

# Title of Bachelor thesis

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vorgelegt von

Felix Soest  
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Institut für Theoretische Physik  
Fakultät Physik  
Bereich Mathematik und Naturwissenschaften  
Technische Universität Dresden  
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1. Gutachter: Prof. Dr. Walter Strunz
2. Gutachter: Associate Professor Oscar Dahlsten, Ph.D.

## Summary

Abstract

English:

Aufmerksamkeit große Fragen? unsere Frage unsere Antwort

Abstract

Deutsch



# Contents

<b>1</b>	<b>Introduction</b>	<b>1</b>
1.1	Intro . . . . .	2
<b>2</b>	<b>Background</b>	<b>3</b>
2.1	Supervised Machine Learning . . . . .	3
2.2	Setting . . . . .	4
<b>3</b>	<b>Experimental Results</b>	<b>7</b>
<b>4</b>	<b>Summary and Outlook</b>	<b>9</b>
<b>5</b>	<b>Bibliography</b>	<b>11</b>



# 1 Introduction

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## 1.1 Intro

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## 2 Background

### 2.1 Supervised Machine Learning

Machine learning is a subfield of artificial intelligence, ‘concerned with the question of how to construct computer programs that automatically improve with experience.’ [5] Supervised machine learning is one of the three machine learning disciplines, besides unsupervised and reinforcement learning. The goal is to find a mapping between an input and an output, in our case an excitation and its respective optimal harvesting policy. Multiple algorithms to find such a mapping exist, however for high dimensional problems artificial neural networks (ANN) are usually used.

The setup is as follows: let  $\mathfrak{N}$  be a feedforward ANN with  $L$  layers,  $\mathfrak{N} : \mathbb{R}^{n_1} \rightarrow \mathbb{R}^{n_L}$ , where  $n_1$  and  $n_L$  denote the dimensionality of the input and output respectively. The network architecture is given by the amount of neurons  $n_l$  in each hidden layer  $l \in [2, L - 1]$ . The neurons in layer  $l$  are represented by their activations  $\vec{a}_l \in \mathbb{R}^{n_l}$ . Additionally each layer includes trainable parameters  $W_l \in \mathbb{R}^{n_{l+1} \times n_l}$  and  $\vec{b}_l \in \mathbb{R}^{n_l}$  called weights and biases. The activations can then be calculated using the following formulae [8]:

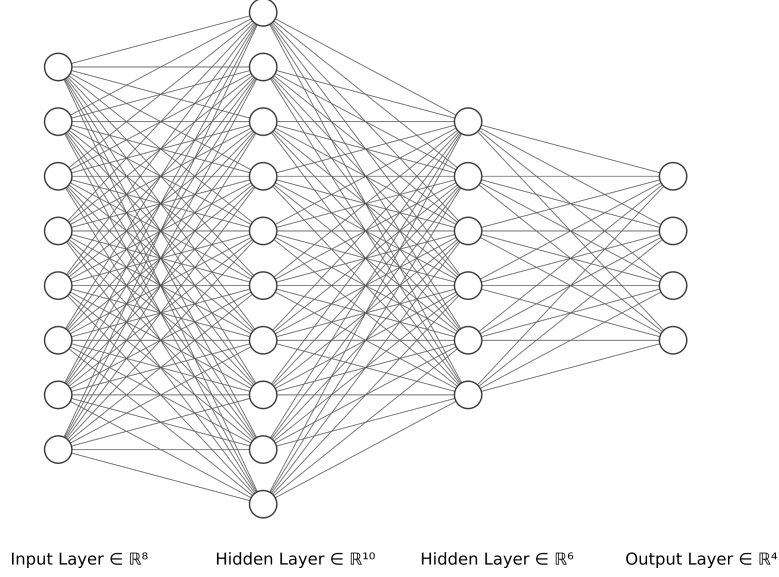
$$\begin{aligned}\vec{a}_2 &= W_1 \vec{a}_1 + \vec{b}_1, \\ \vec{a}_l &= \xi(W_{l-1} \vec{a}_{l-1} + \vec{b}_{l-1}), \quad l \in [2, L - 1],\end{aligned}$$

where  $\xi(x)$  is an activation function applied element wise. Historically, functions such as *tanh* and sigmoid have been used. However, it has been shown [4] that the rectified linear unit  $\text{ReLU}(x) = \max(0, x)$  often provides better results and is used here.

To train an ANN a cost function is defined, often the mean squared error

$$\text{MSE} = \frac{1}{N} \sum_{i=1}^N (\vec{a}_{L,i} - \vec{y}_i)^2,$$

where the summation is performed over the training data  $\{(\vec{x}_i, \vec{y}_i)\}$  and  $\vec{a}_{L,i} = \mathfrak{N}(\vec{x}_i)$  is the output of the neural network. The backpropagation algorithm is used to calculate the gradient of the cost function with respect to the trainable parameters and improve the performance of the ANN [7, 6].



**Figure 2.1:** Example ANN with four layers, including input, output and two hidden layers [3]

## 2.2 Setting

Our setting consists of three qubits: the Drive, System and Transducer qubit. The Drive and Transducer qubits can be set by the experimenter in  $N$  discrete steps modelled as piecewise constant functions of  $(\theta_D, \phi_D)$  and  $(\theta_T, \phi_T)$  respectively (see figure 2.2), the system qubit is initialised in a pure state. In general, unitary evolution of a multipartite system will lead to entanglement, meaning Drive and Transducer bits are no longer pure states. This is at odds with the assumption of piecewise constant control functions. We therefore model Drive and Transducer qubits as series of ancilla qubits which interact with the system such that the state does not entangle and can afterwards be measured [1]. In the remainder of this work we use the interaction Hamiltonian on the three qubit Hilbert space

$$H_{DST} = H_I \otimes \mathbb{I} + \mathbb{I} \otimes H_I, \quad H_I = \sigma_+ \otimes \sigma_- + \sigma_- \otimes \sigma_+$$

unless otherwise noted. The time evolution and work extraction is then calculated as follows, where  $\Delta t$  is time span between qubit switching:

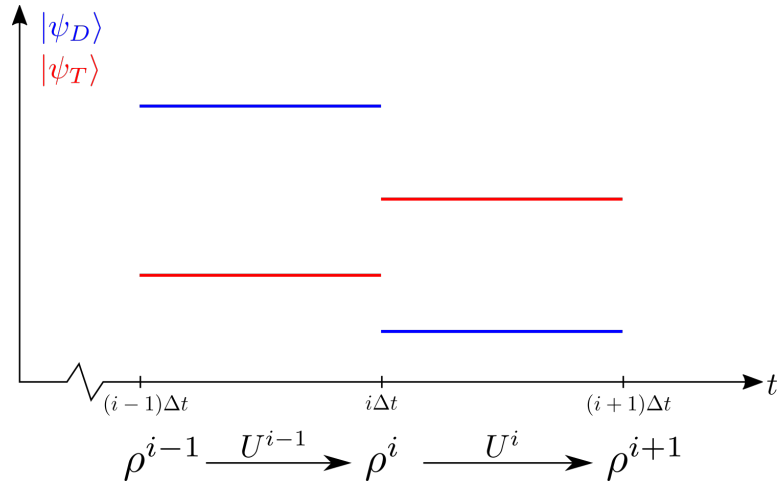
$$H_S^i = \langle \psi_D^i | \langle \psi_T^i | H_{DST} | \psi_D^i \rangle | \psi_T^i \rangle \quad (2.1)$$

$$\rho_S^{i+1} = U^i \rho_S^i U^{i\dagger}, \quad U^i = e^{-iH_S^i \Delta t} \quad (2.2)$$

$$W = -\sum_i \text{Tr} \rho_S^i dH_S^i \quad (2.3)$$

$$dH_S^i = \langle \psi_D^i | \langle \psi_T^{i+1} | H_{DST} | \psi_D^i \rangle | \psi_T^{i+1} \rangle - \langle \psi_D^i | \langle \psi_T^i | H_{DST} | \psi_D^i \rangle | \psi_T^i \rangle. \quad (2.4)$$

Here we use the partial Hamiltonian  $H_S^i$  on  $S$  at time step  $i \in [1, N-1]$ , as well as corresponding system density matrix  $\rho_S^i$ .



**Figure 2.2:** Piecewise constant implementation of Drive and Transducer qubits. The vertical axis shows qubit state in arbitrary units. The qubit states are switched instantaneously and then kept constant for  $\Delta t$  while  $\rho_S$  evolves unitarily.

## 3 Experimental Results



## 4 Summary and Outlook





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## **Erklärung**

Hiermit erkläre ich, dass ich diese Arbeit im Rahmen der Betreuung am Institut für Theoretische Physik ohne unzulässige Hilfe Dritter verfasst und alle Quellen als solche gekennzeichnet habe.

Felix Soest  
Dresden, Monat 2021