Model Checking Quantum Robots
Suggestions for Formally Verifying Quantum Robots

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May 31, 2015

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Acknowledgment

Dott. Francesco Stefanni, University of Verona

Soon-to-be Dr. Prateek Tandon, who initiated the formation of this reading group on quantum robotics.

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Milestones in Model Checking (1)

- Traditional Model Checking via Linear Temporal Logic (LTL) or Computational Tree Logic (CTL):
    1. Clarke, Jr., E. M., Grumberg, O., and Peled, D. A. Model Checking. MIT Press, Cambridge, MA, 1999.
    2. Baier, C., and Katoen, J.-P. Principles of Model Checking. MIT Press, Cambridge, MA, 2008.

- Symbolic Model Checking. McMillan, K. L. Symbolic Model Checking: An approach to the state explosion problem. PhD thesis, Carnegie Mellon University, Pittsburgh, PA, May 1992. Or, DOI: 10.1007/978-1-4615-3190-6

- Bounded Model Checking. Biere, A., Cimatti, A., Clarke, E. M., Strichman, O., and Zhu, Y. Bounded model checking. In Advances in Computers, vol. 58 of Advances in Computers. Elsevier Science Publishing, New York, NY, 2003, pp. 117–148.

Milestones in Model Checking (2)

- CounterExample-Guided Abstraction Refinement (CEGAR). Clarke, E., Grumberg, O., Jha, S., Lu, Y., and Veith, H. Counterexample-guided abstraction refinement. In Proceedings of the 12th International Conference on Computer Aided Verification (CAV 2000) (Chicago, IL, July 15?19 2000), vol. 1855 of Lecture Notes in Computer Science, Springer-Verlag Berlin Heidelberg, pp. 154?169.

- Property Directed Reachability (PDR), or Incremental Construction of Inductive Clauses for Indubitable Correctness (IC3). See http://theory.stanford.edu/~arbrad/.

Types of Mathematical Environments (2): Mathematical expressions that is separate from the main text

- To include mathematical expressions without sequential equation numbers:
  - \begin{displaymath} *formula_text* \end{displaymath}:

$$\nabla \times \mathbf{B} = \mu_0(\mathbf{J} + \varepsilon_0 \frac{\partial \mathbf{E}}{\partial t})$$

  - \$\$ *formula_text* \$\$:

$$\nabla \times \mathbf{B} = \mu_0(\mathbf{J} + \varepsilon_0 \frac{\partial \mathbf{E}}{\partial t})$$

- To include mathematical expressions with sequential equation numbers: \begin{equation}\label{eqn:default} *formula_text* \end{equation}

$$\nabla \times \mathbf{B} = \mu_0(\mathbf{J} + \varepsilon_0 \frac{\partial \mathbf{E}}{\partial t}) \tag{1}$$

Cross Referencing Equations, Tables, and Figures.

This refers to Equation 1, while this refers to the random figure, Figure 2. I am referring to Equations 2.

I am referring to Table 1.

Elements of Math Mode

- Mathematical Symbols: $+, -, =, <, >, /, |, [,]$
- Exponents (superscript) and indices (subscript):
  - x^{2} typesets into x^2
  - x_{2} typesets into x_2
- Fractions: \frac{*numerator*}{*denominator*}, $\frac{1}{2}$
- Roots: \sqrt{root}{argument}. E.g., $\sqrt[3]{8}$
- Continuation dots, ellipsis: \dots, $\dots$; \cdots, $\cdots$; \vdots, $\vdots$; and \ddots, $\ddots$.

Mathematical Symbols

- Greek symbols: \alpha, α
- Calligraphy letters: \mathcal{A}, $\mathcal{A}$
- Binary operators: \pm, $\pm$
- Relations: \ll, $\ll$
- Arrows and pointers: \Longrightarrow, $\Longrightarrow$
- A comprehensive list of mathematical symbols can be found at [**?**].

Greek Symbols

Figure: List of Greek symbols that can be typeset in LATEX

Some Typesetting Tips

- Automatically adjust brackets and braces with the \left and \right commands before the brackets and braces.

- E.g., \left[\frac{1}{2} \right] $\left[\frac{1}{\frac{3}{4}} \right]$

- \begin{equation}
  f(n) = \begin{cases}
  case-1 &: n is odd
  case-2 &: n is even
  \end{cases}
  \end{equation}

-
$$f(n) = \begin{cases} case - 1 & : \text{n is odd} \\ case - 2 & : \text{n is even} \end{cases} \tag{2}$$

Set of Equations

\begin{gather}
minimize BLAH
\underline{x} \in S
subject to:
\end{gather}

$$\text{minimize } f = a \cdot x^2 + b \cdot x^5$$
$$\underline{x} \in S$$
$$\text{subject to :}$$
$$x - y < 6$$
$$x + z > 7$$

Matrices

\left (\begin{array}{ccc}1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{array} \right)

$$\left(\begin{array}{ccc} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{array} \right)$$

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Typesetting Tables in LATEX Documents (1)

```
\begin{table}[htdp]
\caption{default} \label{tab:default}
\begin{center}
\begin{tabular}{|c|c|c|c|}
\hline
Level & Use & Features & Abstraction \\
\hline
Level & Use & Features & Abstraction \\
\hline
Level & Use & Features & Abstraction \\
\hline
\end{tabular}
\end{center}
\end{table}
```

Typesetting Tables in LaTeX Documents (2)

Table: A simple table that is typeset in LaTeX.

Level	Use	Features	Abstraction
Level	Use	Features	Abstraction
Level	Use	Features	Abstraction

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Including Graphics in LaTeX Documents (1)

```
\begin{figure}[h]
\centering
\includegraphics[width=6in]{ – INSERT FILENAME OF FIGURE}
\caption{INSERT CAPTION HERE}
\label{fig:INSERT LABEL OF FIGURE}
\end{figure}
```
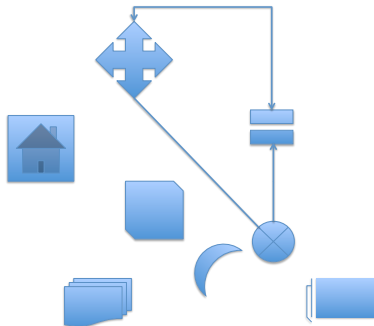
Including Graphics in LaTeX Documents (2)

Figure: A random figure.

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Additional Formal Verification Techniques for Quantum Robots (1)

- Reachability analysis:
    -
    - Possible solution: Quantum partially-observable Markov decision processes (QMDPs)
    - Reference: Shenggang Ying and Mingsheng Ying, "Reachability Analysis of Quantum Markov Decision Processes," *arXiv*, Cornell University, Ithaca, NY, July 9, 2014. Available online from *arXiv* as Version 2 at: http://arxiv.org/abs/1406.6146v2; May 30, 2015 was the last accessed date.
- Quantum Equivalence Checking:
    - Given 2 models of a quantum robot, determine if they are functionally equivalent.
    - Use quantum information decision diagrams (QuIDD), global-phase equivalence, and relative-phase equivalence (Viamontes et al., 2009).
    - Ditto for tensor calculus, dynamic tensor products, partial

Additional Formal Verification Techniques for Quantum Robots (2)

- SMT-based quantum formal verification:
  - Use SMT solver (decision procedure for satisfiability modulo theories) as reasoning engine for formal verification
  - Use reasoning/computational engine for hybrid model checking and theorem proving or model checking and equivalence checking
  - Use fragments of 1st-order logic, such as differential dynamic logics, for hybrid systems verification; see work by Prof. André Platzer at http://symbolaris.com/.
  - Get the quantum logic equivalent of these.
  - References:
    1. Platzer, A. Logical Analysis of Hybrid Systems: Proving Theorems for Complex Dynamics. Springer- Verlag Berlin Heidelberg, Heidelberg, Germany, 2010.

Additional Formal Verification Techniques for Quantum Robots (3)

- Exploit equivalence of maximum satisfiability (Max-SAT), pseudo-boolean optimization (PBO) , and wighted PBO:
  1. Use meta-algorithms via algorithmic portfolio optimization to select the "best" or set of good solutions (Max-SAT, Max-SMT, PBO, or Weighted PBO).
  2. Engineer quantum logic variant/equivalent.
  3. Turn numerical models in the time domain to algebraic models in the frequency domain, via transform methods (e.g., Fourier transform, Laplace transform, and z-transform) and approximations via parameterization and (quasi-) linearization
  4. The meta-algorithms enable us to plug-and-play (or plug-and-pray) components for quantum formal verification.

Additional Formal Verification Techniques for Quantum Robots (4)

- Use Quantum Model Order Reduction for Approximation:
  1. Quantum Model Order Reduction approximates components of quantum robots as continuous-time dynamical systems.
  2. Reference: [1] Viamontes, G. F., Markov, I. L., and Hayes, J. P. Quantum Circuit Simulation. Springer Science+Business Media, B.V., Dordrecht, The Netherlands, 2009.