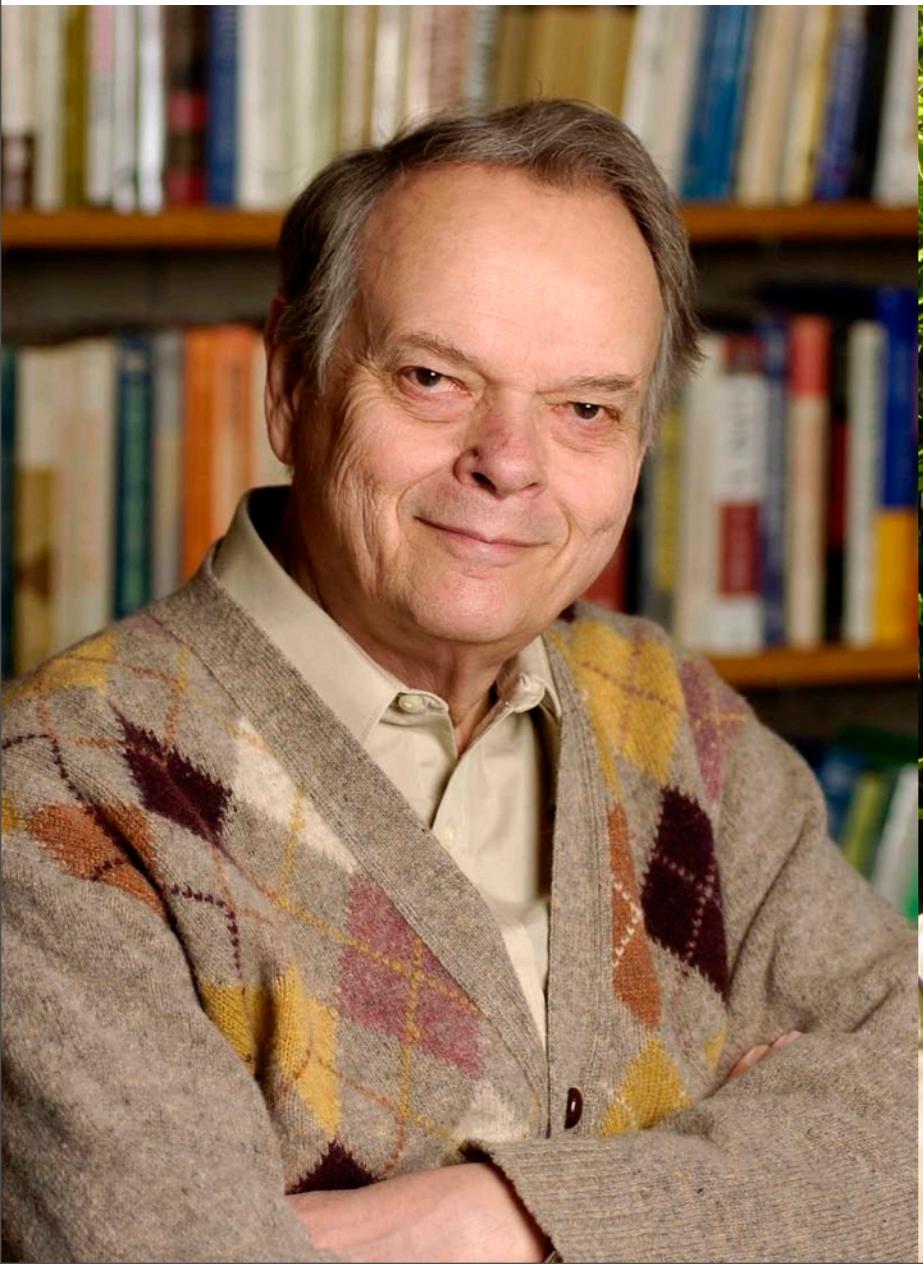
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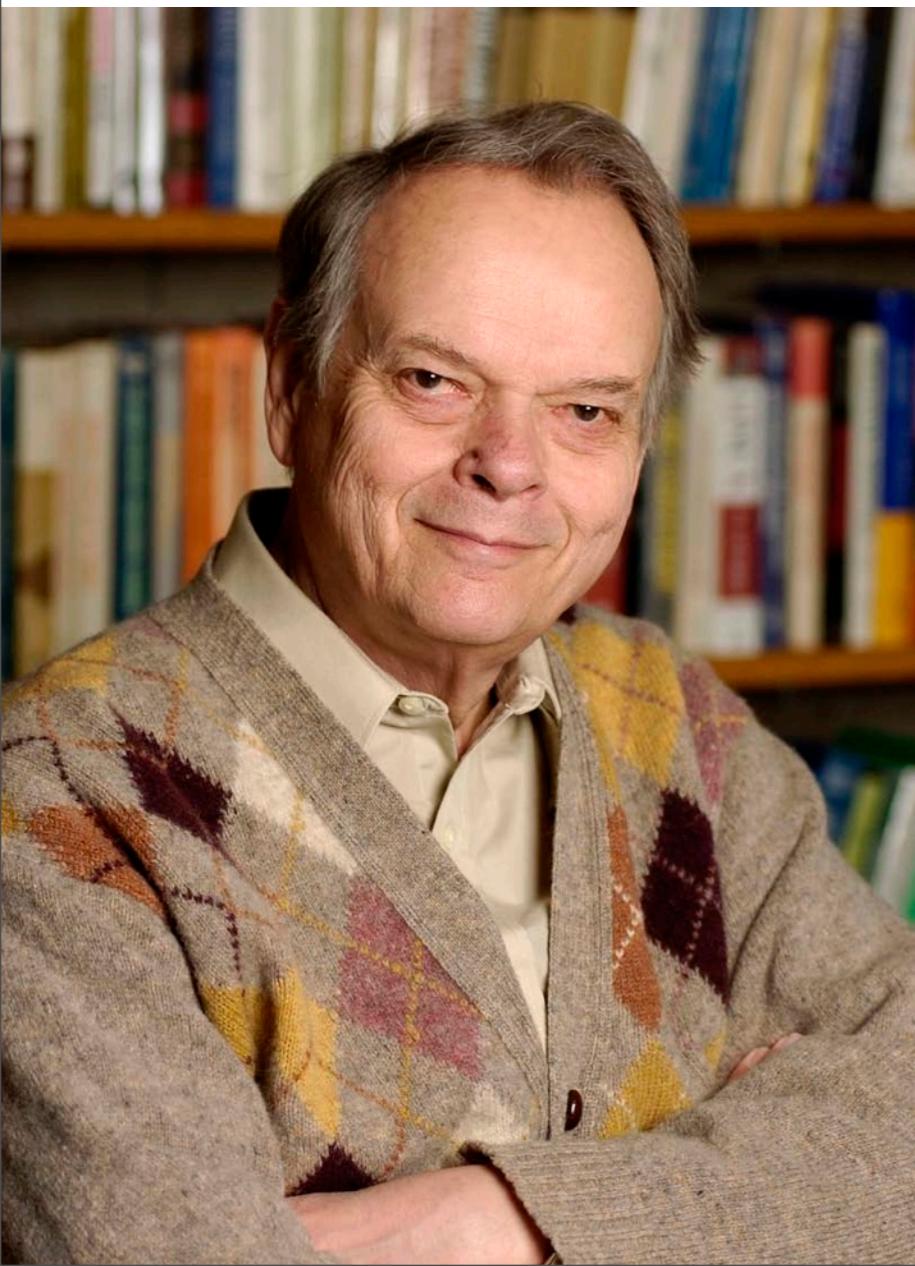
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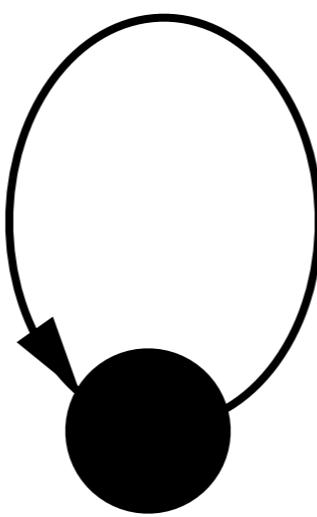
Atkey:
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are symmetries

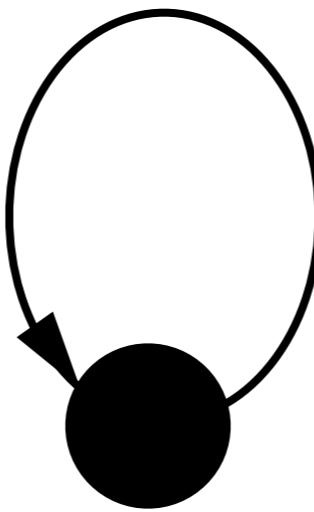


Atkey gives us a
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We'll argue: Atkey subsumes Reynolds + Wadler





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- Reynolds: types are sets, parametricity comes from the relations between them.

Kinds are reflexive graphs

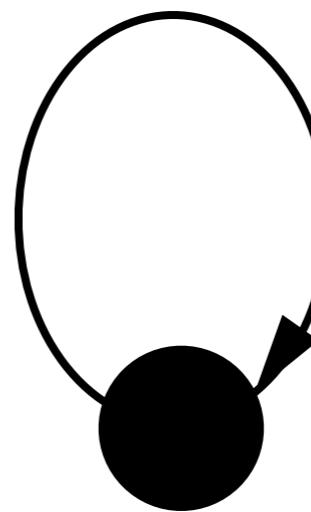
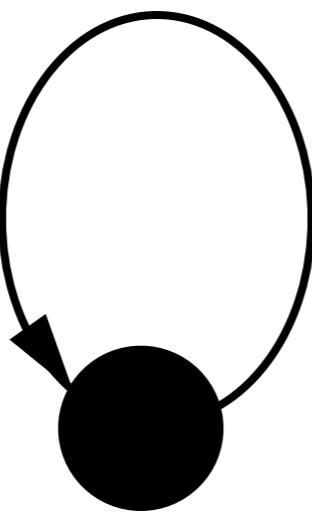
- ❖ Reynolds: types are sets, parametricity comes from the relations between them.
- ❖ Basic relation between Reynolds' types is the subset relation (\subseteq).

Kinds are reflexive graphs

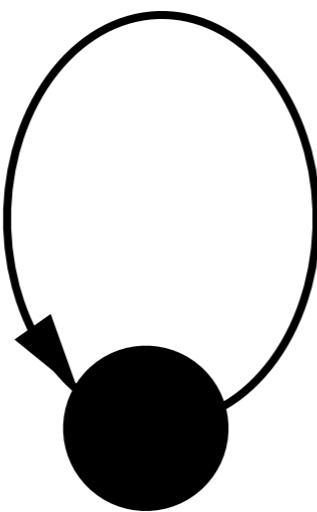
- ❖ Reynolds: types are sets, parametricity comes from the relations between them.
- ❖ Basic relation between Reynolds' types is the subset relation (\subseteq).
- ❖ Form a graph where the objects are types and the edges order types by \subseteq .

Example: bool

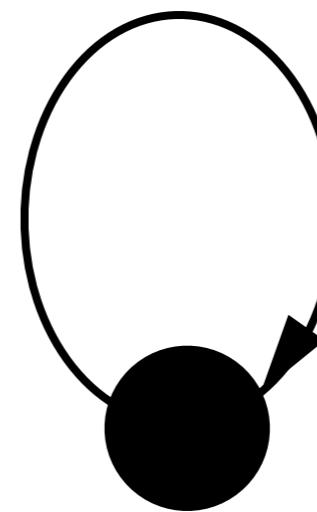
Example: bool



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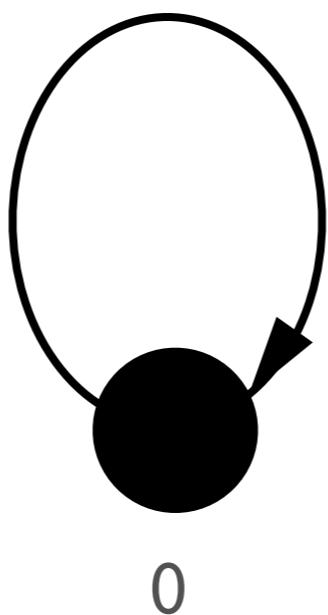
True



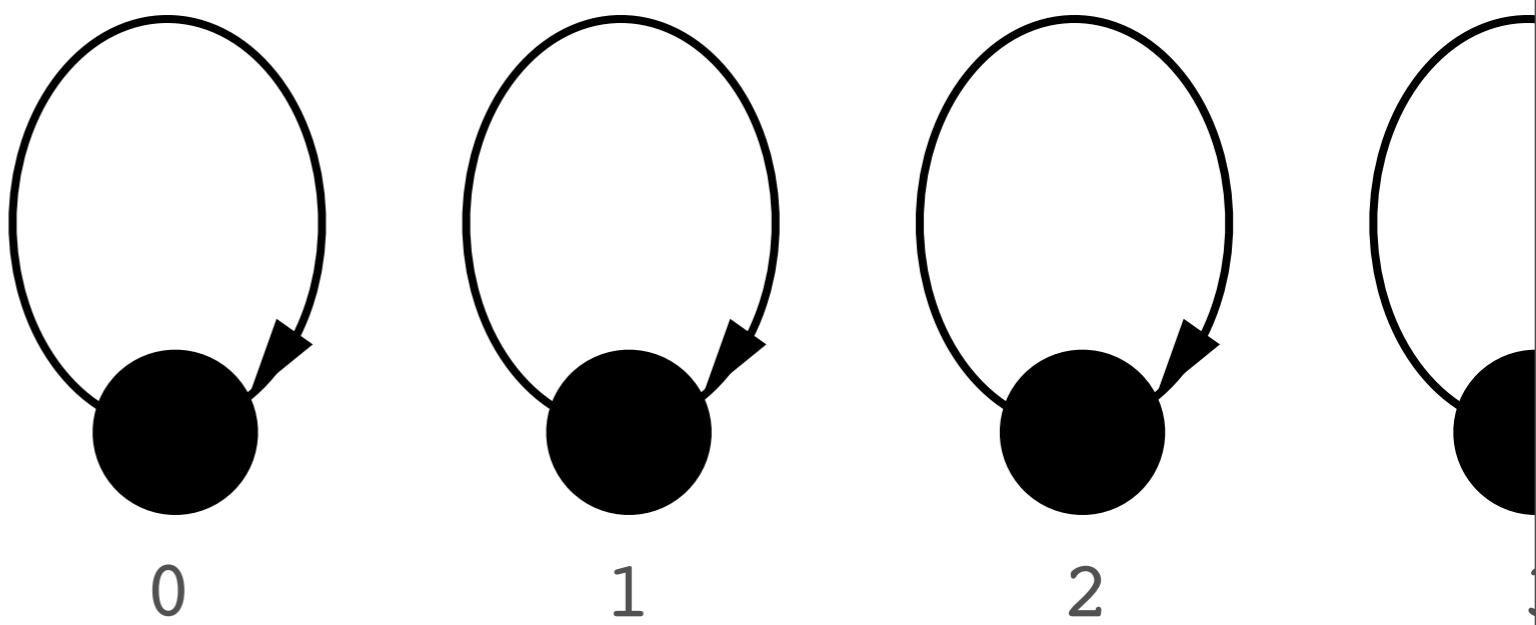
False

Example: nat

Example: nat

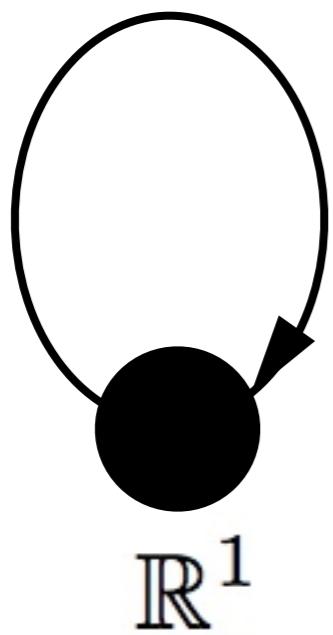


Example: nat

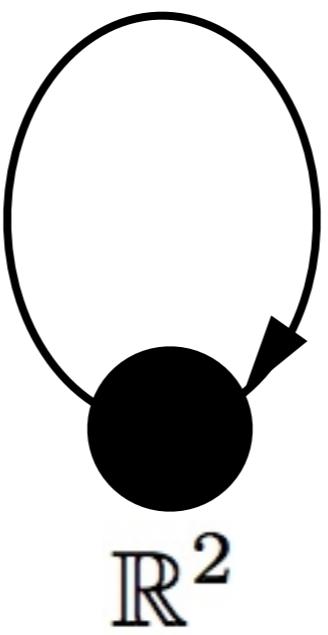


Example: cartesian space ($\mathbb{R}^1 \dots \mathbb{R}^n$)

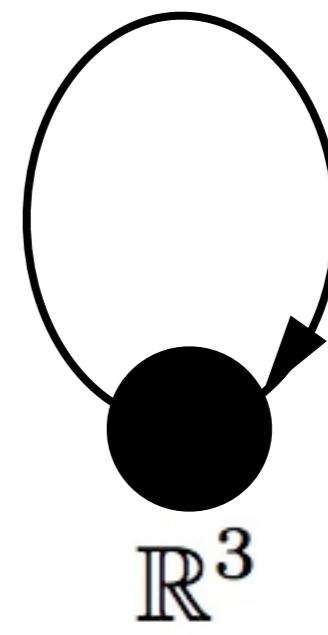
Example: cartesian space ($\mathbb{R}^1 \dots \mathbb{R}^n$)



\mathbb{R}^1



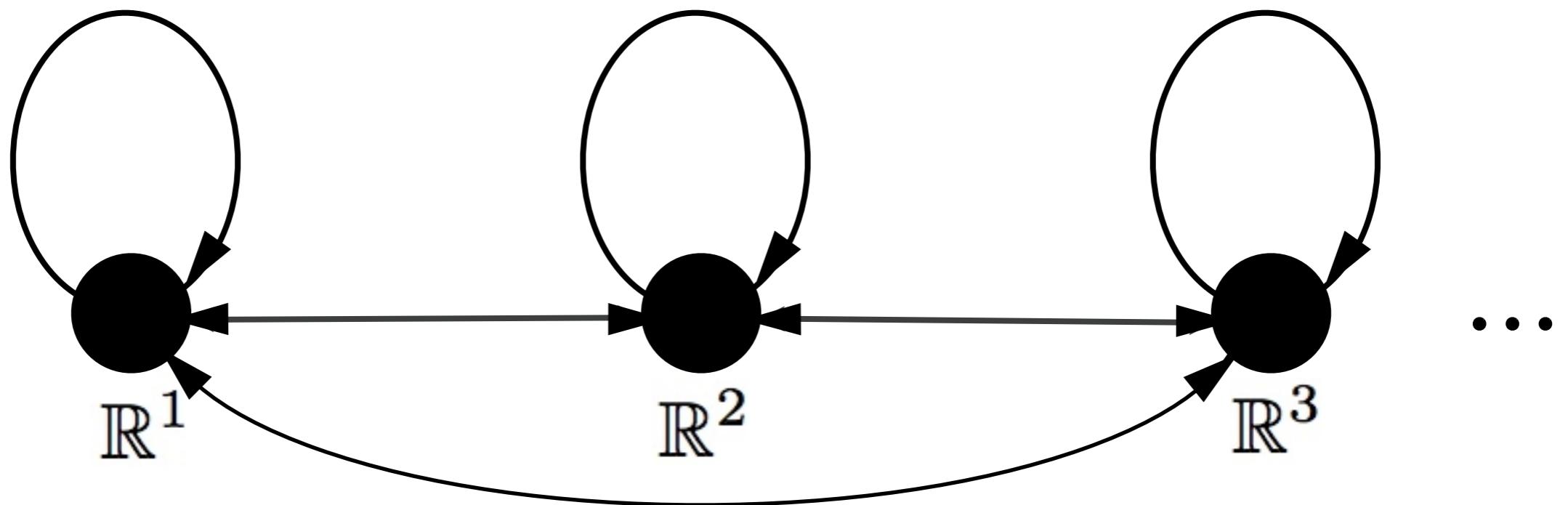
\mathbb{R}^2



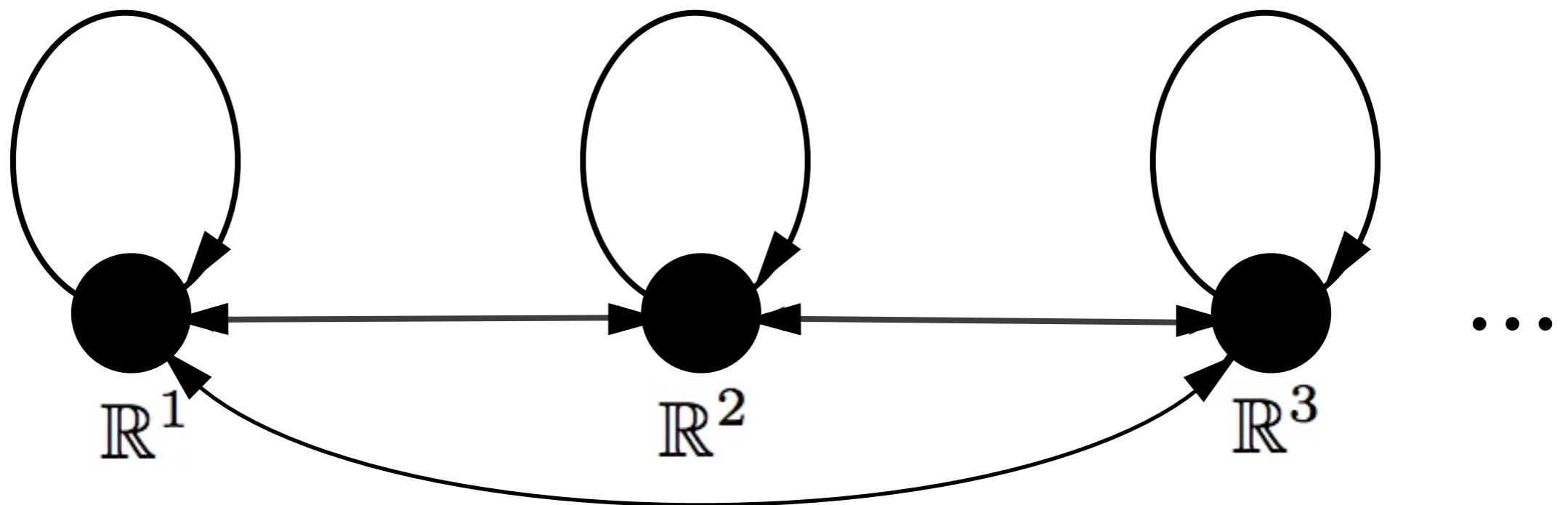
\mathbb{R}^3

...

Example: cartesian space ($\mathbb{R}^1 \dots \mathbb{R}^n$)

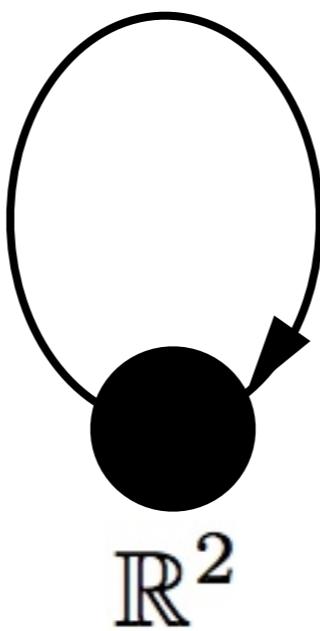


Example: cartesian space ($\mathbb{R}^1 \dots \mathbb{R}^n$)

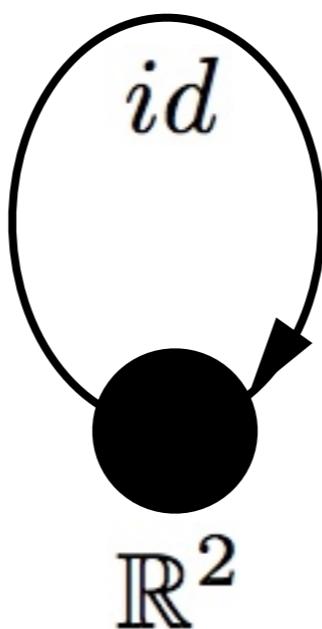


Each arrow represents a family of diffeomorphisms

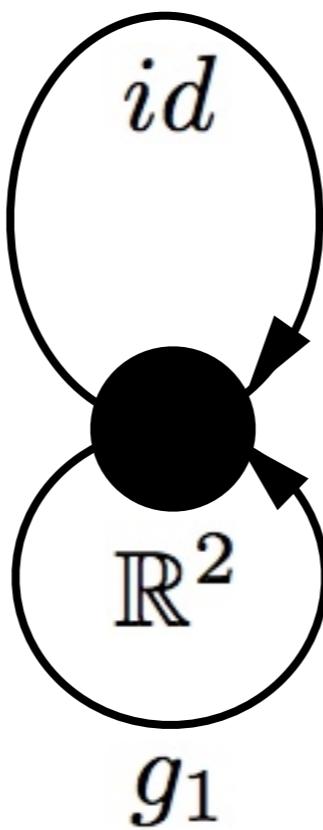
Example: cartesian space



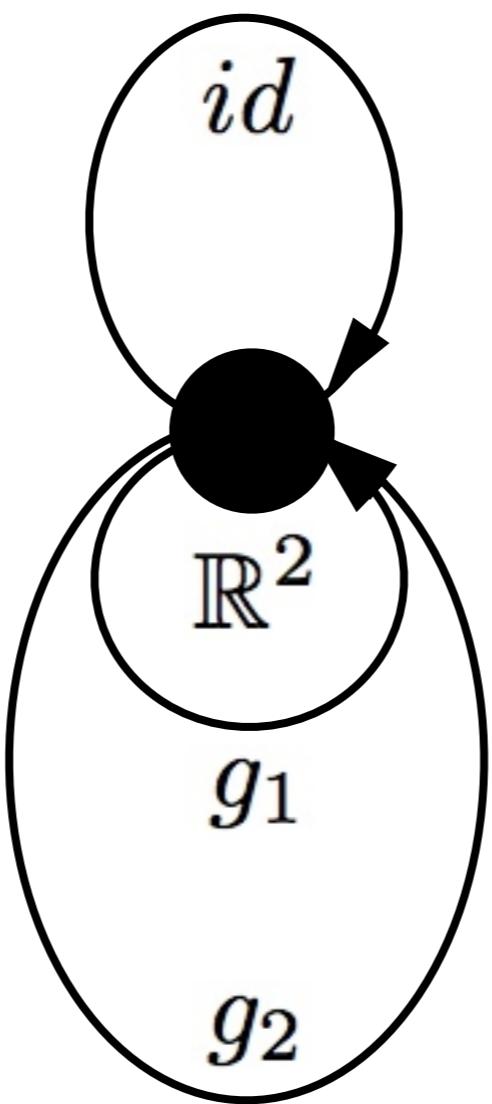
Example: cartesian space



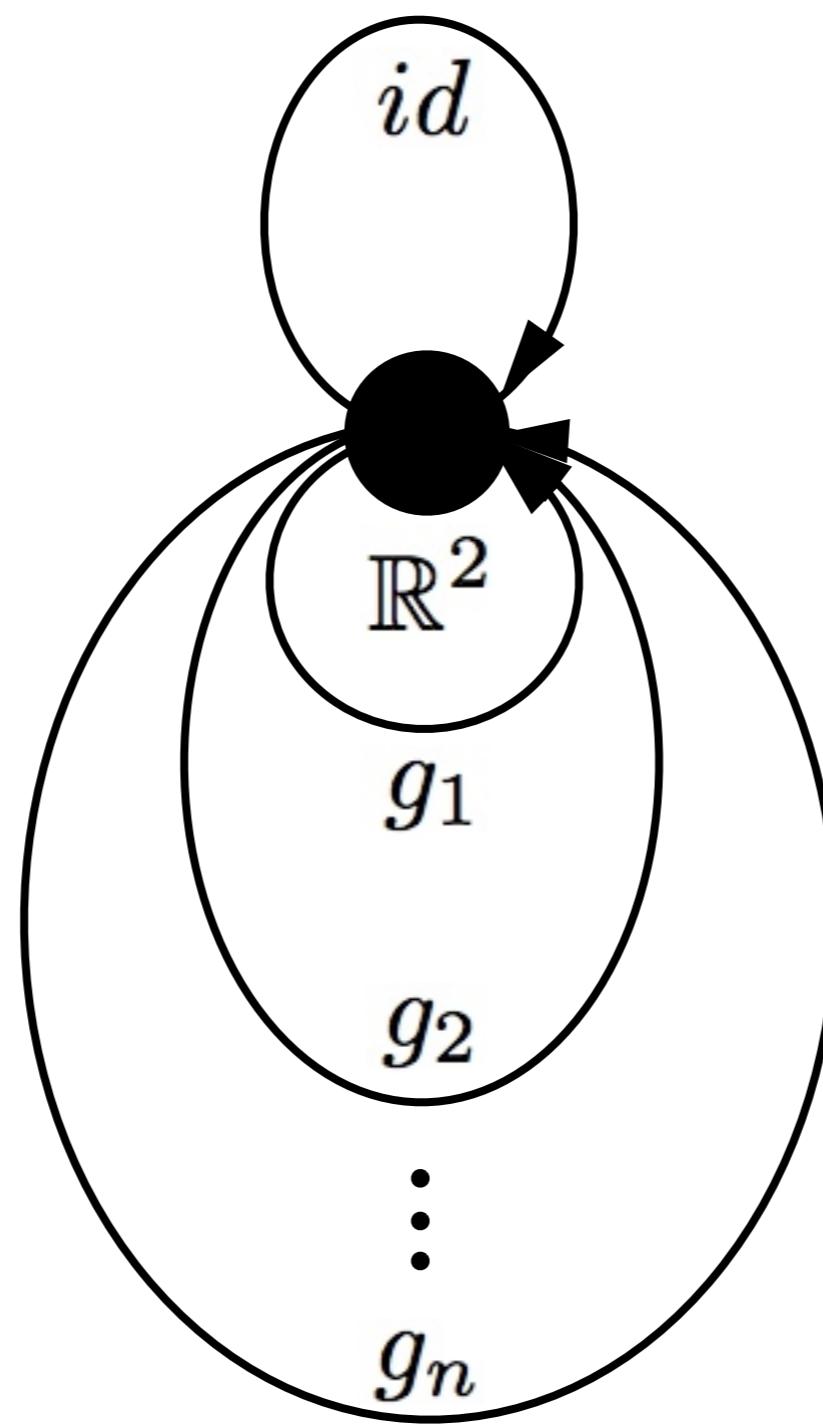
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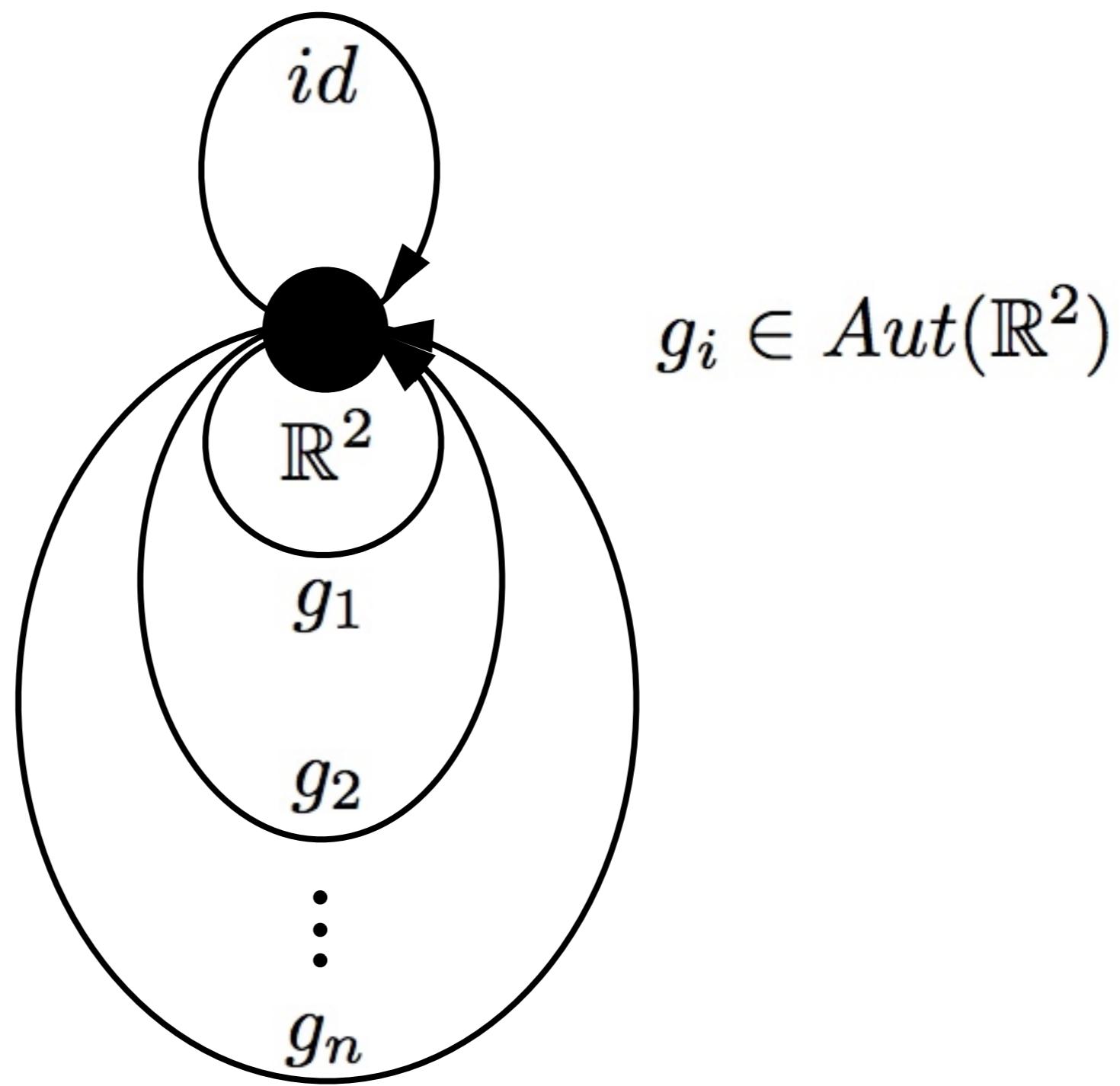
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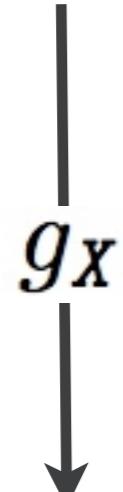
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X list

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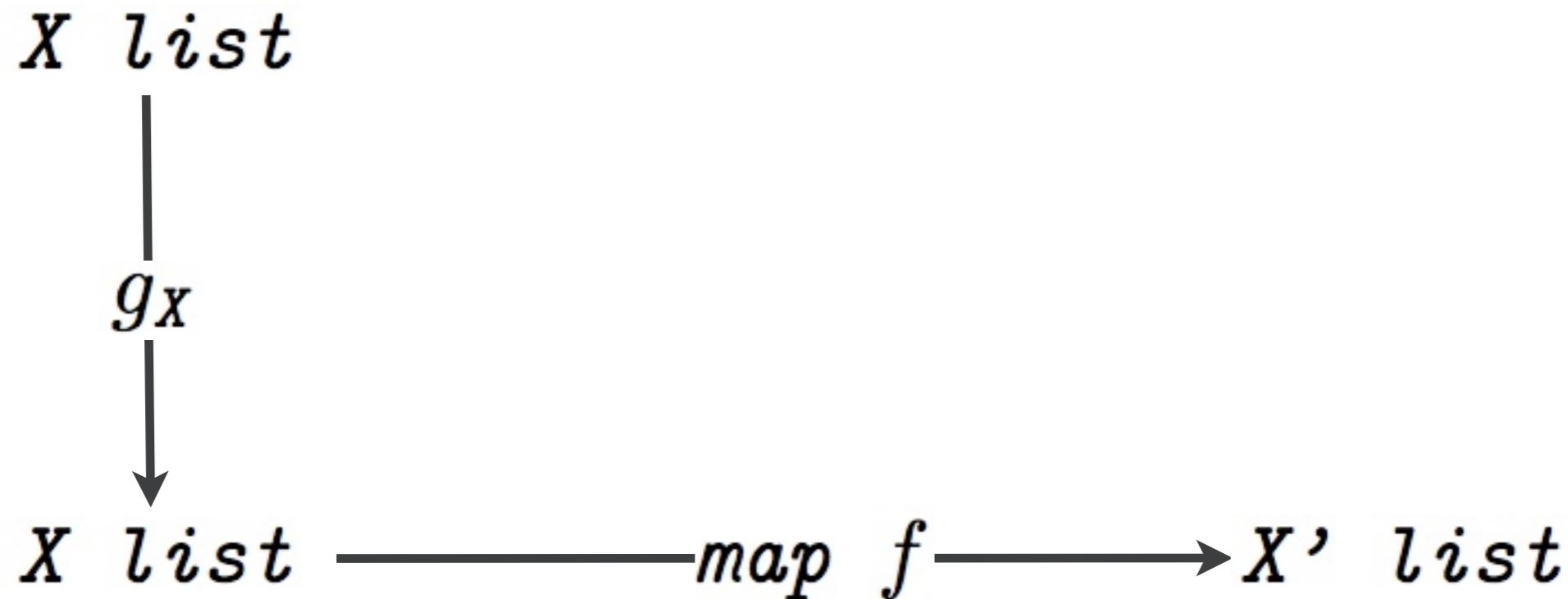
X list



X list

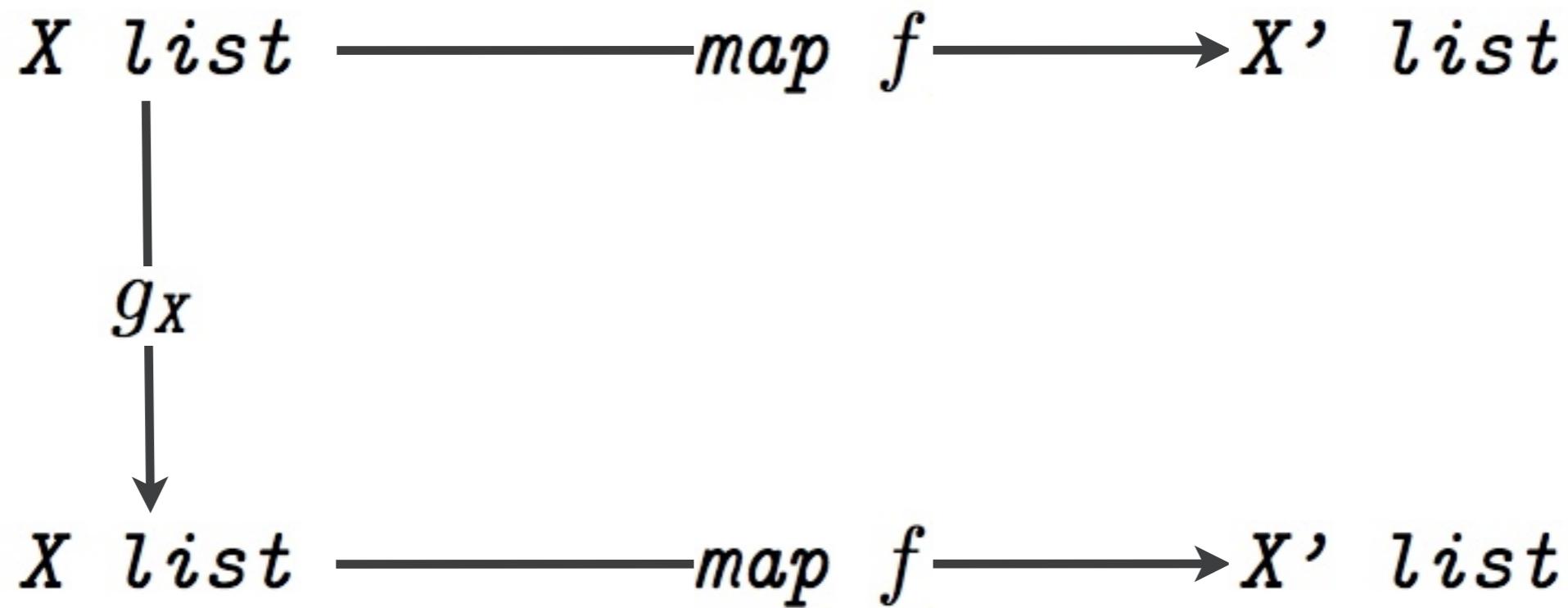
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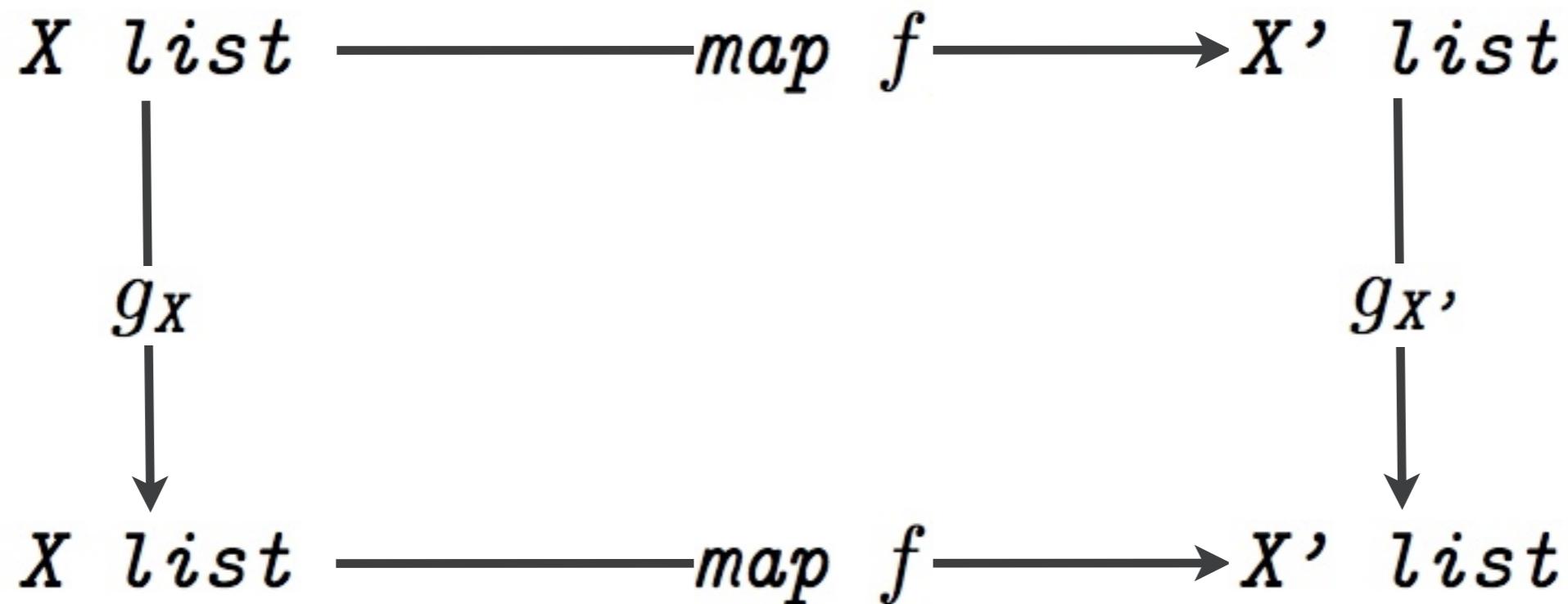
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Atkey: Main Points

- ❖ Extend System $F\omega$ with type system encoding geometric invariances.
- ❖ Interpret kinds as reflexive graphs, types as reflexive graph morphisms.
- ❖ Connect free theorems of Wadler/Reynolds with Noether's theorem via symmetries of these reflexive graphs.

Atkey: Takeaways

- ❖ Types as geometries is a powerful new way of manipulating our "syntactic discipline".
- ❖ Visual intuition, connections to group theory.
- ❖ Physics is only one potential application!



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The End