

MCA 2021

Congreso Matemático de las Américas
12-23 Julio

Mathematical Congress of the Americas
12-23 July

Buenos Aires Argentina

Symbolic vs Numerical: Allies or Enemies?

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& Josué Tonelli-Cueto (Inria Paris/IMJ-PRG)

Sesión especial / Special Session
*Symbolic and Numerical Computation
with Polynomials*

Miércoles / Wednesday 14, 13:00-16:00

Viernes / Friday 16, 11:00-16:00

Miércoles / Wednesday 21, 16:00-21:00

POLYNOMIALS EVERYWHERE I

Polynomials are used for modelling many phenomena:

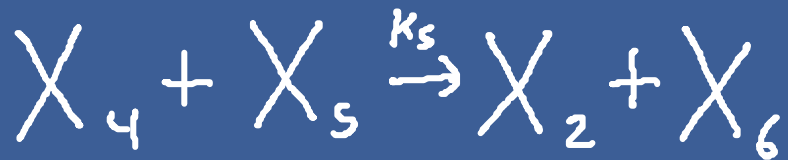
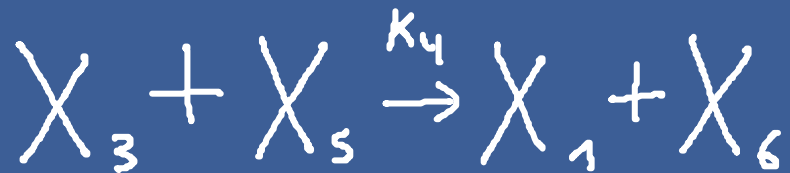
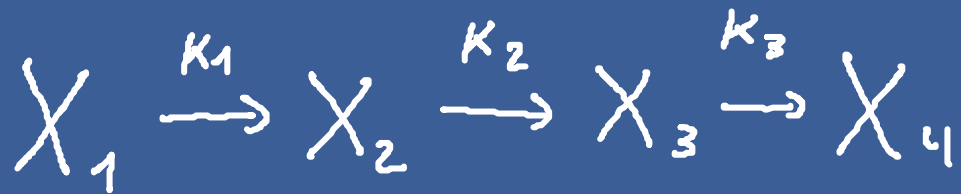
applied

&

theoretical

EXAMPLE 1: CHEMICAL REACTION NETWORKS

Two-component system
with hybrid histidine kinase

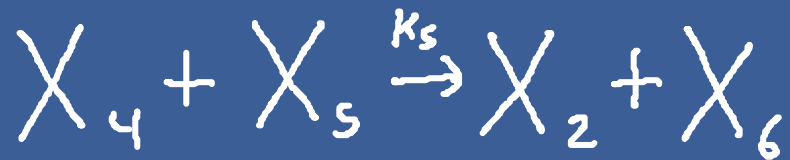
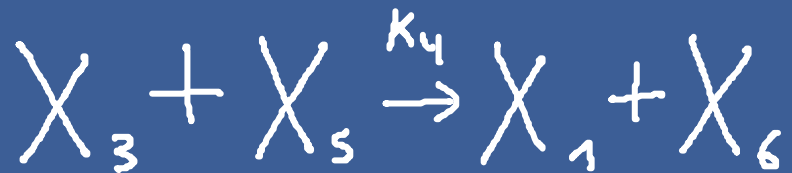
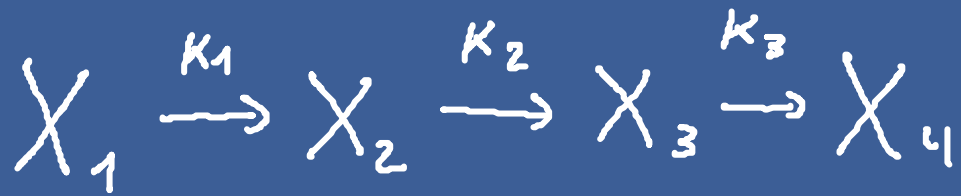


ODE of concentrations

$$\begin{cases} \dot{X}_1 = -k_1 X_1 + k_4 X_3 X_5 \\ \dot{X}_2 = k_1 X_1 - k_2 X_2 + k_5 X_4 X_5 \\ \dot{X}_3 = k_2 X_2 - k_3 X_3 - k_4 X_3 X_5 \\ \dot{X}_4 = k_3 X_3 - k_5 X_4 X_5 \\ \dot{X}_5 = -k_4 X_3 X_5 - k_5 X_4 X_5 + k_6 X_6 \\ \dot{X}_6 = k_4 X_3 X_5 + k_5 X_4 X_5 - k_6 X_6 \end{cases}$$

EXAMPLE 1: CHEMICAL REACTION NETWORKS

Two-component system
with hybrid histidine kinase



ODE of concentrations

$$0 = -k_1 X_1 + k_4 X_3 X_5$$

$$0 = k_1 X_1 - k_2 X_2 + k_5 X_4 X_5$$

$$0 = k_2 X_2 - k_3 X_3 - k_4 X_3 X_5$$

$$0 = k_3 X_3 - k_5 X_4 X_5$$

$$0 = -k_4 X_3 X_5 - k_5 X_4 X_5 + k_6 X_6$$

$$0 = k_4 X_3 X_5 + k_5 X_4 X_5 - k_6 X_6$$

For which k_i we have more than
one equilibrium (i.e. positive zero)?

More in: Bihan, Dickstein & Giavoli. Lower bounds for positive roots and regions of multistationarity in chemical reaction networks.

EXAMPLE 2. ALGEBRAIC VISION



$$\begin{aligned}(x_1, y_1) &\in \mathbb{R}P^2 \times \mathbb{R}P^2 \\(x_2, y_2) &\in \mathbb{R}P^2 \times \mathbb{R}P^2 \\(x_3, y_3) &\in \mathbb{R}P^2 \times \mathbb{R}P^2 \\(x_4, y_4) &\in \mathbb{R}P^2 \times \mathbb{R}P^2 \\(x_5, y_5) &\in \mathbb{R}P^2 \times \mathbb{R}P^2\end{aligned}$$

X

Y

Essential matrix: $E \in \mathbb{R}^{3 \times 3}$ (gives relative orientations)

$$2EE^T E = \text{tr}(EE^T)E \quad \det E = 0 \quad y_i^T E x_i = 0$$

More in: Nister. An efficient solution to the five-point relative pose problem.

POLYNOMIALS EVERYWHERE II

(Theoretical)
Questions

Applications

Problems with polynomials

How
to understand
them?

How
to solve them?

GEOMETRY OF POLYNOMIALS

Commutative algebra

Algebraic geometry

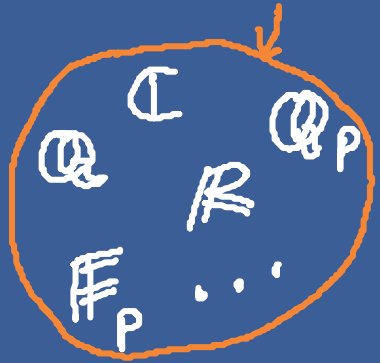
Differential geometry...

A CASE STUDY FOR COMPUTATION: POLYNOMIAL SYSTEM SOLVING

HOW IS THE SYSTEM GIVEN?

GIVEN?

coefficients

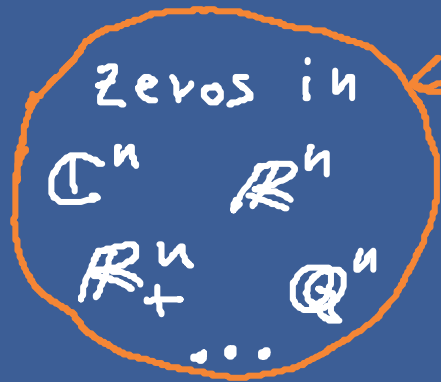


exact or approximate?

Cost of operation
bit arithmetic

structured
dense sparse

WHAT MEANS TO FIND A ZERO?



how to represent it?

approximation

RUR

à la Smale

isolating boxes

floating point

algebraic extensions (Gröbner bases)

HOW MUCH DOES COMPUTATION COST?

COST?

Complexity framework

worst-case

condition-based

probabilistic

WARNING:

NOT EVERYTHING IS FINDING ZEROS!

Existence
of solutions

Elimination

Counting
solutions

Computing
topological
invariants

Implicitization

Computing
degree/dimension

SYMBOLIC vs. NUMERICAL

exact
vs.
approximate

input operations
output

implicit assumptions
of computation

Cost
bit vs. arithmetic

Complexity framework
worst-case probabilistic
condition-based

A ROADMAP TO THE SESSION

Existence
of Solutions

Dickenstein
Sombra

Elimination/
Implicitization

D'Andrea Krick
Tsigaridas

Computing
over p -adics
Rojas

Solving Structured
Polynomial Systems

Buse' Regan

Homotopy Continuation

Cucker Rodriguez
Malajovich Walker

Computing
over \mathbb{R}

Szanto Yap

Numerical
Complexity Theory

Burr Carrasco

Positive dimensional
systems

Herrero Sottile

Ergür

Spheres: Etayo

Applications

Bürgisser Garrote Jeronimo

And for the Europe-based researchers,
one advice for the session...

