

Entanglement detection

with imprecise measurements

Simon Morelli



TECHNISCHE
UNIVERSITÄT
WIEN

Entanglement



Entanglement

A state is entangled, if it is not a convex combination of product states

$$\rho \neq \sum_i p_i \rho_A^i \otimes \rho_B^i$$

Entanglement

A state is entangled, if it is not a convex combination of product states

$$\rho \neq \sum_i p_i \rho_A^i \otimes \rho_B^i$$

An observable W is an entanglement witness, if for all separable states

$$\text{Tr}(W\sigma) \geq 0$$

Entanglement

A state is entangled, if it is not a convex combination of product states

$$\rho \neq \sum_i p_i \rho_A^i \otimes \rho_B^i$$

An observable W is an entanglement witness, if for all separable states

$$\text{Tr}(\mathcal{W}\sigma) \geq 0$$

and for some entangled states

$$\text{Tr}(\mathcal{W}\rho) < 0$$

Entanglement

A state is entangled, if it is not a convex combination of product states

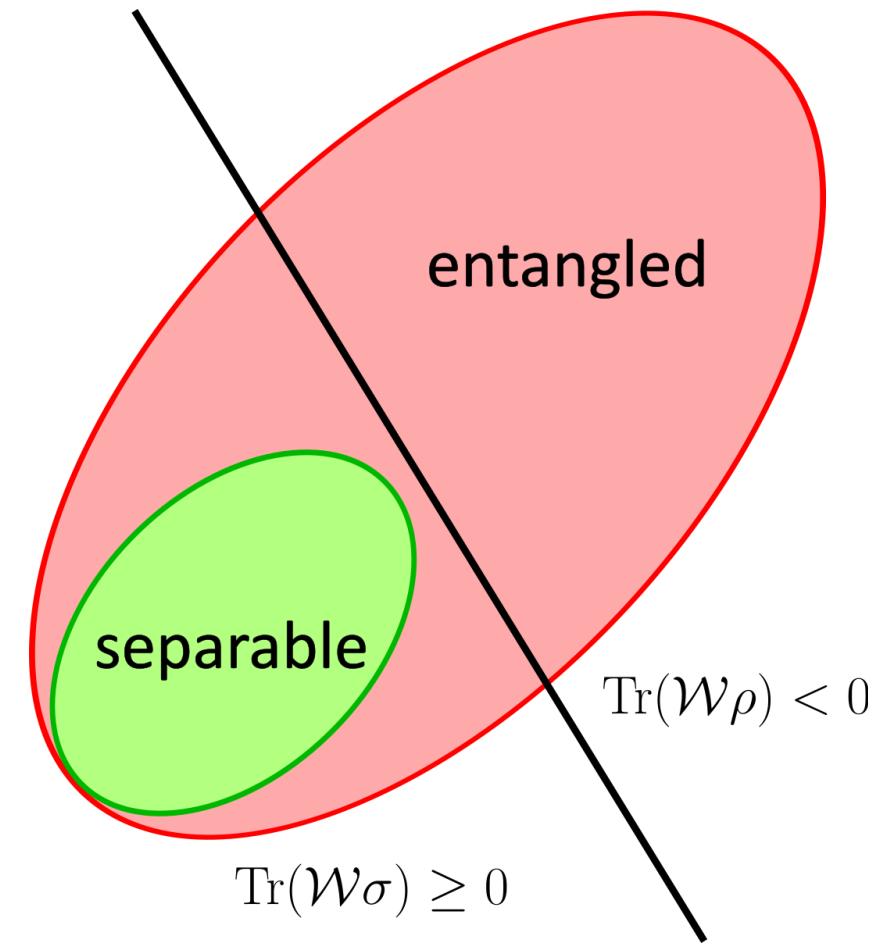
$$\rho \neq \sum_i p_i \rho_A^i \otimes \rho_B^i$$

An observable W is an entanglement witness, if for all separable states

$$\text{Tr}(\mathcal{W}\sigma) \geq 0$$

and for some entangled states

$$\text{Tr}(\mathcal{W}\rho) < 0$$



Entanglement detection (ED)



Entanglement detection (ED)

$$\text{Tr}(\mathcal{W} \rho) = \sum_{x,y} p_{xy} \text{Tr}(A_x \otimes B_y \rho)$$

Entanglement detection (ED)

$$\text{Tr}(\mathcal{W} \rho) = \sum_{x,y} p_{xy} \text{Tr}(A_x \otimes B_y \rho)$$

$$\xleftarrow{\hspace{1cm}} \rho \xrightarrow{\hspace{1cm}}$$

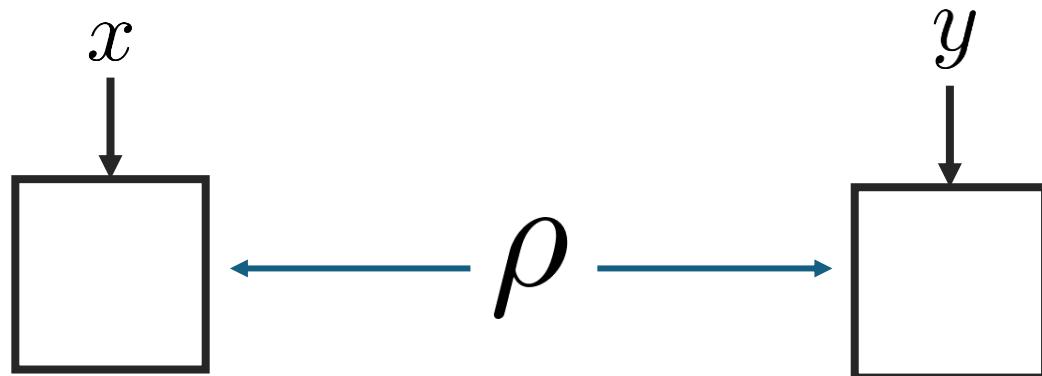
Entanglement detection (ED)

$$\mathrm{Tr}(\mathcal{W} \rho) = \sum_{x,y} p_{xy} \mathrm{Tr}(A_x \otimes B_y \rho)$$



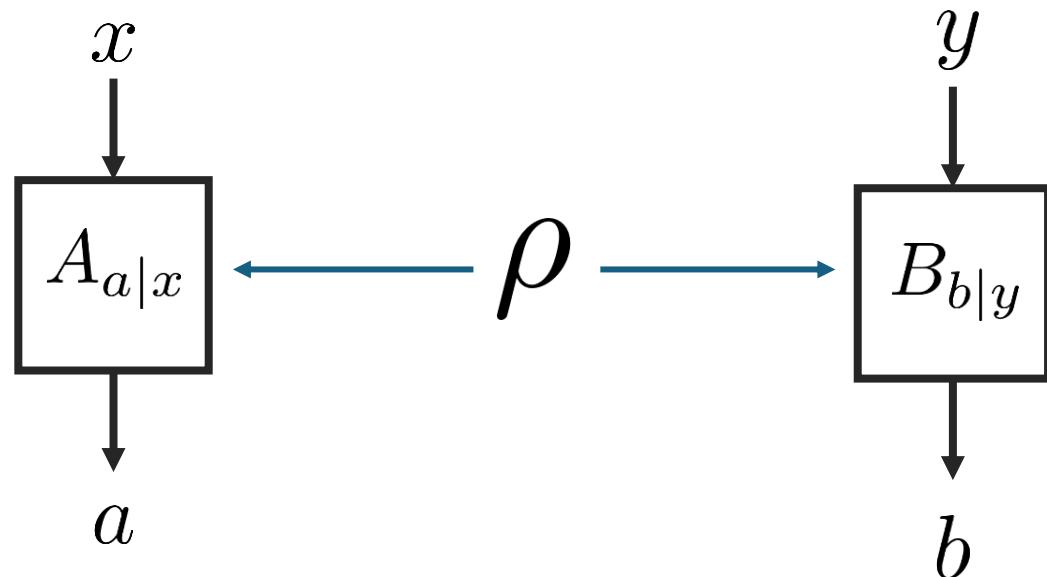
Entanglement detection (ED)

$$\text{Tr}(\mathcal{W} \rho) = \sum_{x,y} p_{xy} \text{Tr}(A_x \otimes B_y \rho)$$



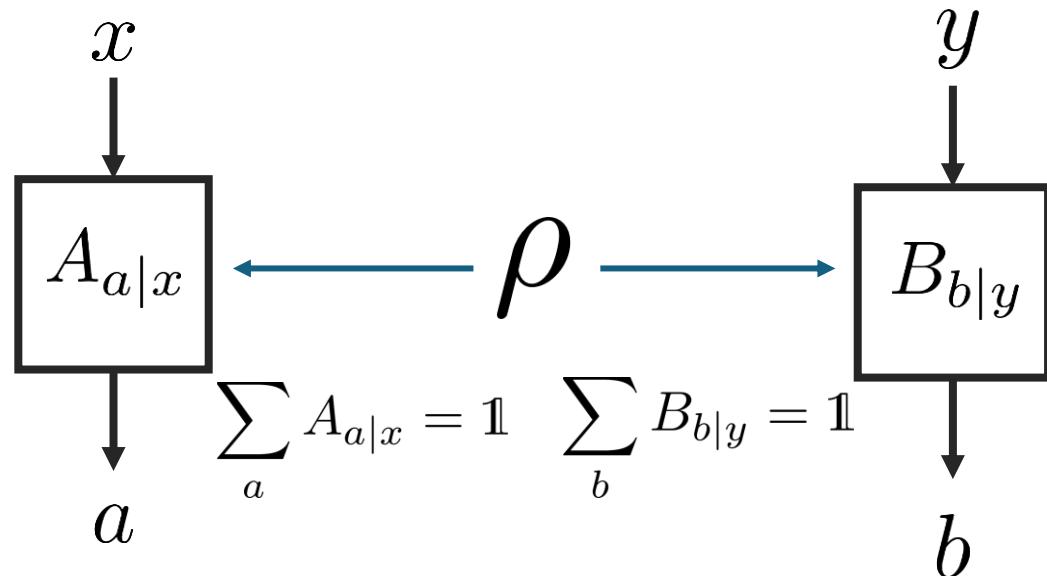
Entanglement detection (ED)

$$\text{Tr}(\mathcal{W} \rho) = \sum_{x,y} p_{xy} \text{Tr}(A_x \otimes B_y \rho)$$



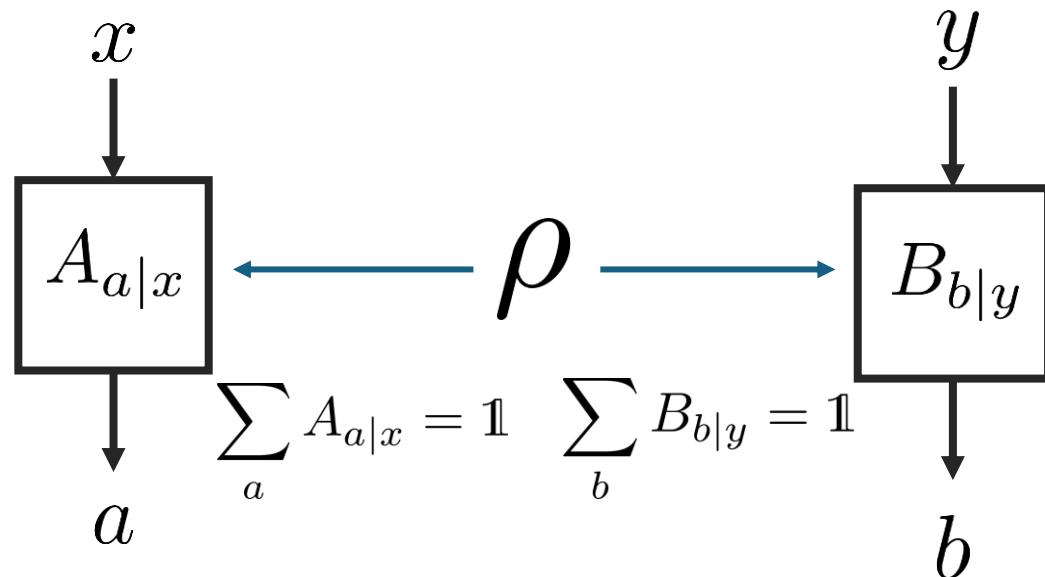
Entanglement detection (ED)

$$\text{Tr}(\mathcal{W} \rho) = \sum_{x,y} p_{xy} \text{Tr}(A_x \otimes B_y \rho)$$



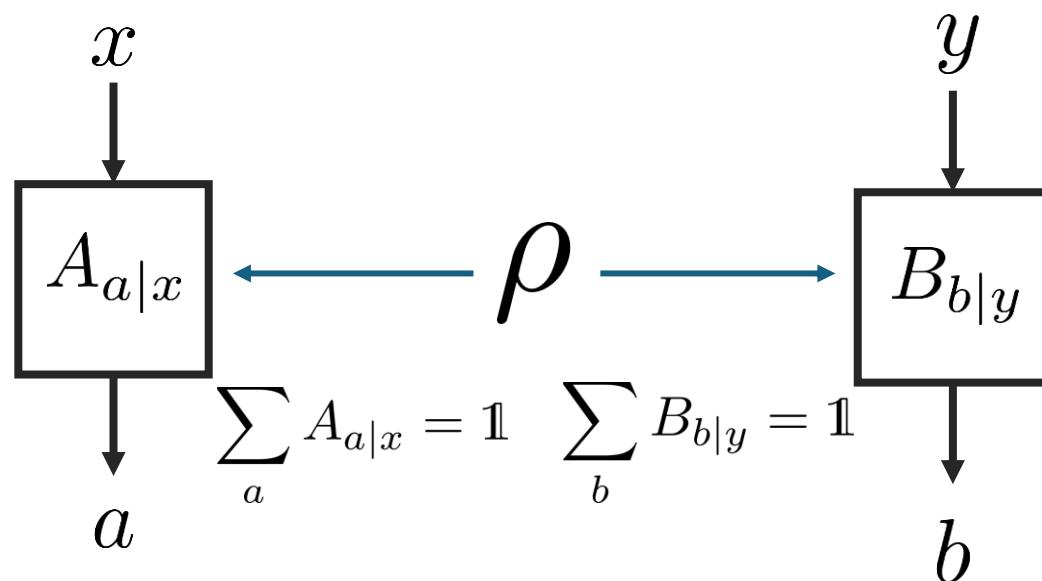
Entanglement detection (ED)

$$p(ab|xy) = \text{Tr}(A_{a|x} \otimes B_{b|y} \rho)$$



Entanglement detection (ED)

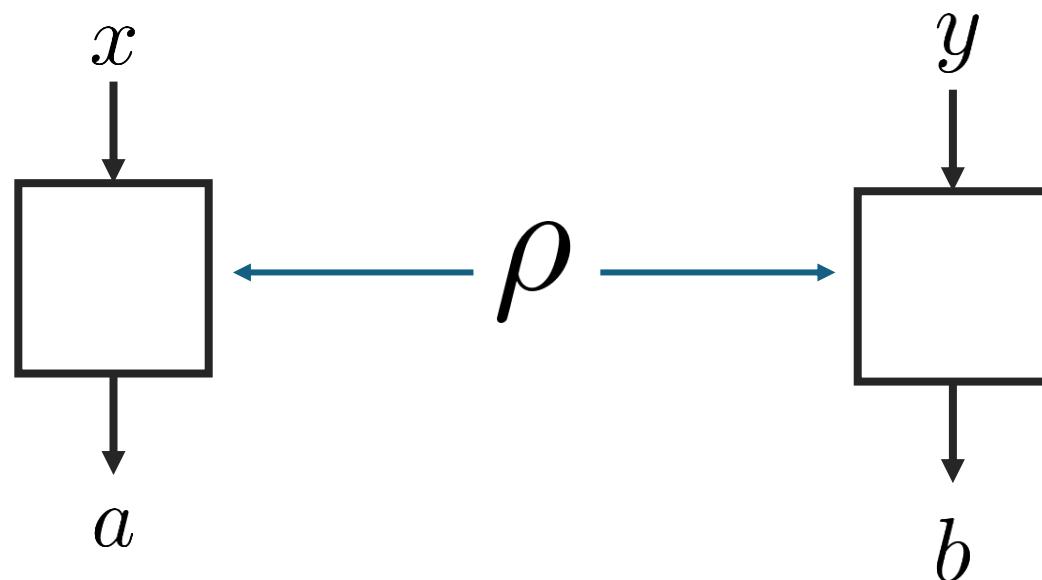
$$p(ab|xy) = \text{Tr}(A_{a|x} \otimes B_{b|y} \rho)$$



detect entanglement
 if all states generating the
 outcome statistic for the
performed measurements
 are entangled

Entanglement detection (ED)

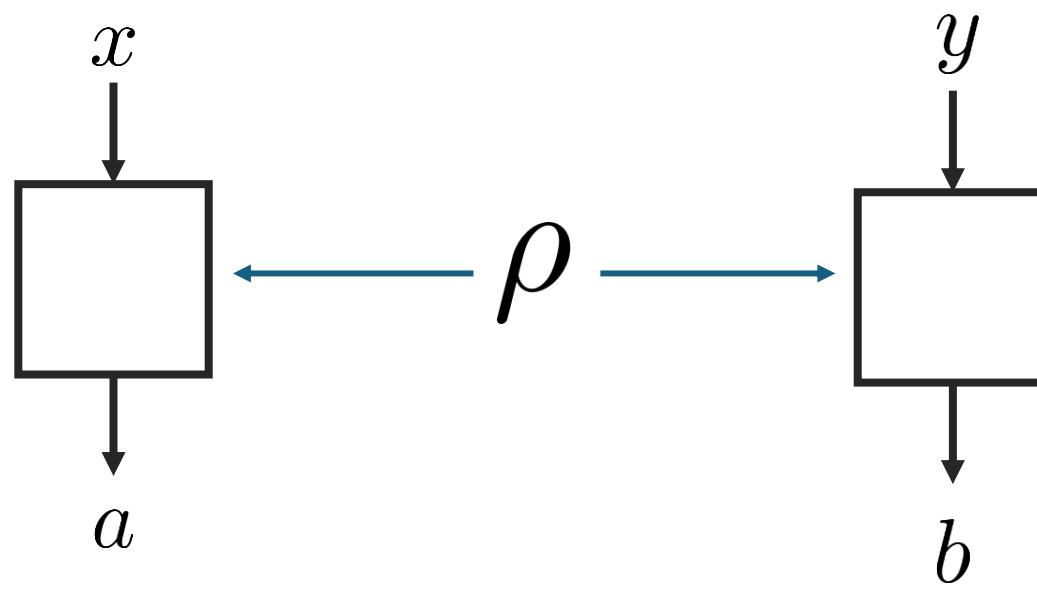
$$p(ab|xy) = \text{Tr}(A_{a|x} \otimes B_{b|y} \rho)$$



detect entanglement
if all states generating the
outcome statistic for the
performed measurements
are entangled

Entanglement detection (ED)

$$p(ab|xy) = \text{Tr}(A_{a|x} \otimes B_{b|y} \rho)$$



detect entanglement

if all states generating the outcome statistic for the performed measurements are entangled

observe nonlocality

if all states generating the outcome statistic with any arbitrary measurements are entangled

ED with bounded distrust



ED with bounded distrust

Operational notion of
measurement inaccuracy

ED with bounded distrust

Operational notion of
measurement inaccuracy

$$\mathcal{F}_x^A = \frac{1}{d} \sum_{a=1}^d \text{Tr}(A_{a|x} A_{a|x}^\varepsilon) \geq 1 - \varepsilon_x^A$$

ED with bounded distrust

Operational notion of
measurement inaccuracy

$$\mathcal{F}_x^A = \frac{1}{d} \sum_{a=1}^d \text{Tr}(A_{a|x} A_{a|x}^\varepsilon) \geq 1 - \varepsilon_x^A$$

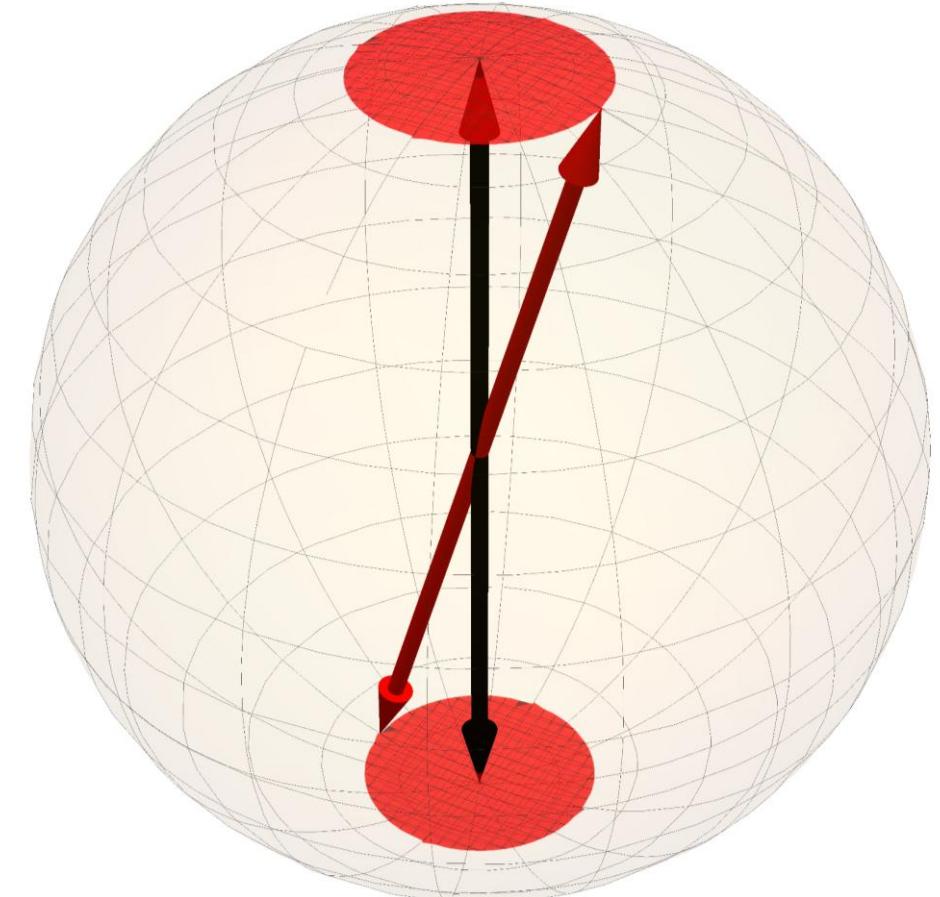
$$\mathcal{F}_y^B = \frac{1}{d} \sum_{b=1}^d \text{Tr}(B_{b|y} B_{b|y}^\varepsilon) \geq 1 - \varepsilon_y^B$$

ED with bounded distrust

Operational notion of
measurement inaccuracy

$$\mathcal{F}_x^A = \frac{1}{d} \sum_{a=1}^d \text{Tr}(A_{a|x} A_{a|x}^\varepsilon) \geq 1 - \varepsilon_x^A$$

$$\mathcal{F}_y^B = \frac{1}{d} \sum_{b=1}^d \text{Tr}(B_{b|y} B_{b|y}^\varepsilon) \geq 1 - \varepsilon_y^B$$



Tuning measurement inaccuracy



Tuning measurement inaccuracy



Entanglement detection

Tuning measurement inaccuracy

Entanglement detection

$$\mathcal{W}^{(2)} = X \otimes X + Z \otimes Z$$

Tuning measurement inaccuracy

Entanglement detection

$$\mathcal{W}^{(2)} = X \otimes X + Z \otimes Z$$

$$\langle \mathcal{W}^{(2)} \rangle_{\rho_{\text{sep}}} \leq 1 = \mathcal{B}_{\text{sep}}$$

Tuning measurement inaccuracy

Entanglement detection

$$\mathcal{W}^{(2)} = X \otimes X + Z \otimes Z$$

$$\langle \mathcal{W}^{(2)} \rangle_{\rho_{\text{sep}}} \leq 1 = \mathcal{B}_{\text{sep}}$$

ED with bounded distrust

Tuning measurement inaccuracy

Entanglement detection

$$\mathcal{W}^{(2)} = X \otimes X + Z \otimes Z$$

$$\langle \mathcal{W}^{(2)} \rangle_{\rho_{\text{sep}}} \leq 1 = \mathcal{B}_{\text{sep}}$$

ED with bounded distrust

$$\mathcal{W}_\varepsilon^{(2)} = A_x^\varepsilon \otimes B_x^\varepsilon + A_z^\varepsilon \otimes B_z^\varepsilon$$

Tuning measurement inaccuracy

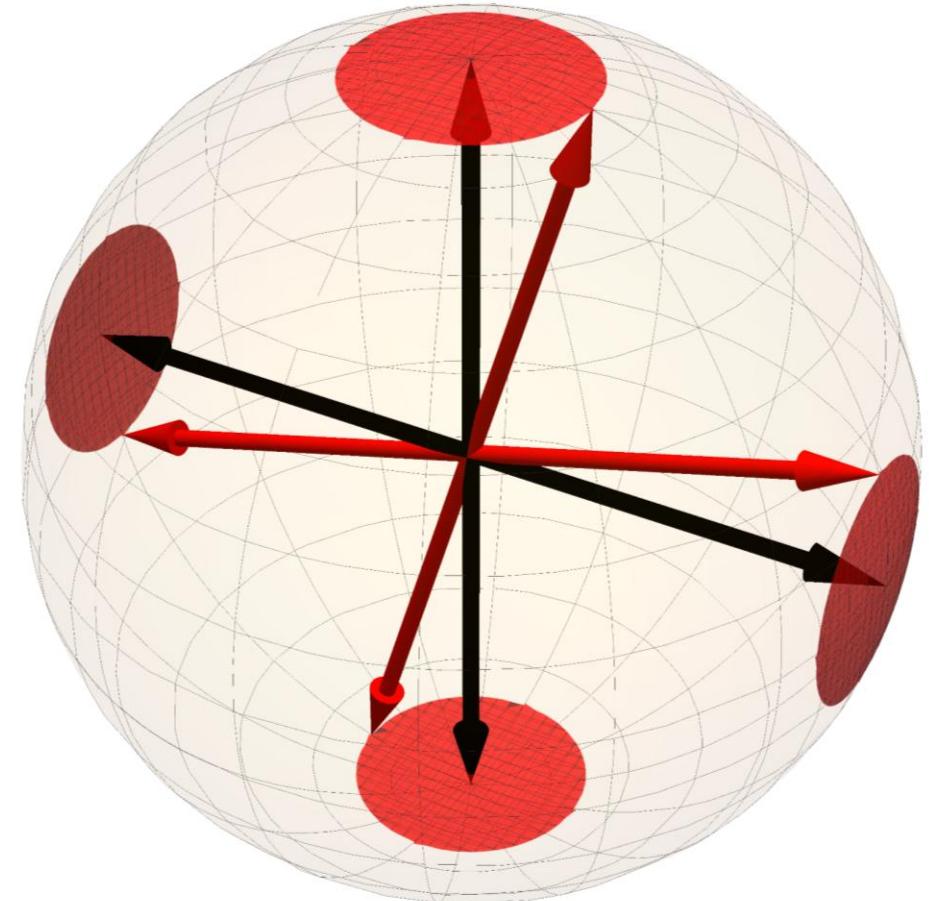
Entanglement detection

$$\mathcal{W}^{(2)} = X \otimes X + Z \otimes Z$$

$$\langle \mathcal{W}^{(2)} \rangle_{\rho_{\text{sep}}} \leq 1 = \mathcal{B}_{\text{sep}}$$

ED with bounded distrust

$$\mathcal{W}_\varepsilon^{(2)} = A_x^\varepsilon \otimes B_x^\varepsilon + A_z^\varepsilon \otimes B_z^\varepsilon$$



Tuning measurement inaccuracy

Entanglement detection

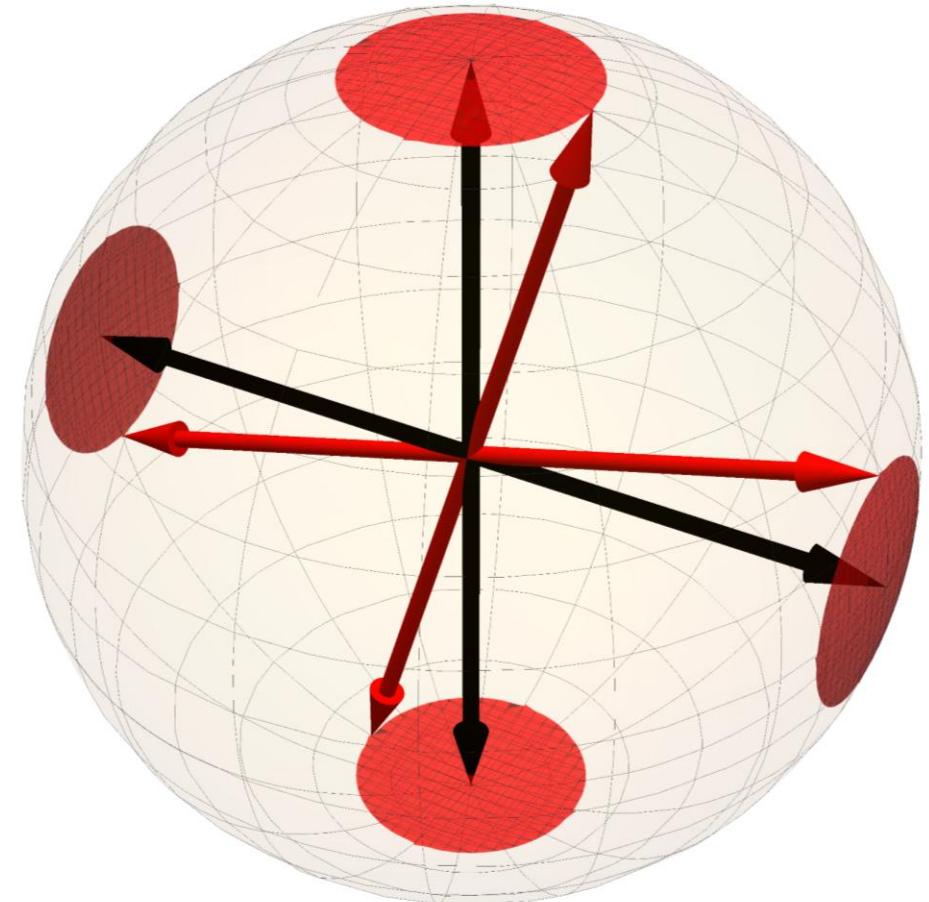
$$\mathcal{W}^{(2)} = X \otimes X + Z \otimes Z$$

$$\langle \mathcal{W}^{(2)} \rangle_{\rho_{\text{sep}}} \leq 1 = \mathcal{B}_{\text{sep}}$$

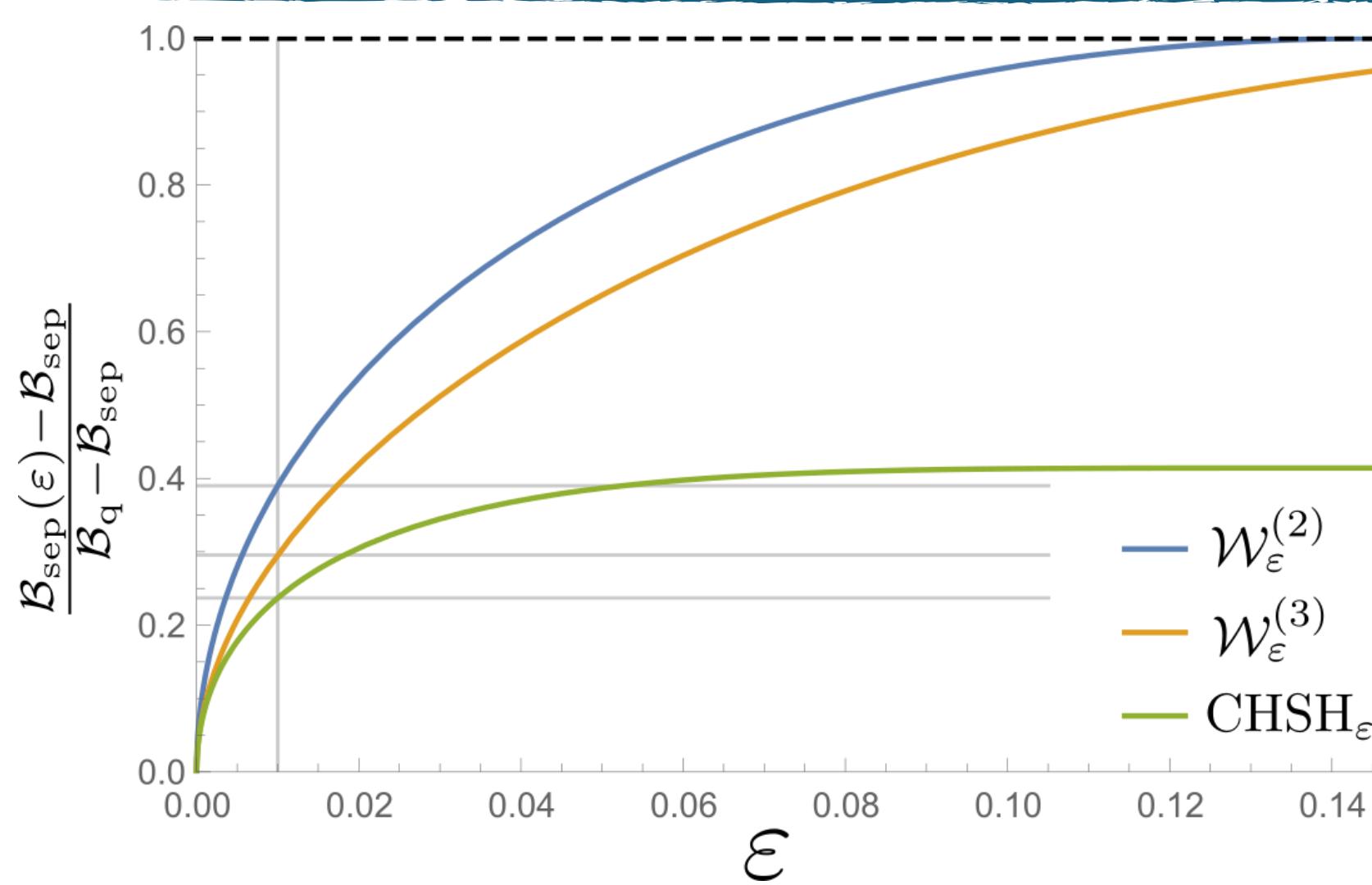
ED with bounded distrust

$$\mathcal{W}_{\varepsilon}^{(2)} = A_x^{\varepsilon} \otimes B_x^{\varepsilon} + A_z^{\varepsilon} \otimes B_z^{\varepsilon}$$

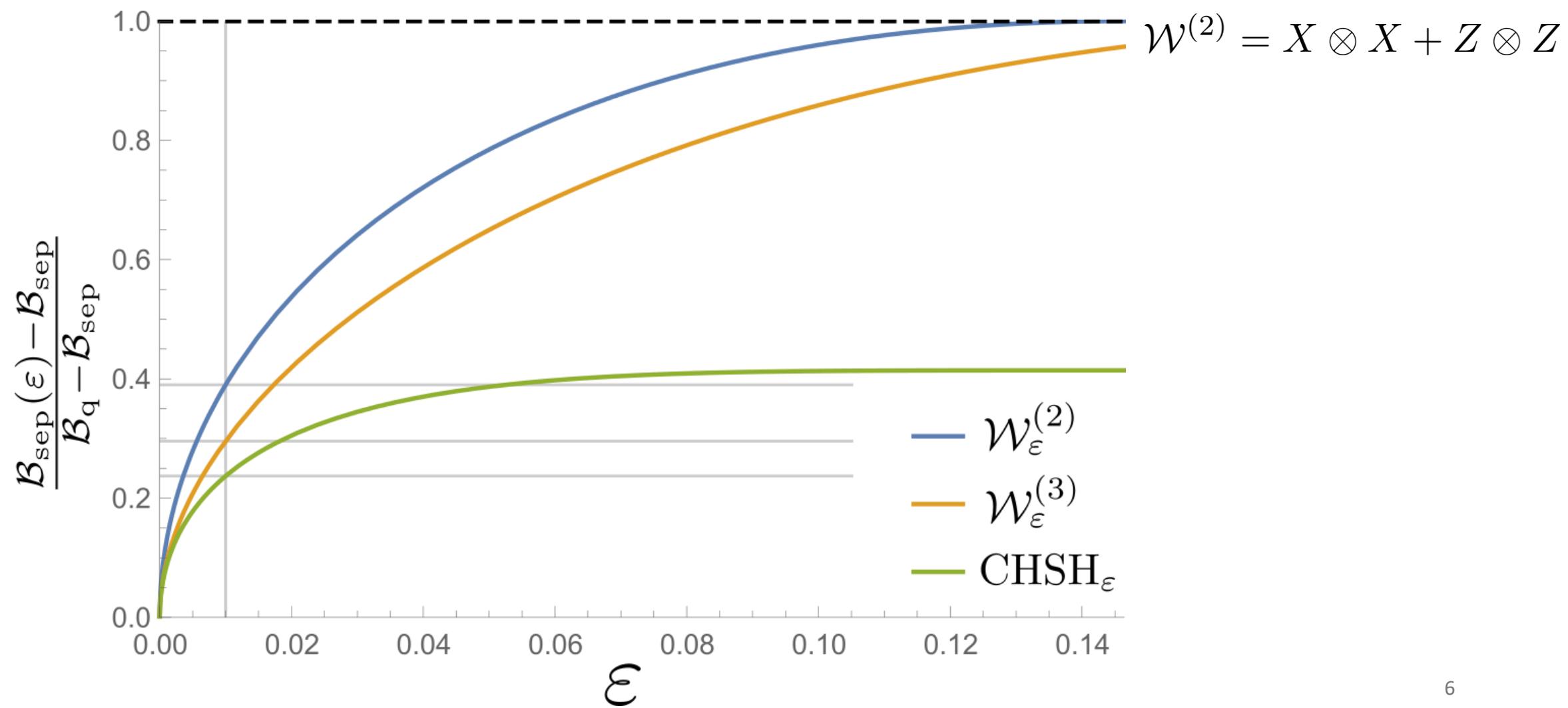
$$\begin{aligned} \langle \mathcal{W}_{\varepsilon}^{(2)} \rangle_{\rho_{\text{sep}}} &\leq 1 + 4(1 - 2\varepsilon)\sqrt{\varepsilon(1 - \varepsilon)} \\ &= \mathcal{B}_{\text{sep}}(\varepsilon) \end{aligned}$$



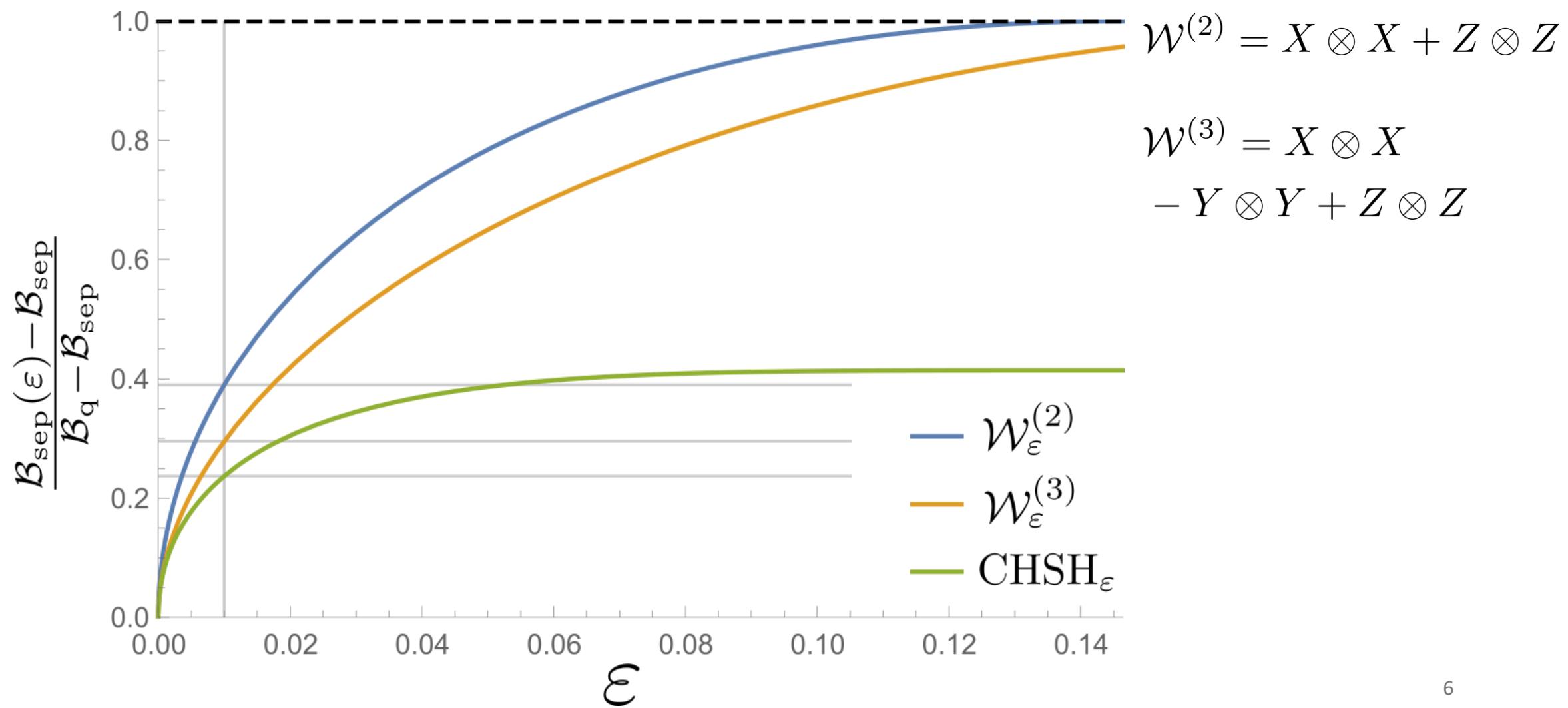
Impact of inaccuracies



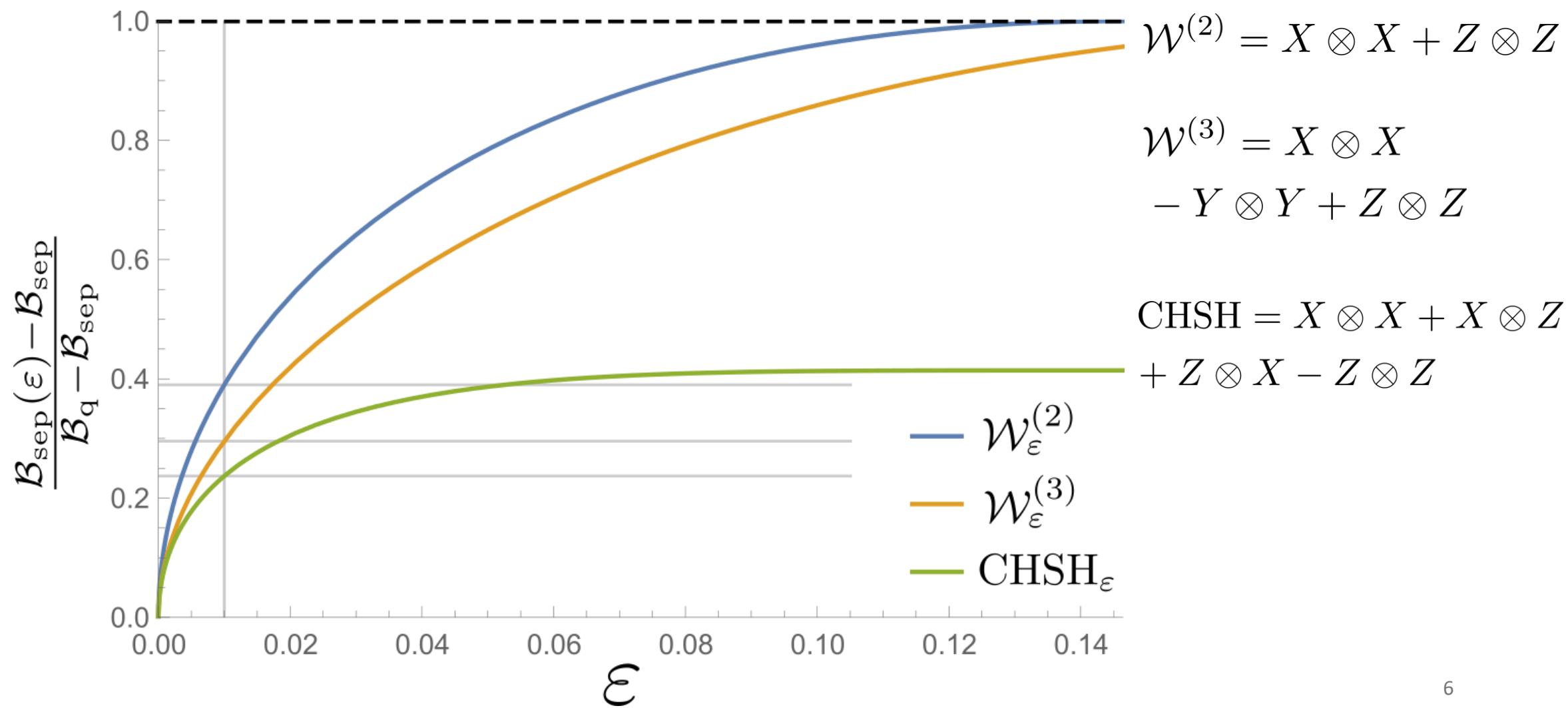
Impact of inaccuracies



Impact of inaccuracies



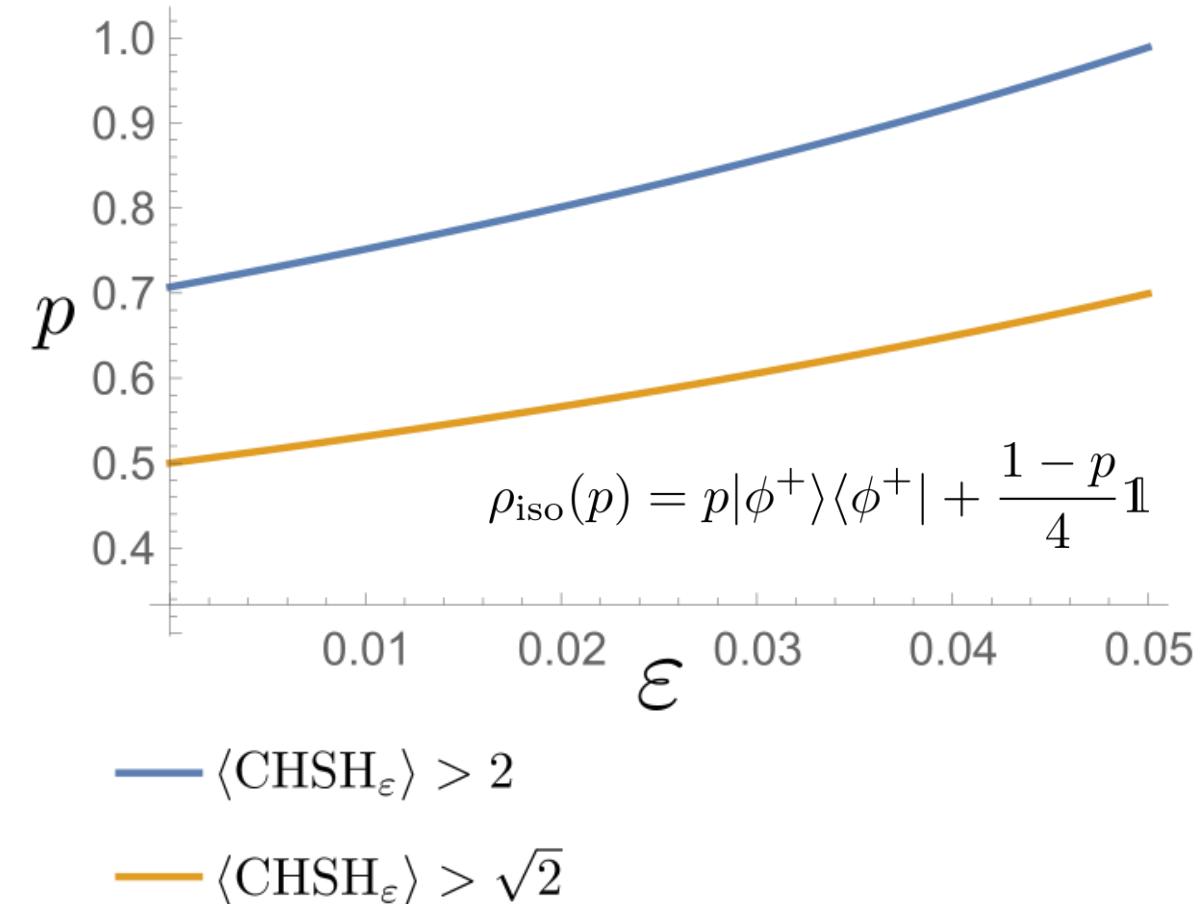
Impact of inaccuracies



Advantages of ED with inaccuracies

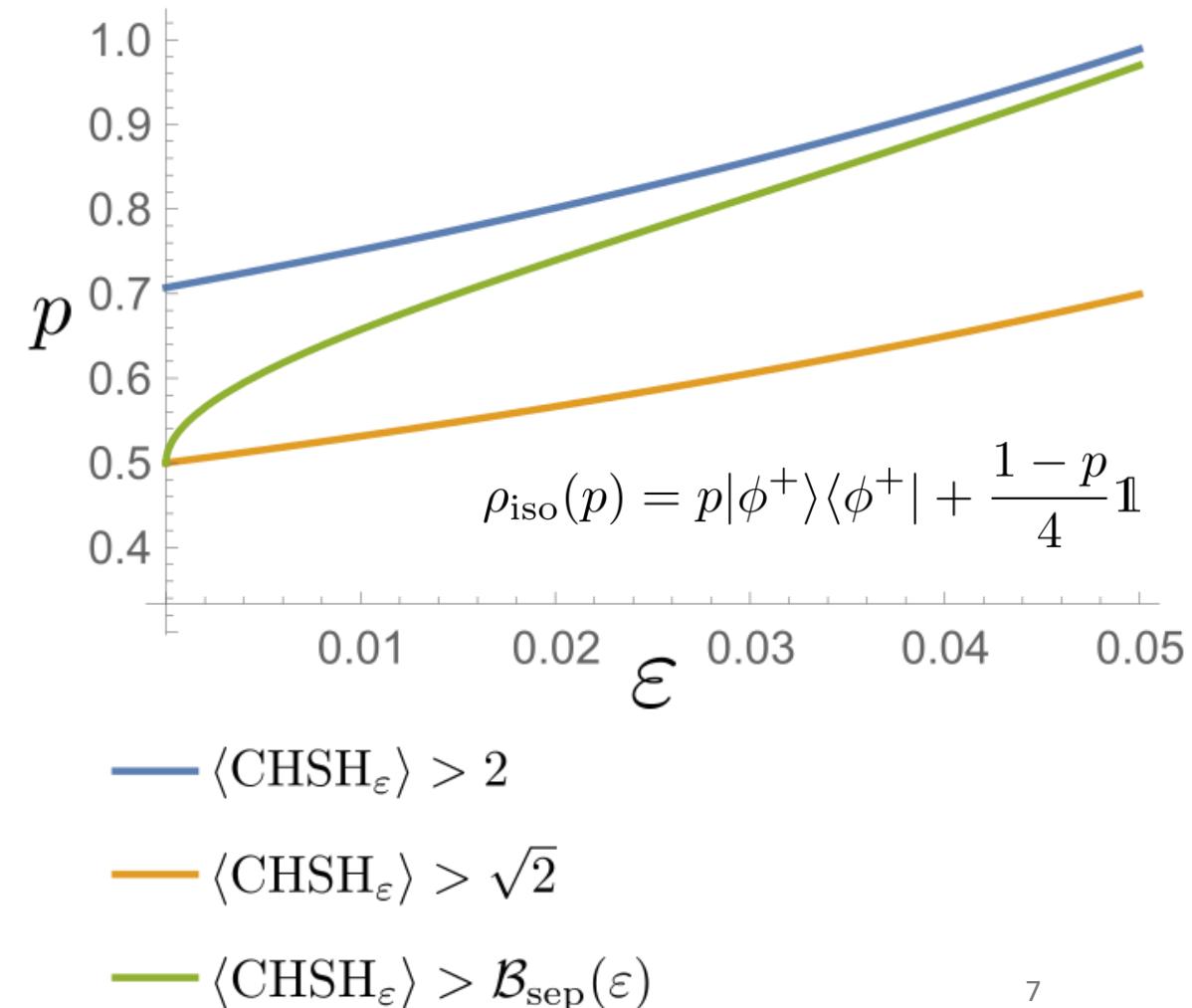


Advantages of ED with inaccuracies



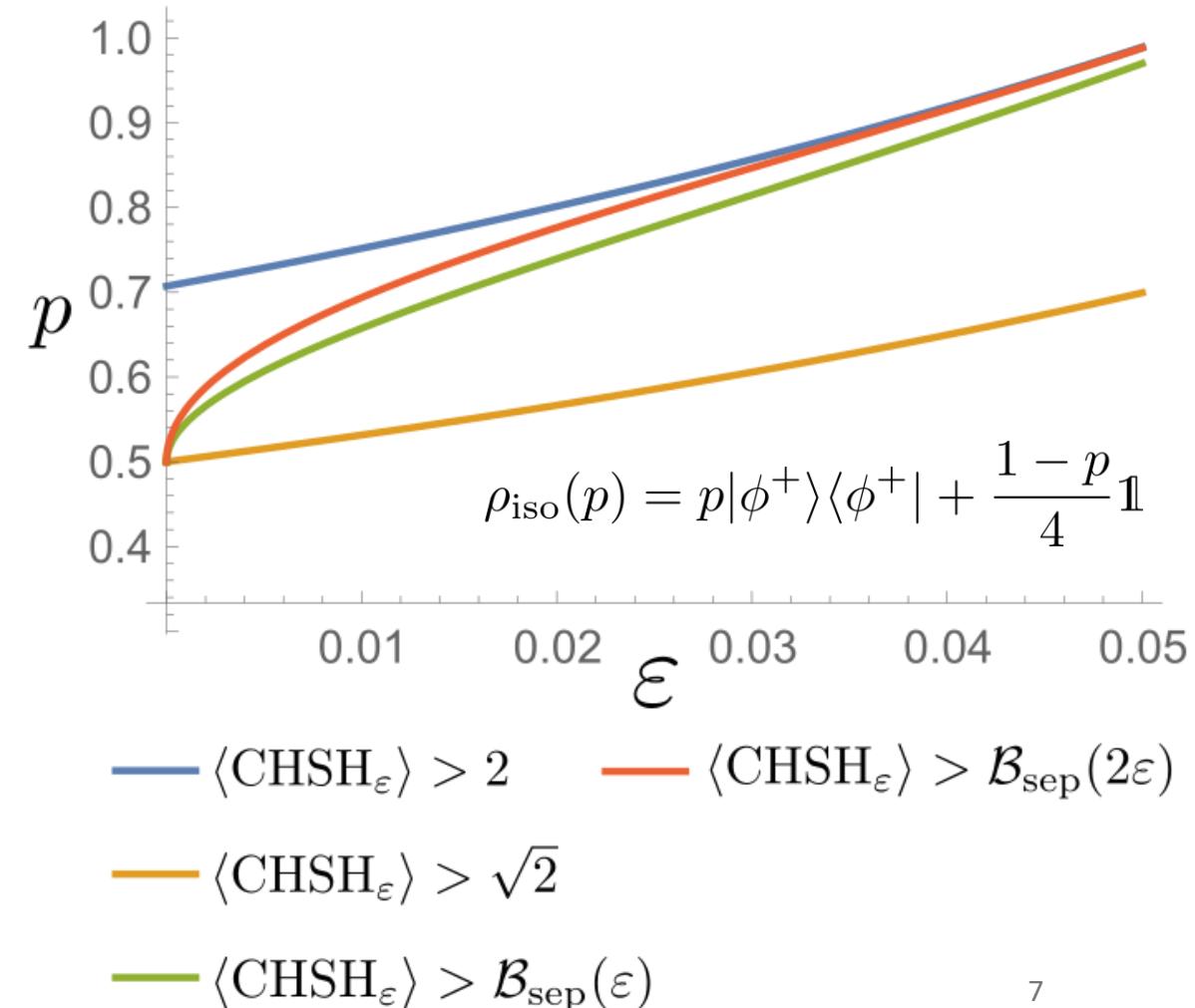
Advantages of ED with inaccuracies

- Account for inaccuracies using information on the measurements



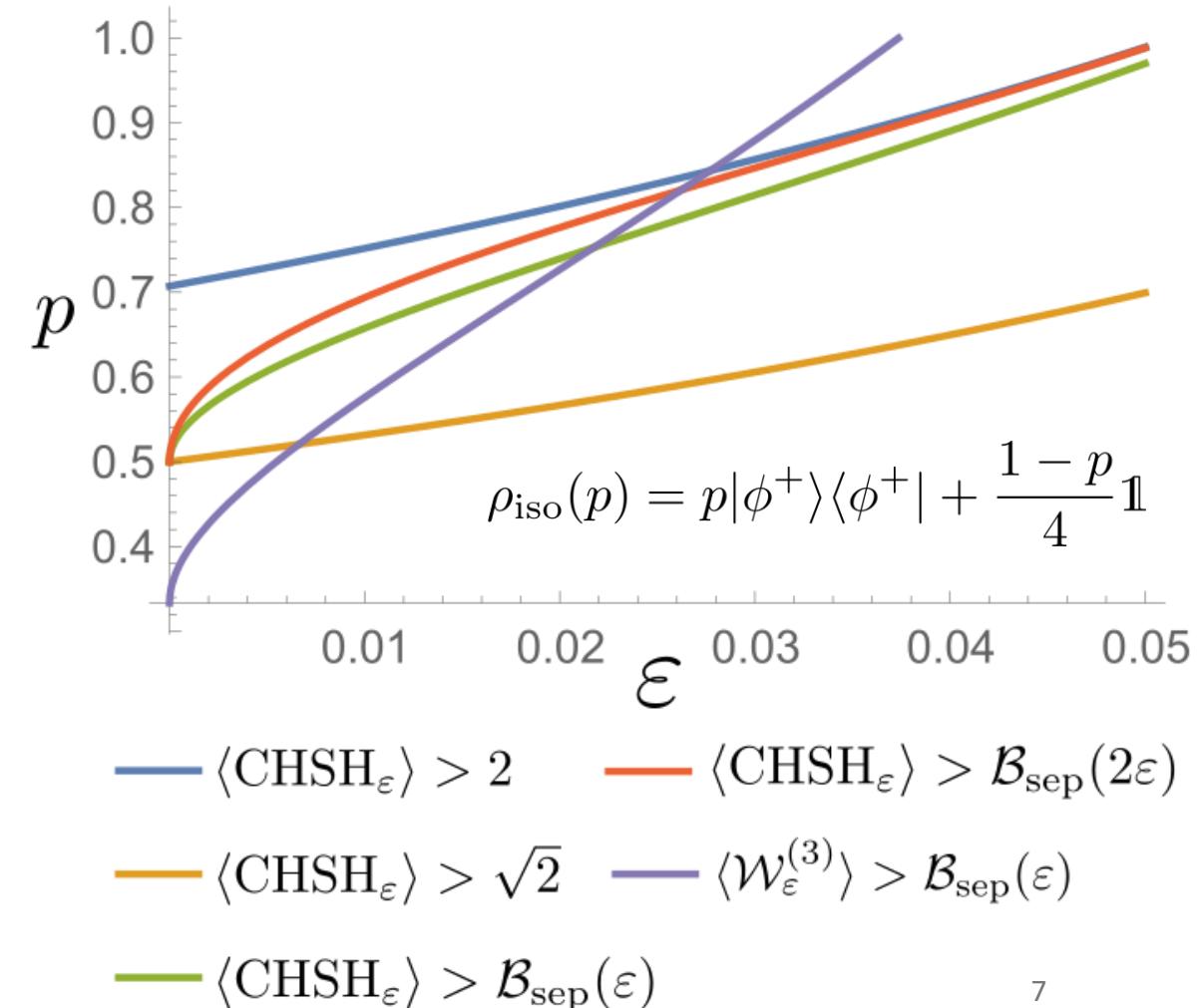
Advantages of ED with inaccuracies

- Account for inaccuracies using information on the measurements
- Choose the level of trust in the set-up



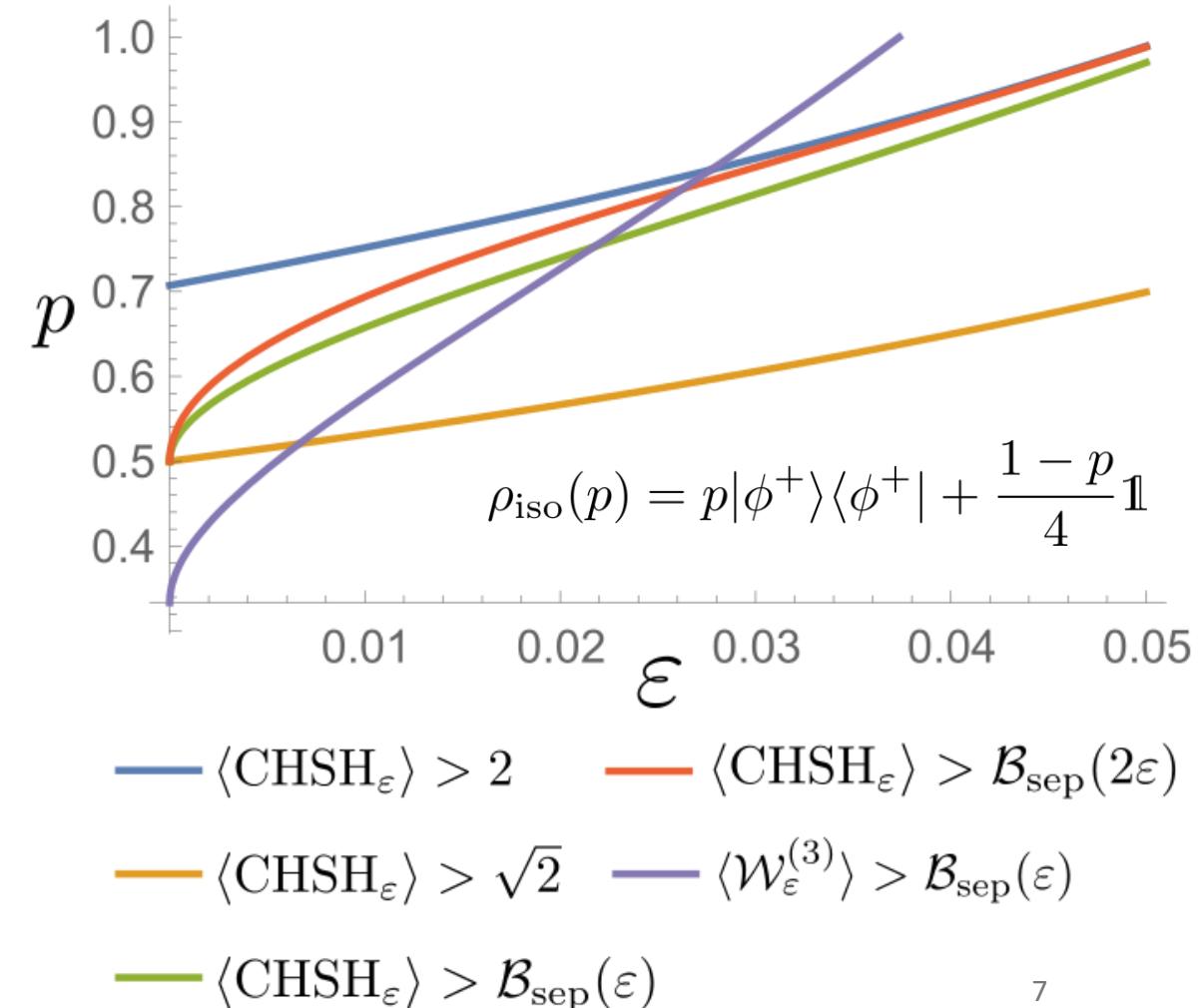
Advantages of ED with inaccuracies

- Account for inaccuracies using information on the measurements
- Choose the level of trust in the set-up
- Known witnesses can be used



Advantages of ED with inaccuracies

- Account for inaccuracies using information on the measurements
- Choose the level of trust in the set-up
- Known witnesses can be used
- Generalization to higher dimensions and more parties



Multipartite ED



Multipartite ED

Mermin witness

$$\mathcal{M}^{(n)} = \frac{1}{2} \left(\bigotimes_{j=1}^n (X + iY) + \bigotimes_{j=1}^n (X - iY) \right)$$

Multipartite ED

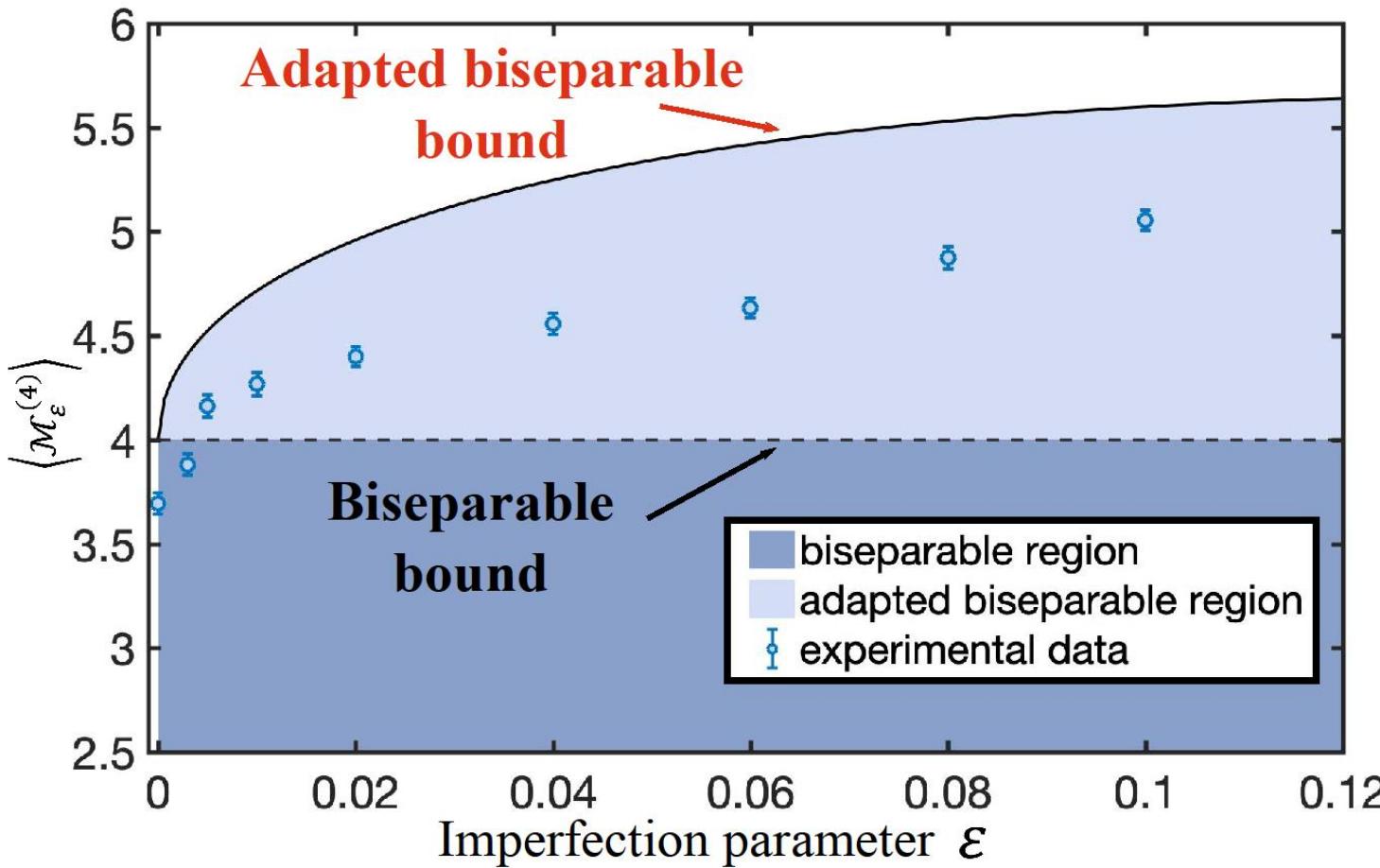
Mermin witness

$$\mathcal{M}^{(n)} = \frac{1}{2} \left(\bigotimes_{j=1}^n (X + iY) + \bigotimes_{j=1}^n (X - iY) \right)$$

has the biseparable bound

$$\langle \mathcal{M}_\varepsilon^{(n)} \rangle_{\rho_{\text{bisepl}}} \leq 2^{n-2} \left(1 - 2\varepsilon + 2\sqrt{\varepsilon(1-\varepsilon)} \right)$$

Multipartite ED



Mermin witness

$$\mathcal{M}^{(n)} = \frac{1}{2} \left(\bigotimes_{j=1}^n (X + iY) + \bigotimes_{j=1}^n (X - iY) \right)$$

has the biseparable bound

$$\langle \mathcal{M}_\varepsilon^{(n)} \rangle_{\rho_{\text{bisepl}}} \leq 2^{n-2} \left(1 - 2\varepsilon + 2\sqrt{\varepsilon(1-\varepsilon)} \right)$$

High-dimensional ED

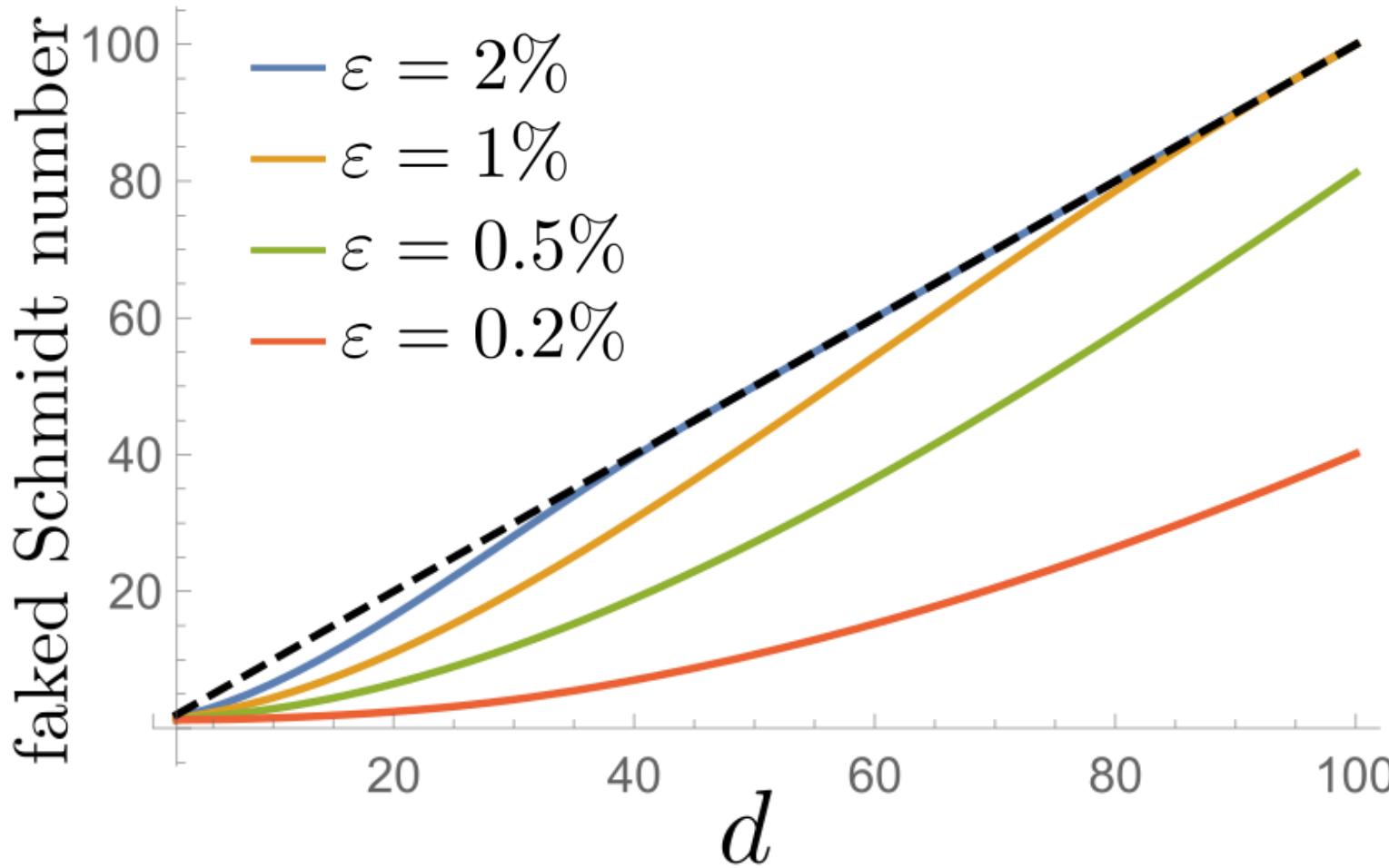


High-dimensional ED

Measuring m mutually unbiased bases, states of Schmidt number r satisfy

$$\sum_{l=1}^m \sum_{i=0}^{d-1} \langle e_i^{(l)} (e_i^{(l)})^* | \rho | e_i^{(l)} (e_i^{(l)})^* \rangle \leq 1 + \frac{(m-1)r}{d}$$

High-dimensional ED



Measuring m mutually unbiased bases, states of Schmidt number r satisfy

$$\sum_{l=1}^m \sum_{i=0}^{d-1} \langle e_i^{(l)} (e_i^{(l)})^* | \rho | e_i^{(l)} (e_i^{(l)})^* \rangle \leq 1 + \frac{(m-1)r}{d}$$

Summary



Summary

- Perfect measurements are an unrealistic idealization

Summary

- Perfect measurements are an unrealistic idealization
- Operational definition of measurement inaccuracy

Summary

- Perfect measurements are an unrealistic idealization
- Operational definition of measurement inaccuracy
- Imprecisions can highly impact the validity of witnesses

Summary

- Perfect measurements are an unrealistic idealization
- Operational definition of measurement inaccuracy
- Imprecisions can highly impact the validity of witnesses
- Adjust separable bounds to the inaccuracy

Summary

- Perfect measurements are an unrealistic idealization
- Operational definition of measurement inaccuracy
- Imprecisions can highly impact the validity of witnesses
- Adjust separable bounds to the inaccuracy
- Extend to multiple parties and higher dimensions



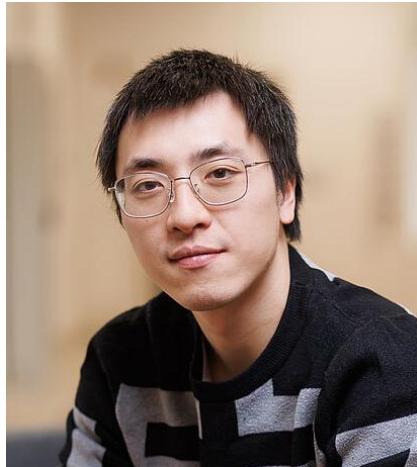
Armin
Tavakoli



Hayata
Yamasaki



Marcus
Huber



Huan Cao
& Philip
Walther
group



Robert
Fickler
& team

Thank you!