

Improving Hadron Matrix Element Determination using the Variational Method

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CSSM/QCDSF/UKQCD

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Lattice QCD Motivation

- Calculation of g_A , g_S and $\langle x \rangle$ have been difficult.

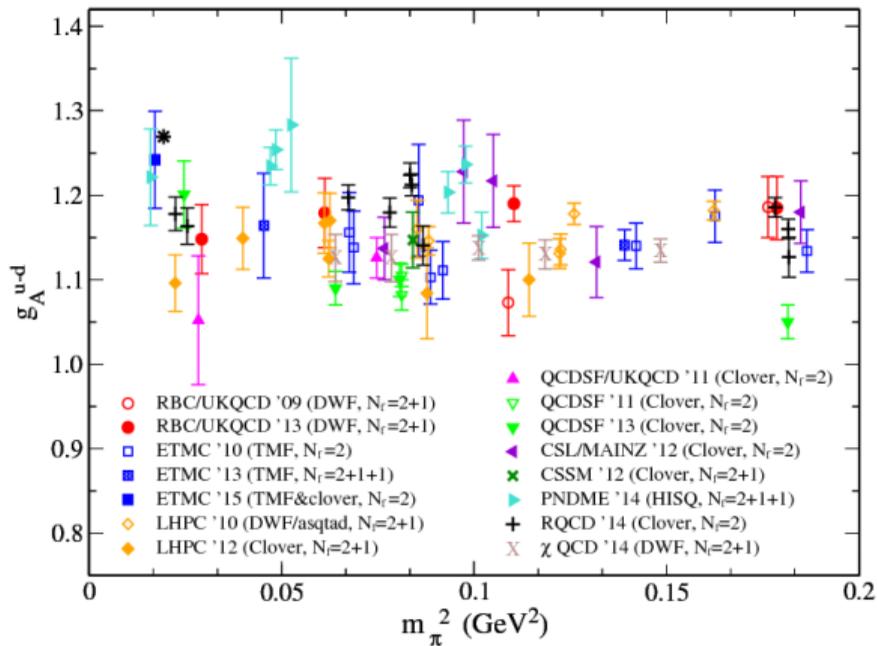


Figure: Constantinou 2015

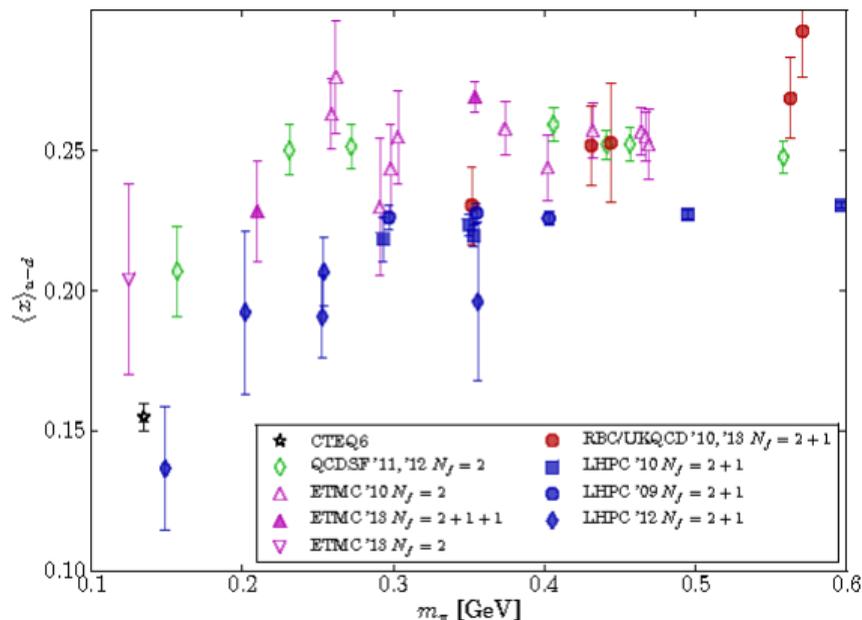


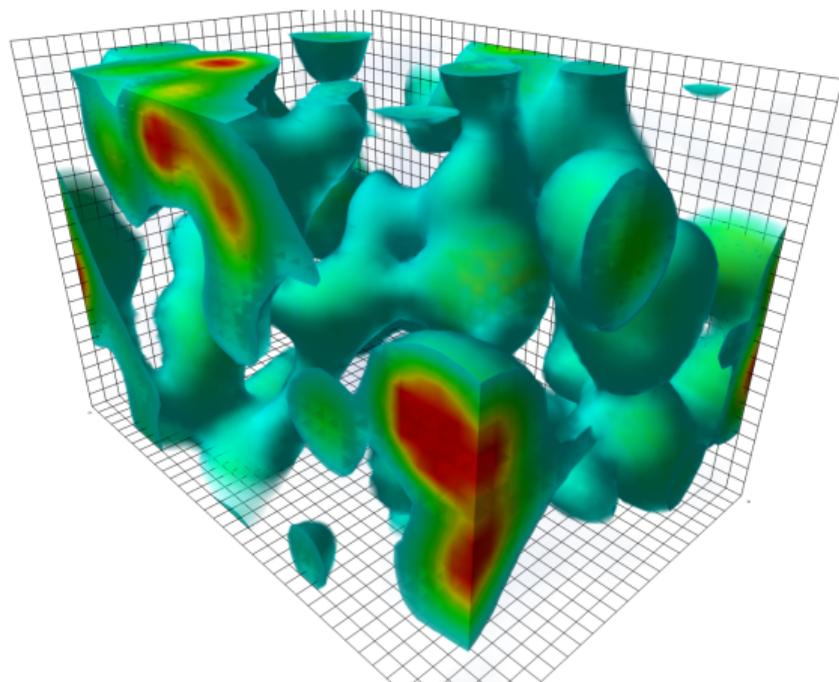
Figure: Syritsyn 2014

Aim

- Some problems associated with calculating these include:
 - ▶ Finite size effects
 - ▶ Renormalisation
 - ▶ Continuum extrapolation
 - ▶ Excited-state contamination
- This talk:
 - ▶ $g_A, g_S, \langle x \rangle$
 - ▶ form factors, G_E, G_M, G_A, G_P
- Emphasis on excited-state contamination effects
- Some proposed methods to improve this include:
 - ▶ Summation method
 - ▶ Two-state fit method
 - ▶ Variational method
- The aim of this work is to systematically compare 3 three methods for all quantities extracted.

Calculation Parameters

- QCDSF/UKQCD/CSSM gauge fields.
- SU(3)-symmetric point
- $m_\pi \approx 470$ MeV.
- Lattice Spacing of 0.074 fm
- $32^3 \times 64$ volume.
- Gauge-invariant Gaussian smearing.



Calculation Parameters

- Summation / two-state fit methods:
 - ▶ $t_{sink} - t_{source} = 10, 13, 16, 19, 22$ ($0.74 \text{ fm} \leq t \leq 1.63 \text{ fm}$)
 - ▶ Smearing = 32 sweeps (rms radius = 0.248 fm)
- Variational method:
 - ▶ $t_{sink} - t_{source} = 13, 16$ (0.96 fm , 1.184 fm)
 - ▶ Smearings = 32, 64, 128 sweeps (rms radius = 0.248 fm, 0.351 fm, 0.496 fm)

	t	10	13	16	19	22
N_{smear}						
32		*	*	*	*	*
64			*			
128			*			
variational			*	*		

Two-Point Correlators

Defined as:

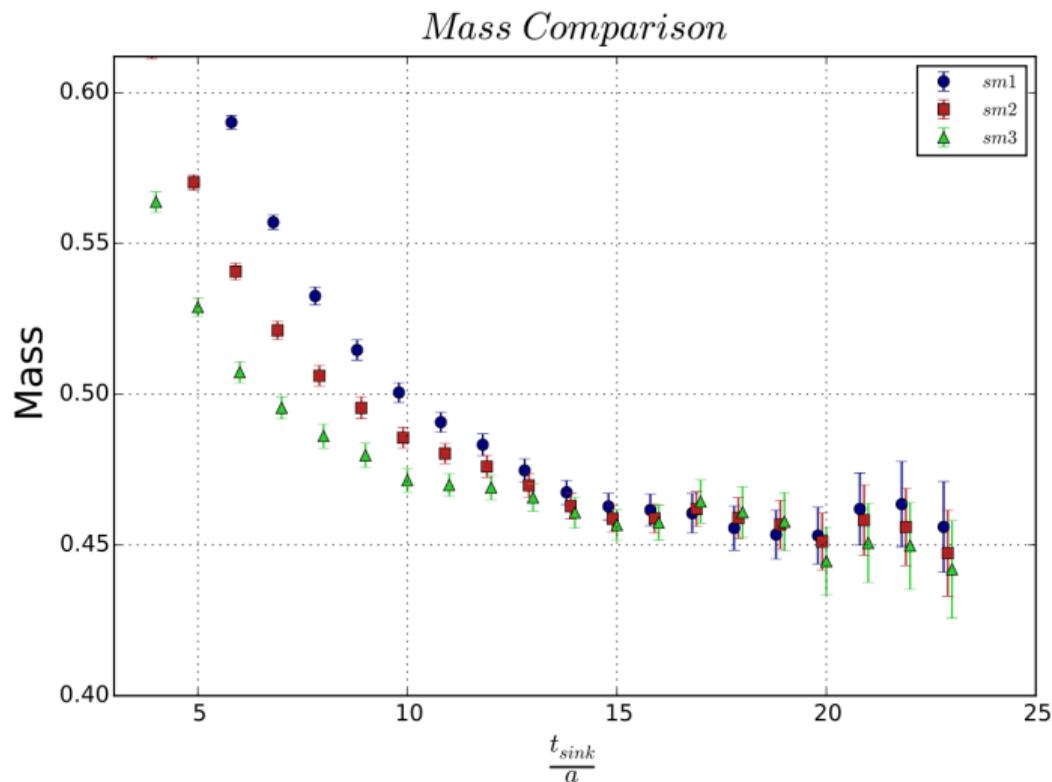
$$G_2(\Gamma; \vec{p}, t) = \sum_{\vec{x}} e^{-i\vec{p}\cdot\vec{x}} \text{Tr} \{ \Gamma \langle \Omega | \chi(\vec{x}, t) \bar{\chi}(0) | \Omega \rangle \}$$

Which reduces to:

$$G_2(\Gamma_4; \vec{p}, t) = \sum_{\alpha} e^{-E_{\vec{p}}^{\alpha} t} \bar{Z}_{\vec{p}}^{\alpha} Z_{\vec{p}}^{\alpha}$$

Can find the mass m , via:

$$\log \left(\frac{G_2(\Gamma_4; \vec{0}, t)}{G_2(\Gamma_4; \vec{0}, t + \Delta t)} \right) \xrightarrow{t \gg 0} m \Delta t$$



Variational Method

Create a linear combination that strongly couples to state α

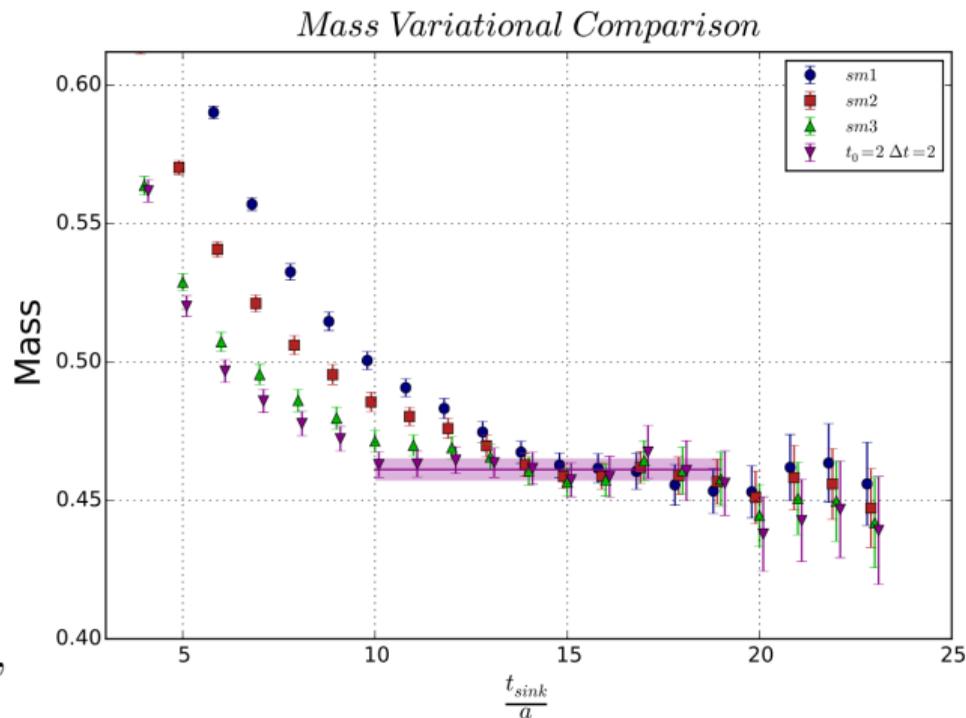
$$\phi^\alpha(x, \vec{p}) \equiv \sum_i v_i^\alpha(\vec{p}) \chi_i(x),$$

$$\bar{\phi}^\alpha(0, \vec{p}) \equiv \sum_i u_i^\alpha(\vec{p}) \bar{\chi}_i(0)$$

u and v obtained by solutions to a Generalised Eigenvalue Problem.

Optimal 2 point correlator is produced by projecting with u and v :

$$G_2^\alpha(\vec{p}, t; \Gamma) = v_i^\alpha(\vec{p}) (G_2)_{ij}(\Gamma; \vec{p}, t) u_j^\alpha(\vec{p}),$$



Three-point correlators

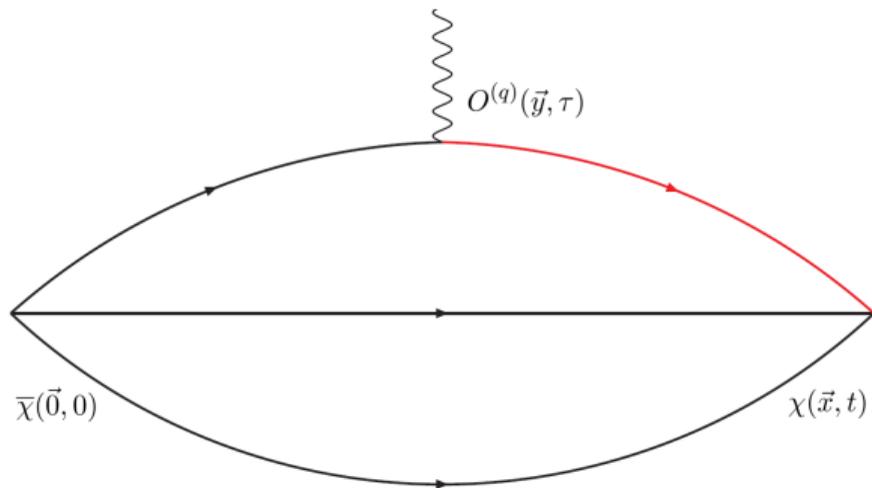
Three-point correlator defined as:

$$G_3(\Gamma; \vec{p}', t; \vec{q}, \tau; O^{(q)}) = \sum_{\vec{x}, \vec{y}} e^{-i\vec{p}' \cdot \vec{x}} e^{i\vec{q} \cdot \vec{y}} \text{Tr} \left\{ \Gamma \langle \Omega | \chi(\vec{x}, t) O^{(q)}(\vec{y}, \tau) \bar{\chi}(\vec{0}, 0) | \Omega \rangle \right\}$$

For zero momentum, a simple ratio gives us an extracted value

$$R(\Gamma; t; \tau; O^{(q)}) \equiv \frac{G_3(\Gamma; t; \tau; O^{(q)})}{G_2(\Gamma_4; t)} \xrightarrow{t \gg \tau \gg 0} FF$$

Selecting appropriate $O^{(q)}$ and Γ gives access to $FF = g_A, g_S$ etc..



Variational Method for Three-Point Correlators

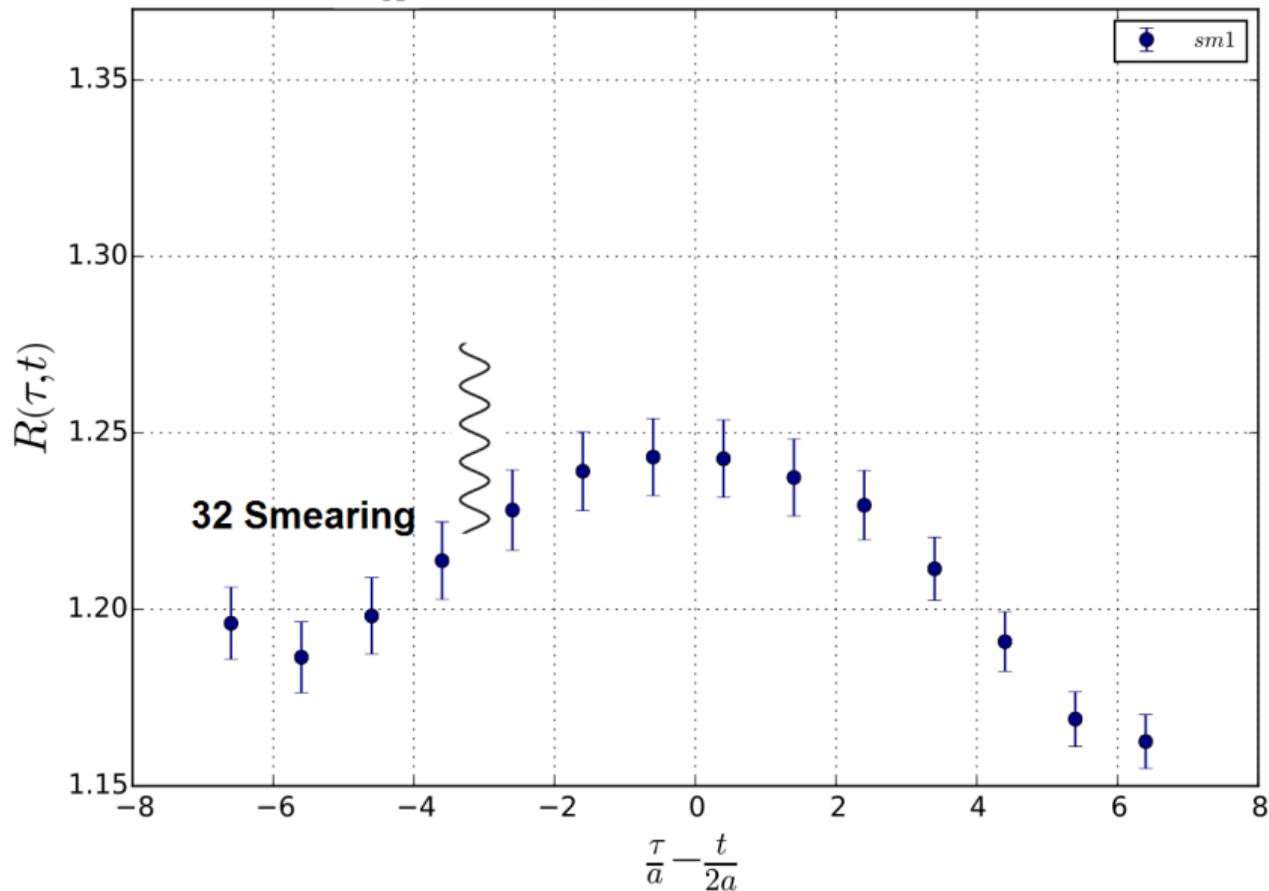
Extending the variational method to three-point correlators, we have:

$$G_3^\alpha(\Gamma; \vec{p}', t; \vec{q}, \tau; O^{(q)}) = \sum_{\vec{x}, \vec{y}} e^{-i\vec{p}' \cdot \vec{x}} e^{i\vec{q} \cdot \vec{y}} \text{Tr} \left\{ \Gamma \langle \Omega | \phi^\alpha(x, \vec{p}) O^{(q)}(y) \bar{\phi}^\alpha(0, \vec{p}) | \Omega \rangle \right\}$$

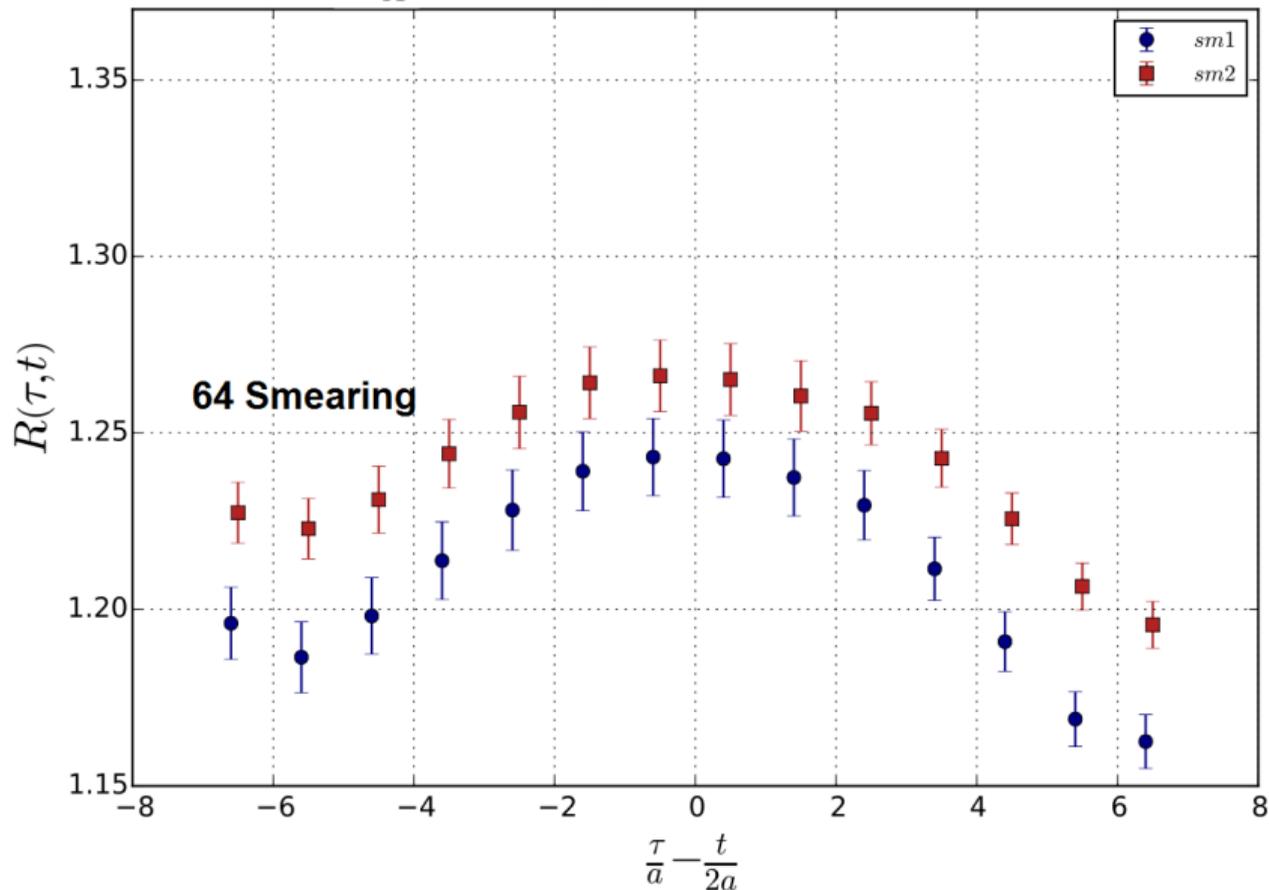
So in terms of calculation, we can use the same u and v vectors in the three-point correlator construction via the projection:

$$G_3^\alpha(\Gamma; \vec{p}', t; \vec{q}, \tau; O^{(q)}) = v_i^\alpha(\vec{p}') (G_3)_{ij}(\Gamma; \vec{p}', t; \vec{q}, \tau; O^{(q)}) u_j^\alpha(\vec{p})$$

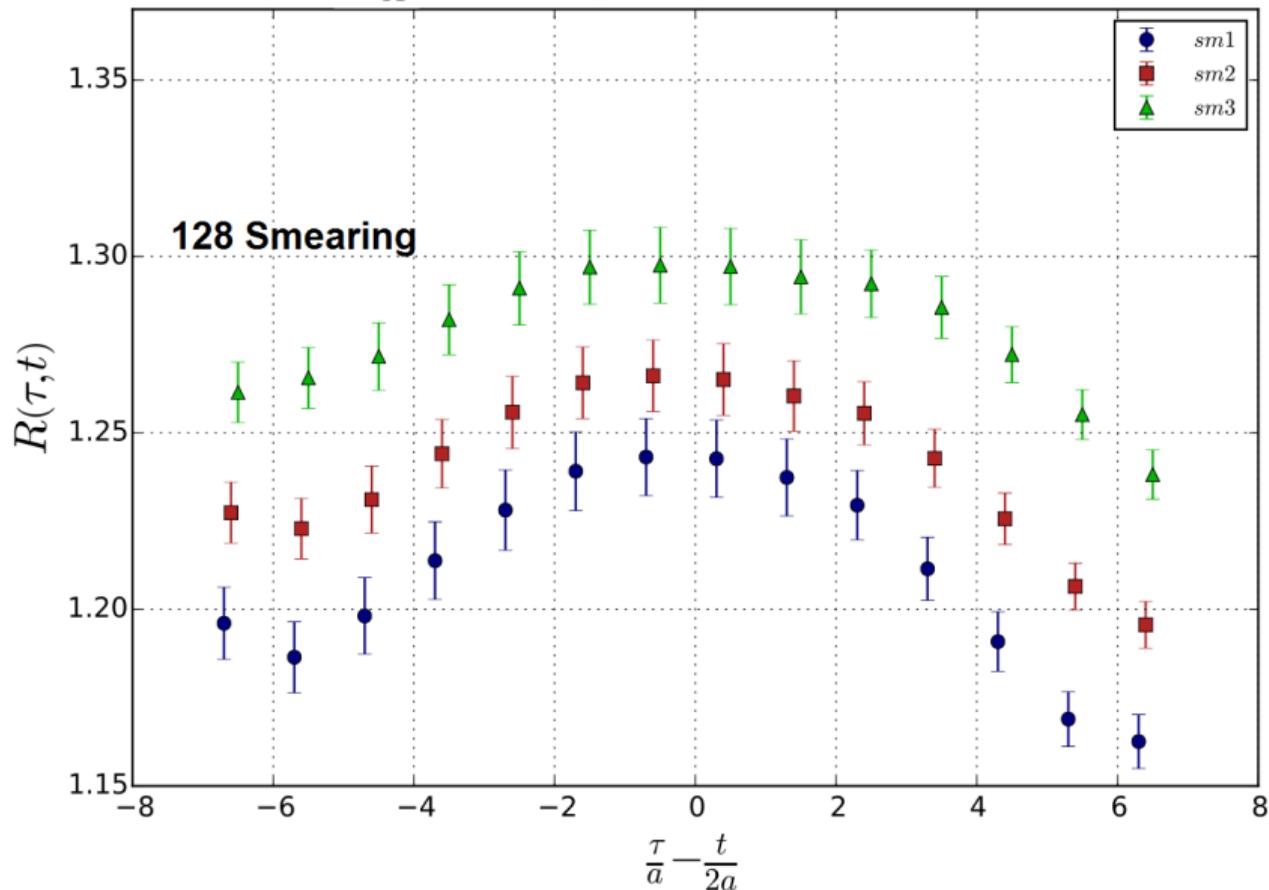
\tilde{g}_A Smearing Comparison $t=13$

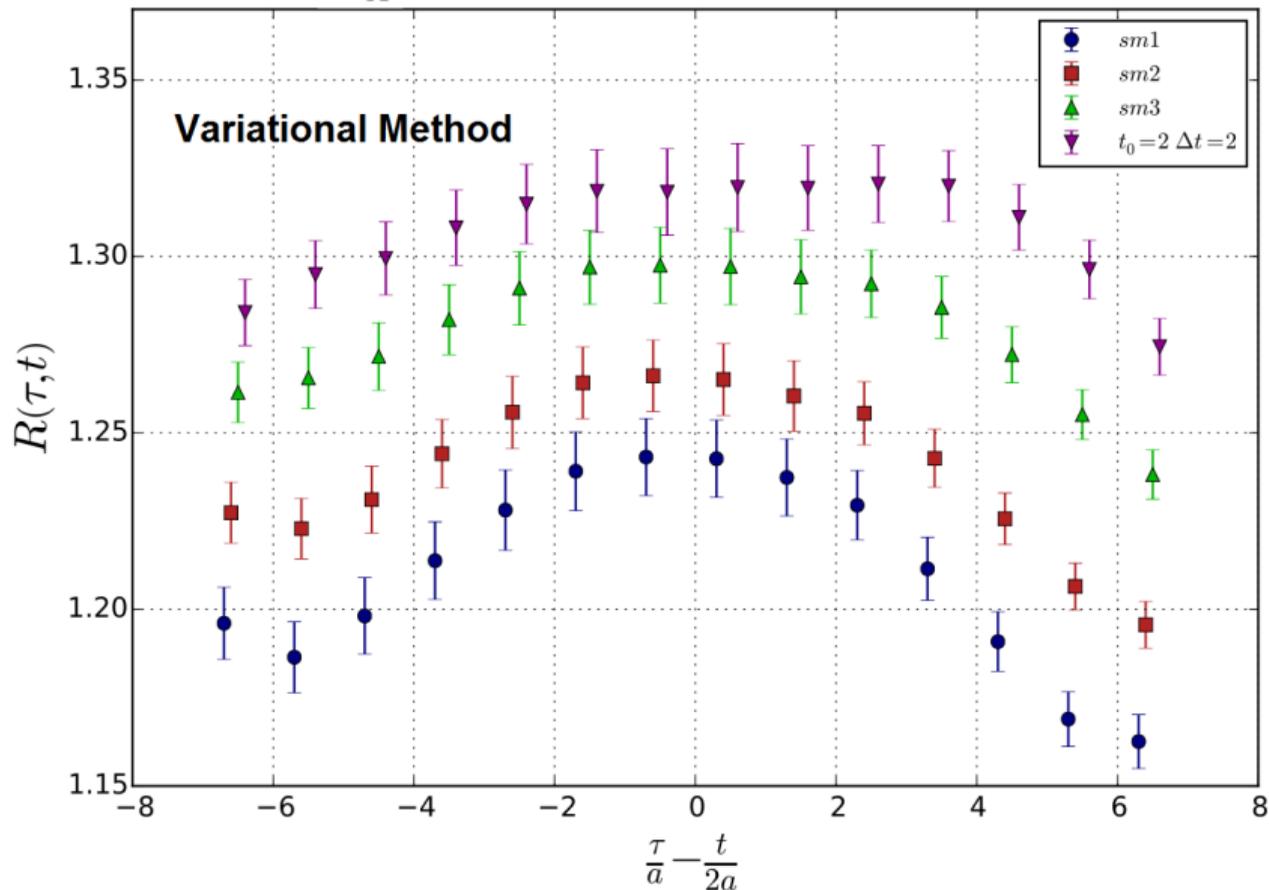


\tilde{g}_A Smearing Comparison $t=13$

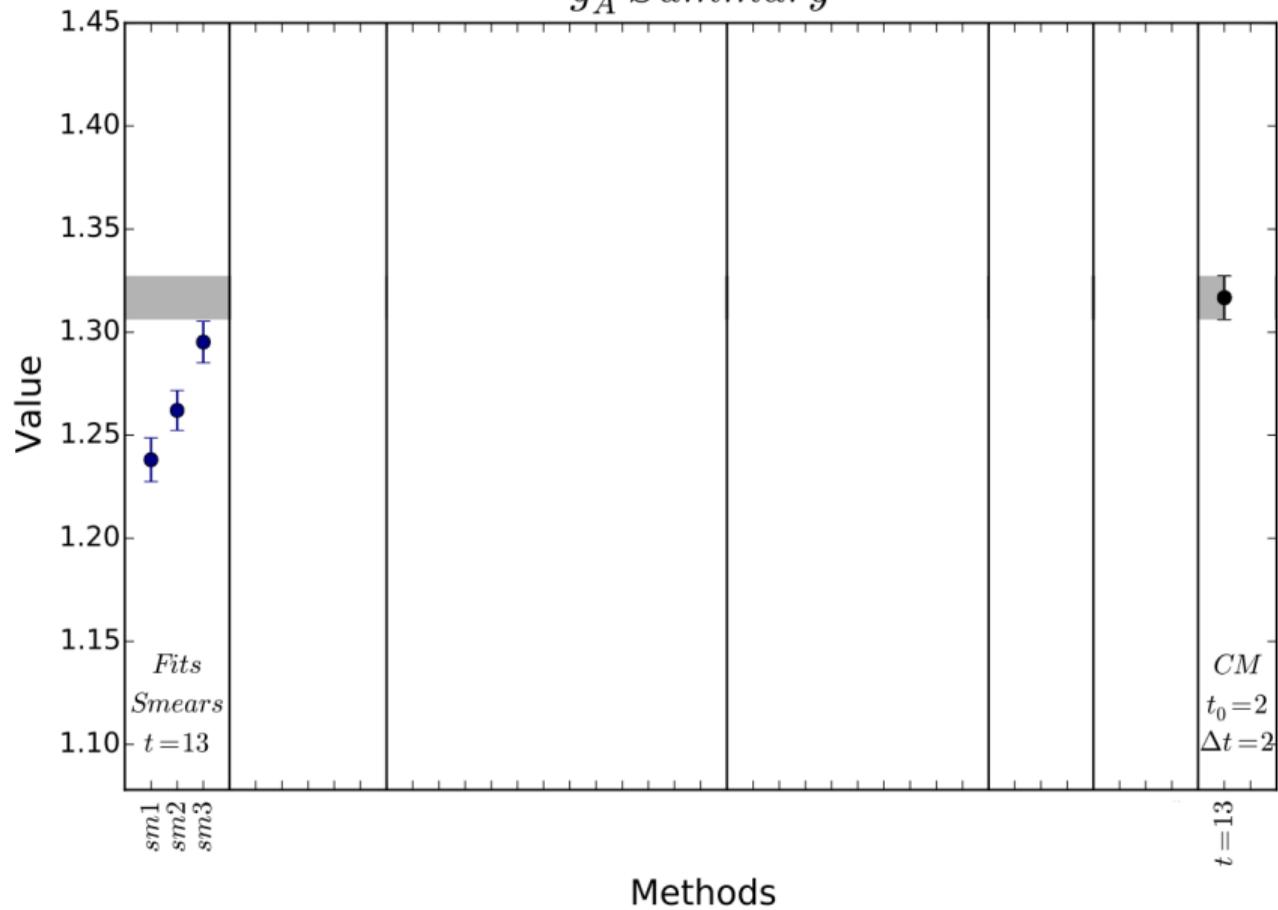


\tilde{g}_A Smearing Comparison $t=13$

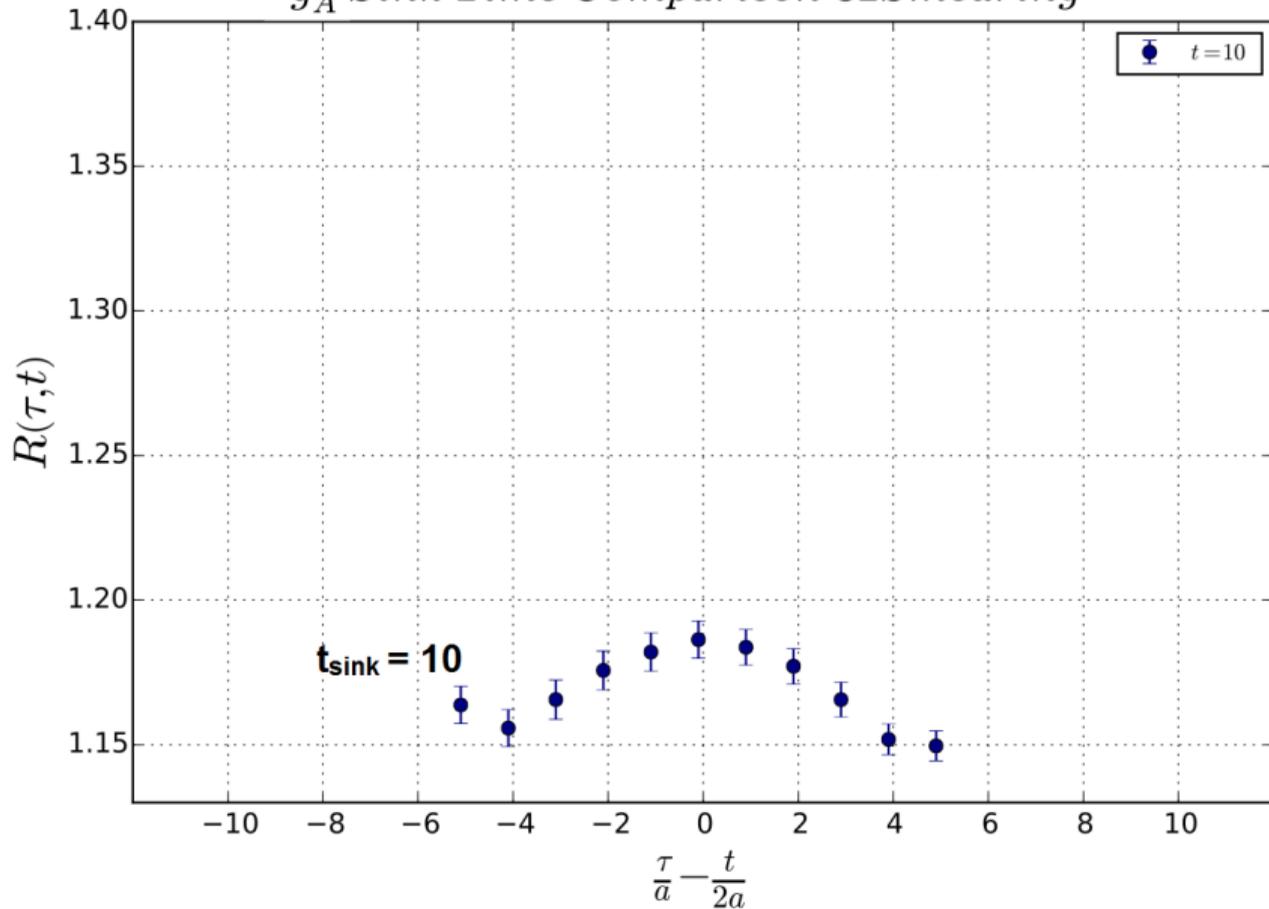


\tilde{g}_A Variational Comparison $t=13$ 

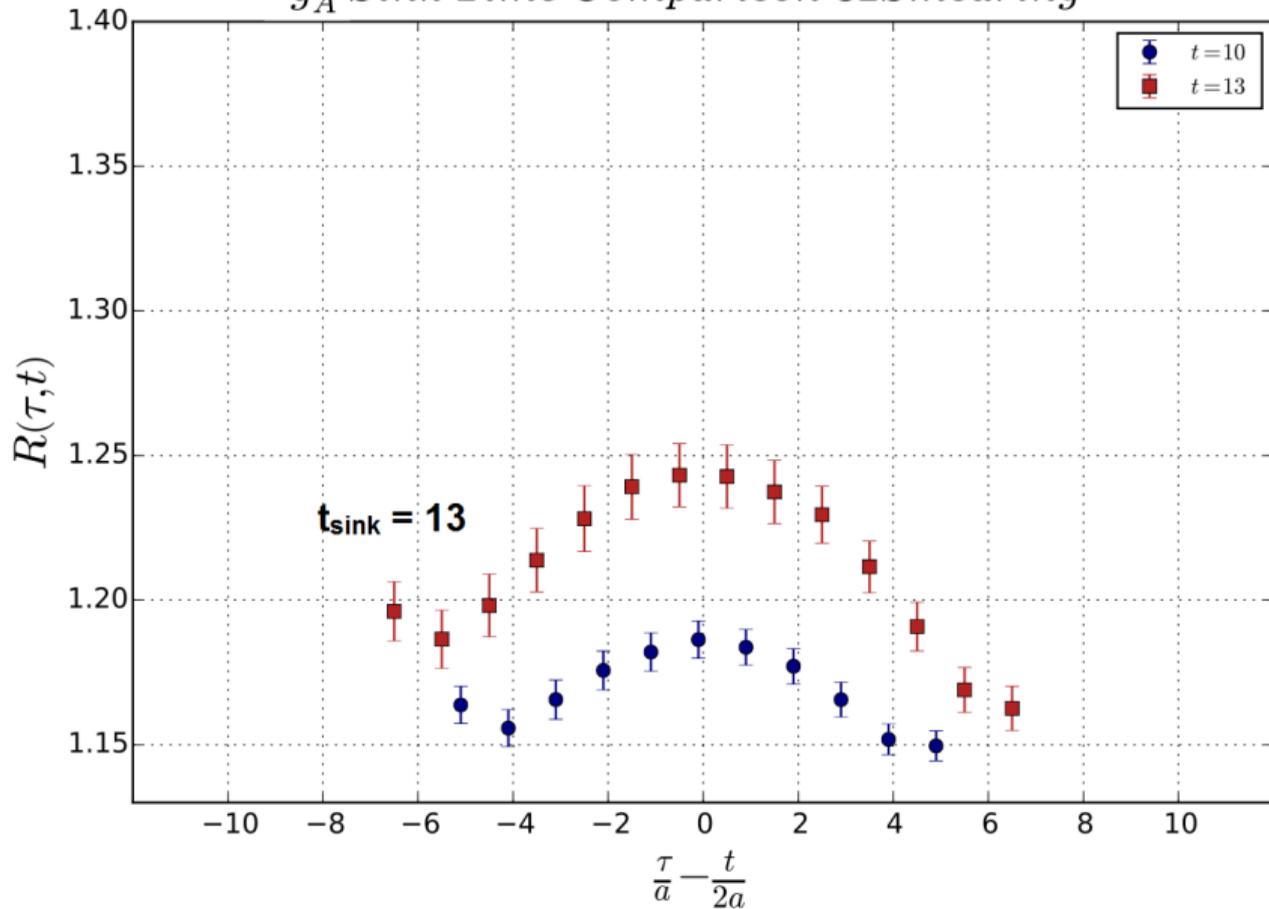
\tilde{g}_A Summary



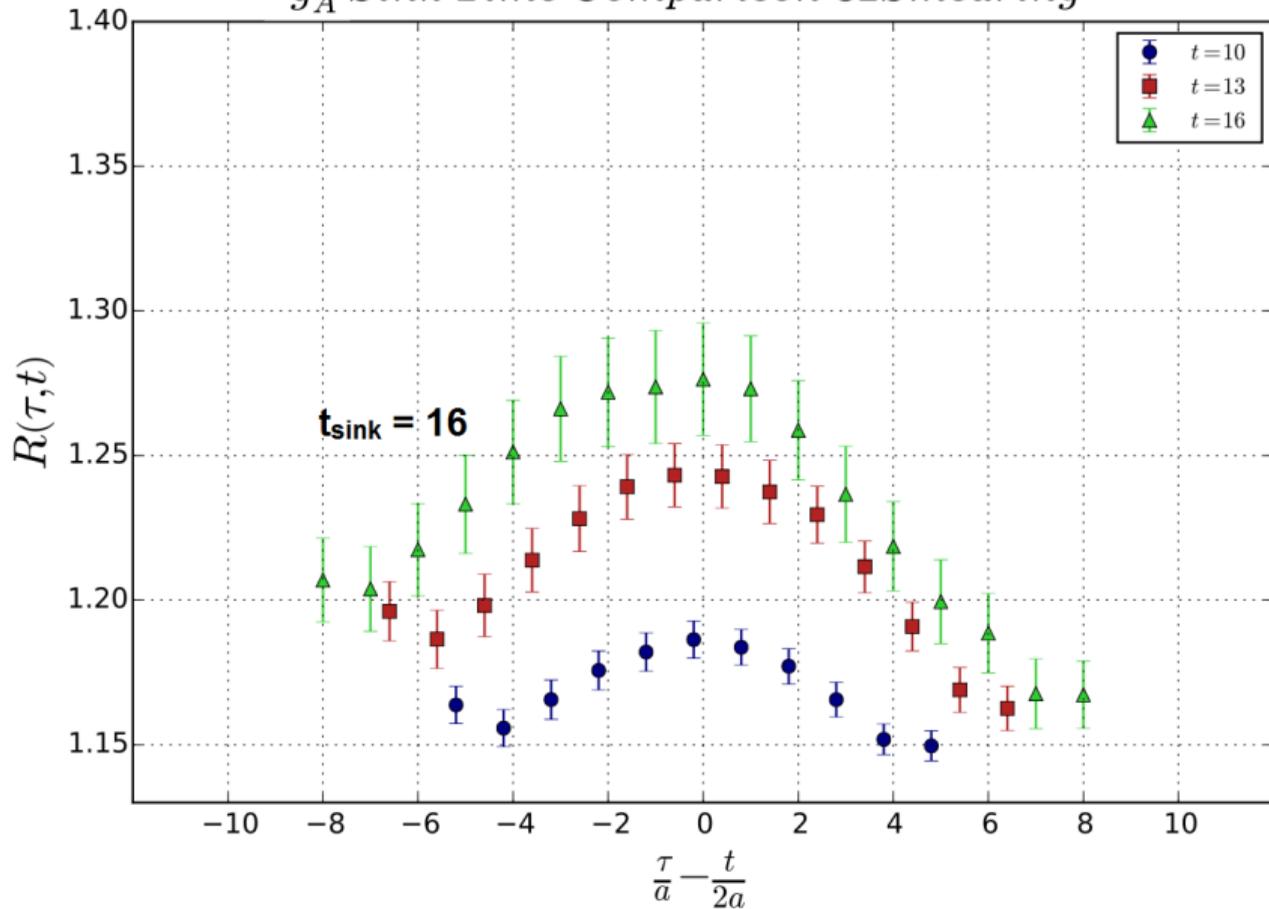
\tilde{g}_A Sink Time Comparison 32Smearing



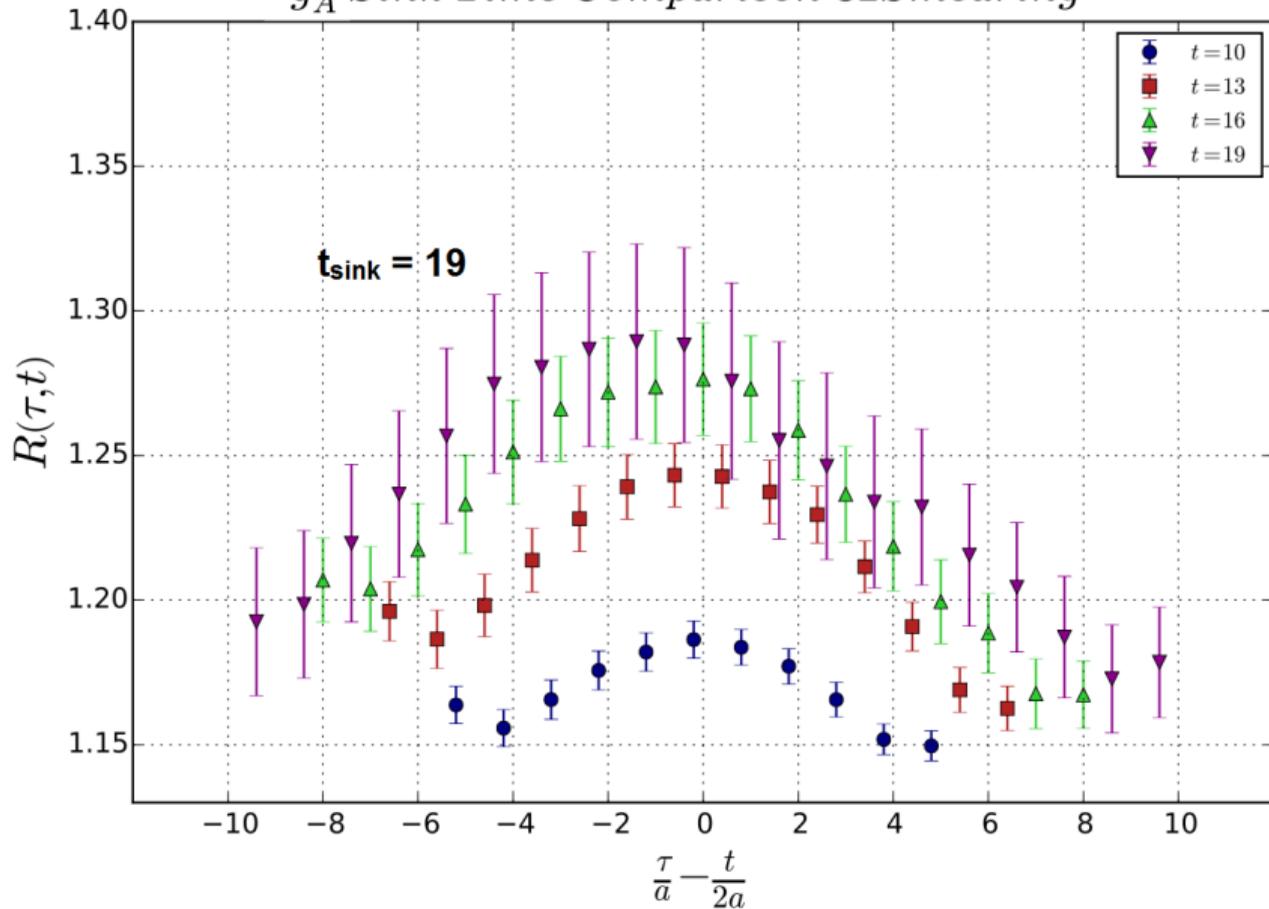
\tilde{g}_A Sink Time Comparison 32Smearing



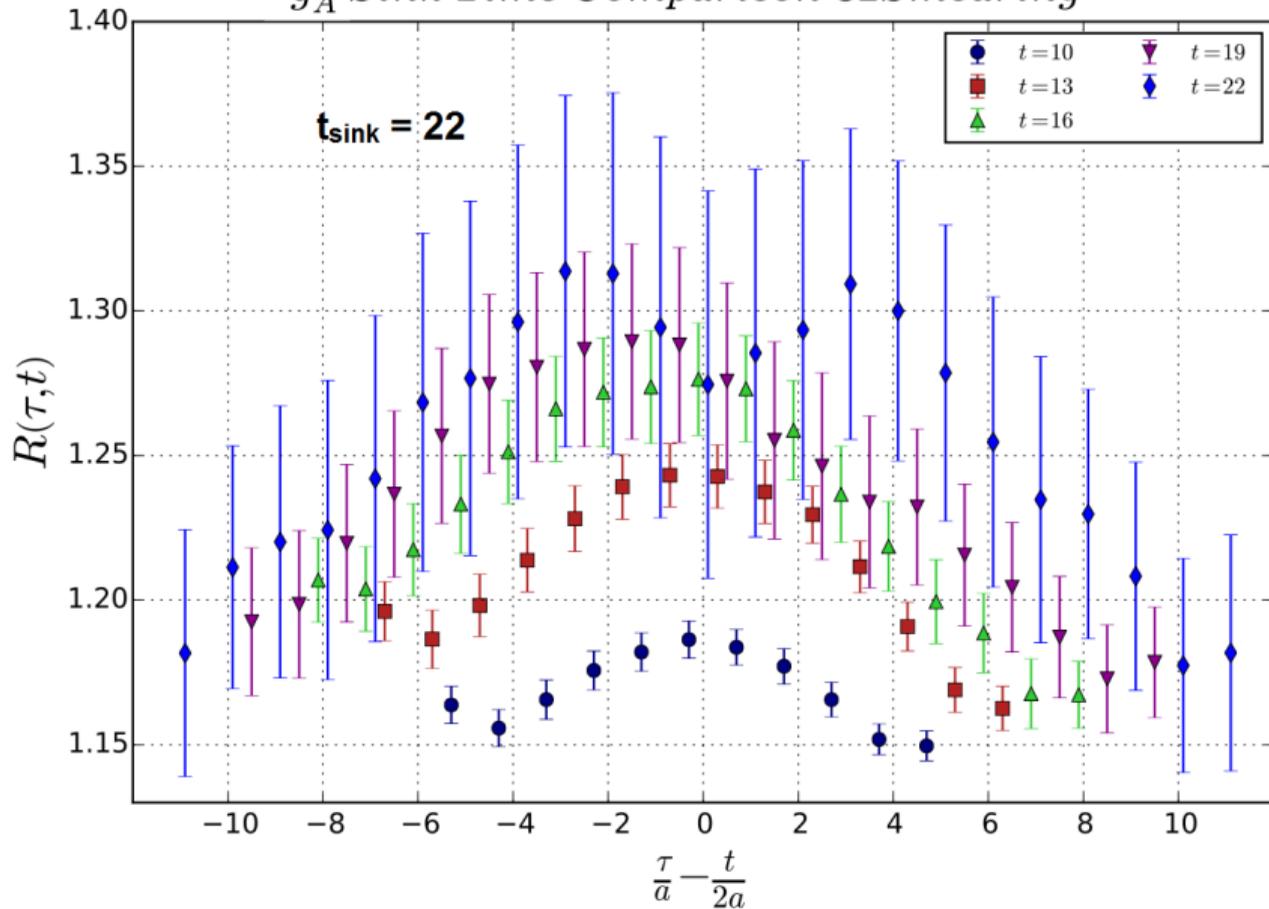
\tilde{g}_A Sink Time Comparison 32Smearing



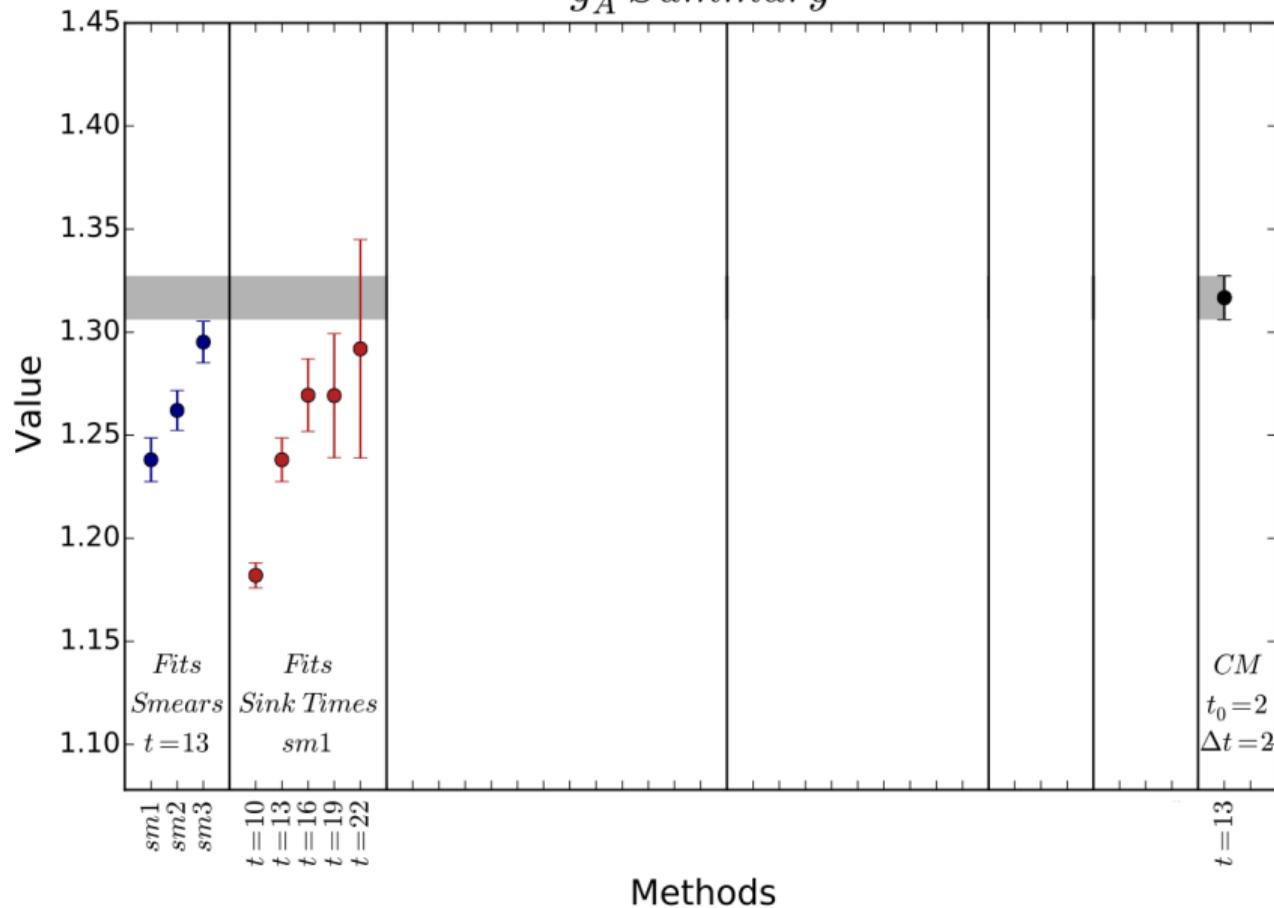
\tilde{g}_A Sink Time Comparison 32Smearing



\tilde{g}_A Sink Time Comparison 32Smearing



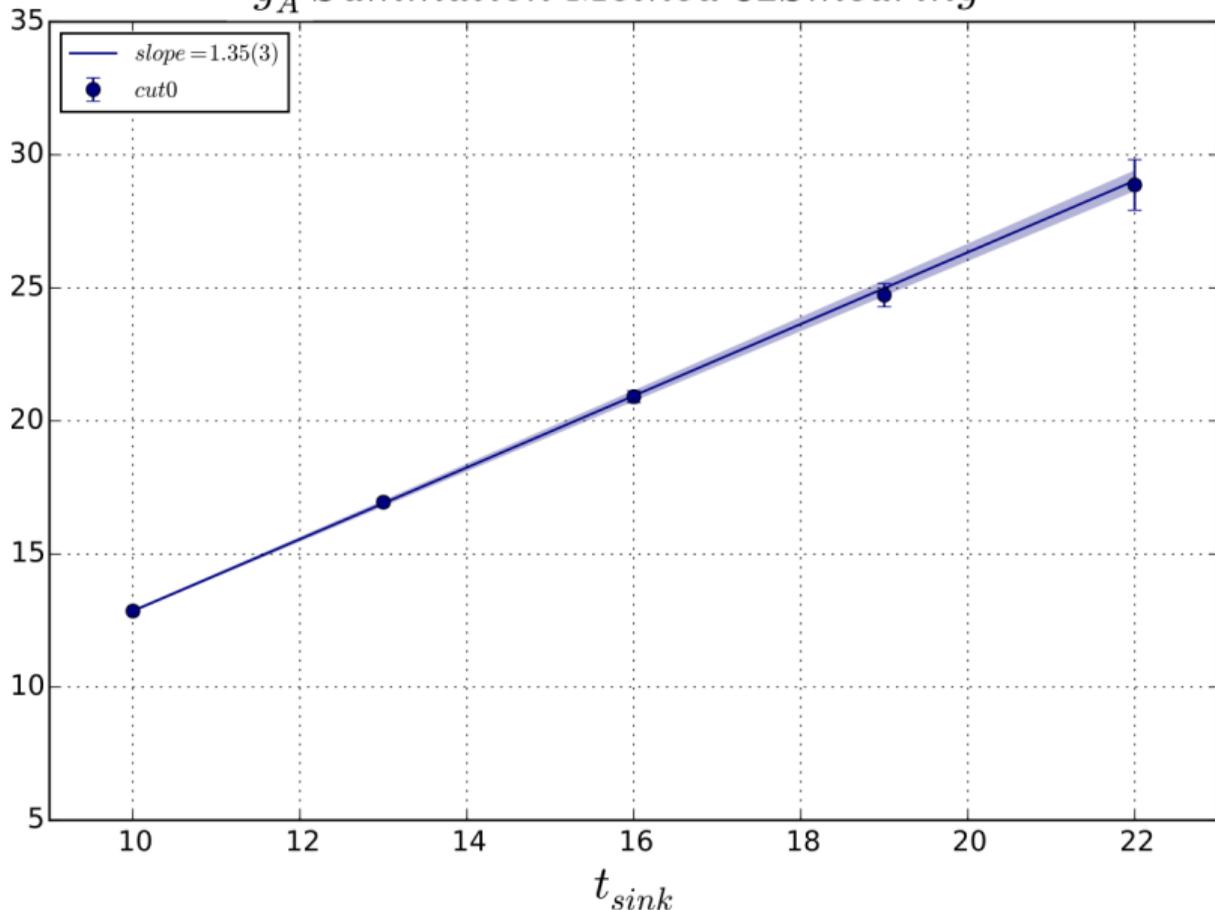
\tilde{g}_A Summary



\tilde{g}_A Summation Method 32Smearing

$$S(t) = \sum_{\tau=\delta t}^{t-\delta t} R(t, \tau) \rightarrow c + t \left\{ FF + \mathcal{O}\left(e^{-\Delta m t}\right) \right\}$$

- Where $\Delta m = m^1 - m^0$.
- Free to choose δt (or cut value).

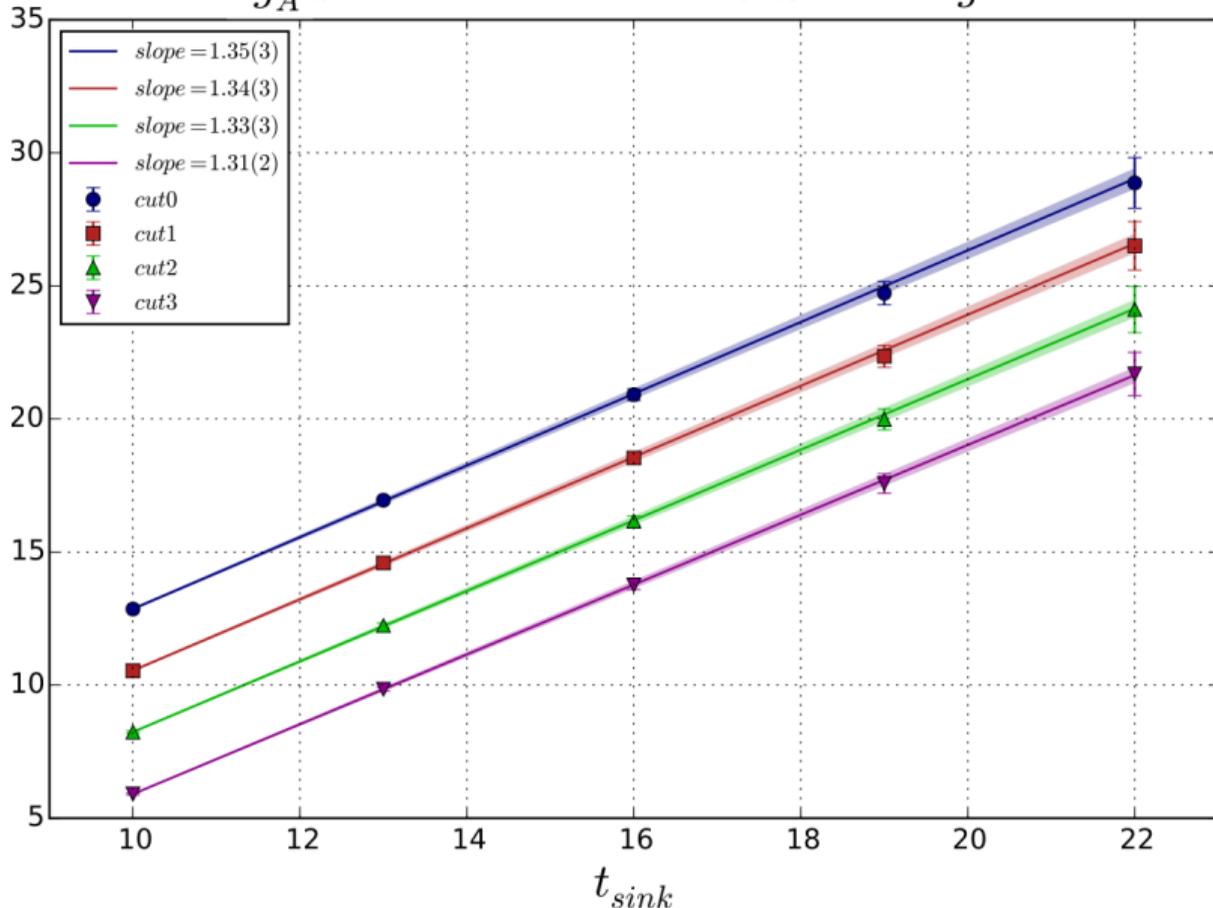


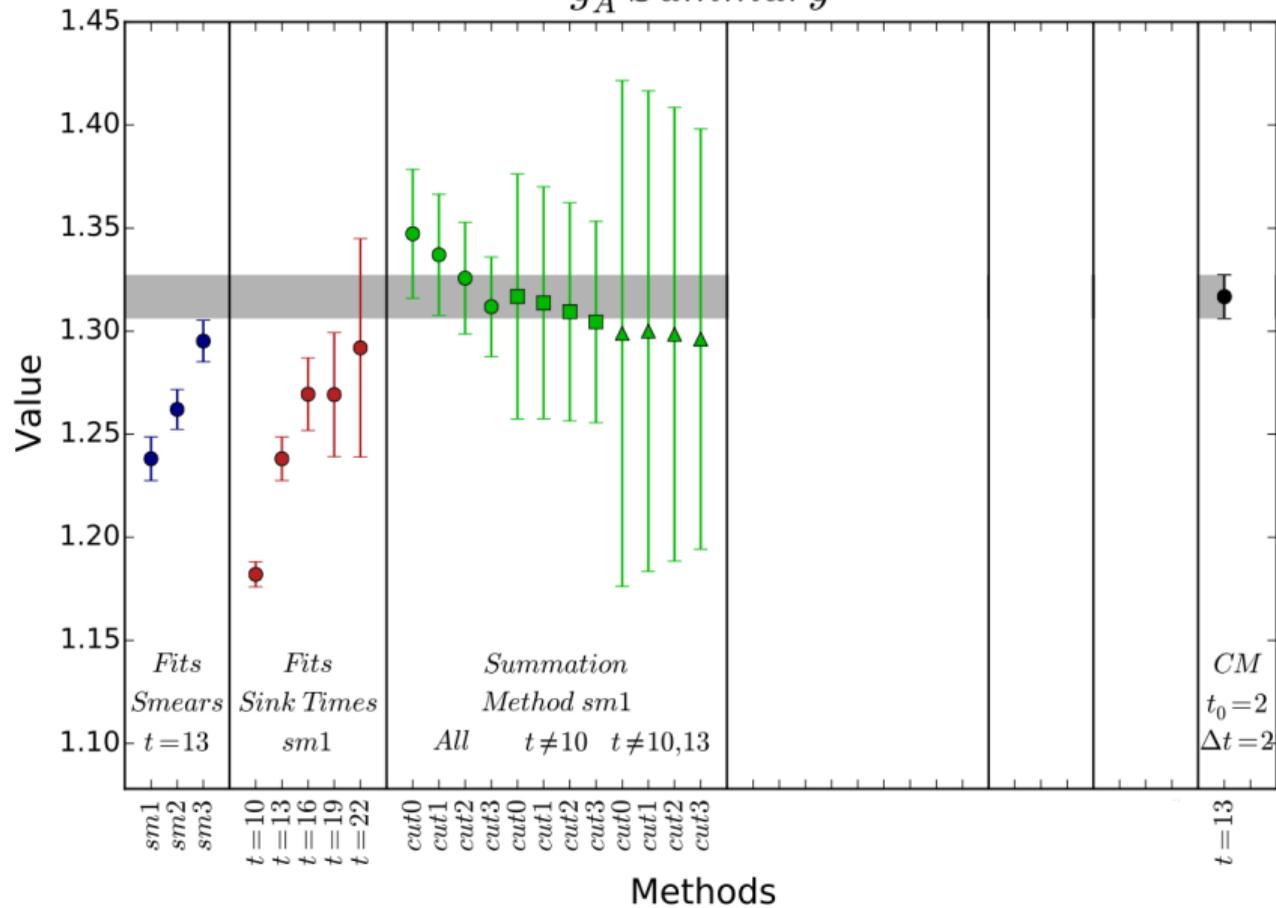
\tilde{g}_A Summation Method 32Smearing

$$S(t) = \sum_{\tau=\delta t}^{t-\delta t} R(t, \tau) \rightarrow$$

$$c + t \left\{ FF + \mathcal{O} \left(e^{-\Delta m t} \right) \right\}$$

- Where $\Delta m = m^1 - m^0$.
- Free to choose δt (or cut value).



\tilde{g}_A Summary

Two-Exponential Fit

Fitting an expected function for the two states produces mass and coefficient parameters

$$G_2(\vec{0}, t) = A_m e^{-mt} + A'_m e^{-(m+\Delta m)t}$$

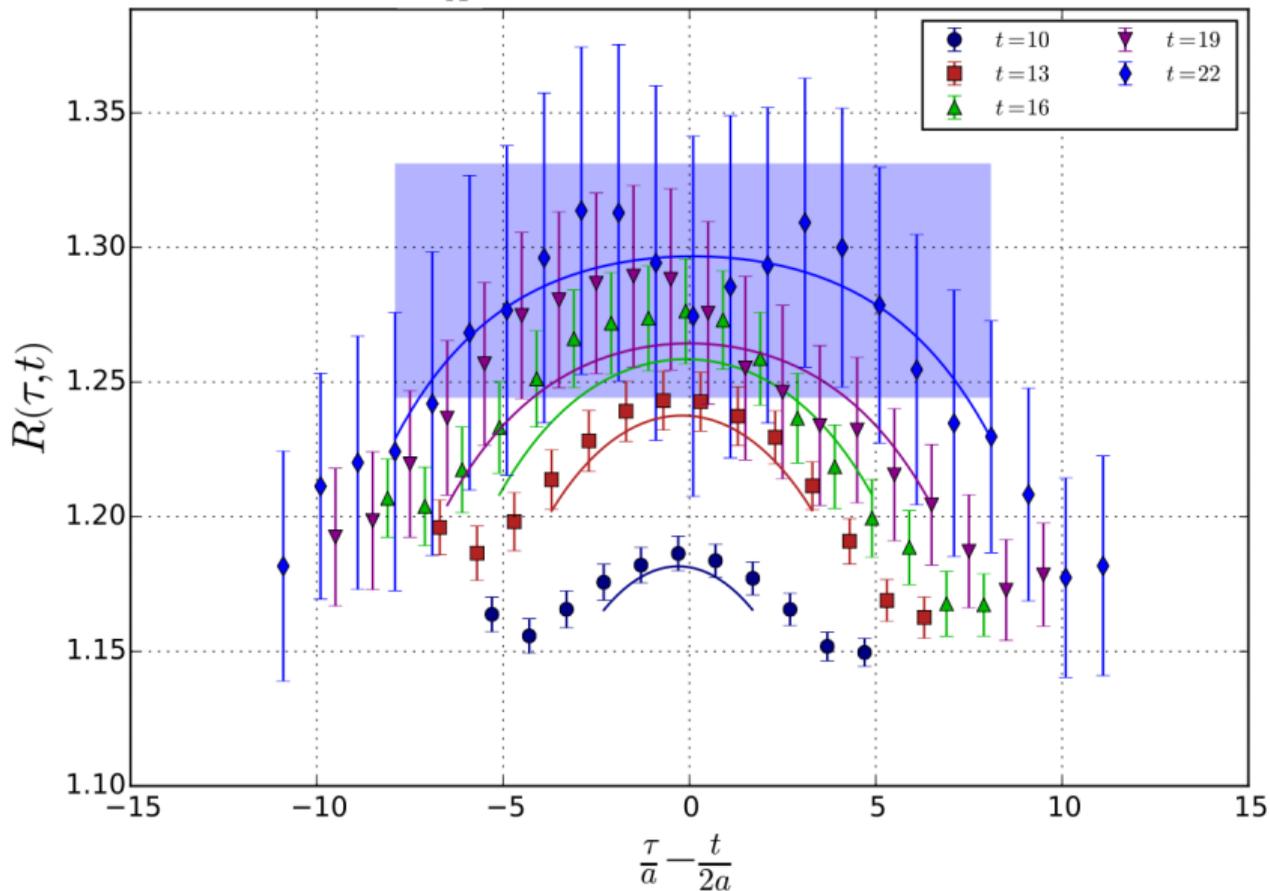
Then use the fit parameters above to fit another expected function for the three-point case

$$G_3(\Gamma; \vec{0}, t; \vec{0}, \tau; O^{(q)}) = A_m e^{-mt} \left\{ B_0 + B_1 \left(e^{-\Delta m \tau} + e^{-\Delta m(t-\tau)} \right) + B_2 e^{-\Delta m t} \right\}.$$

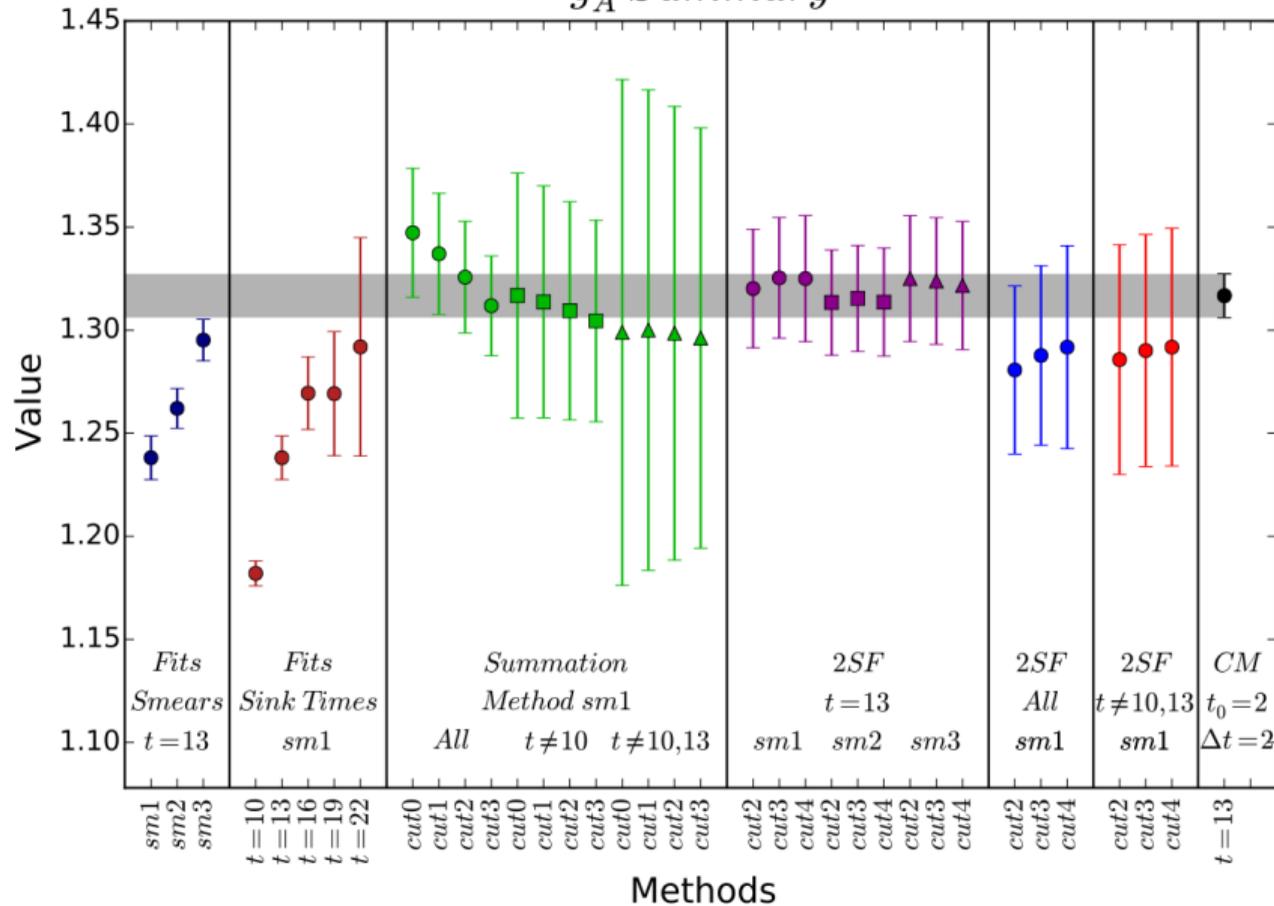
Where B_0 is proportional to the matrix element in question,

B_2 can only be calculated if fitting over multiple sink times.

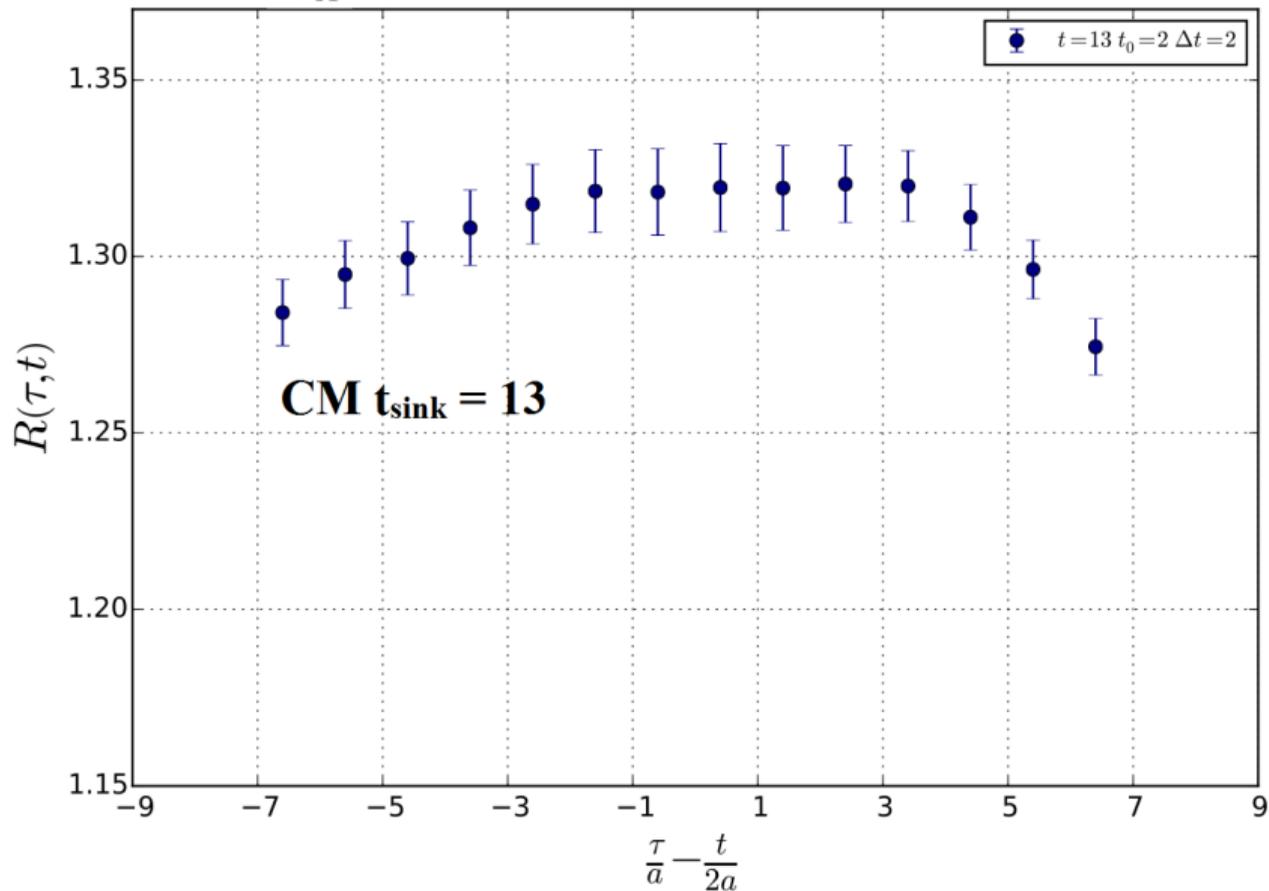
\tilde{g}_A 2SFT Sink Comparison



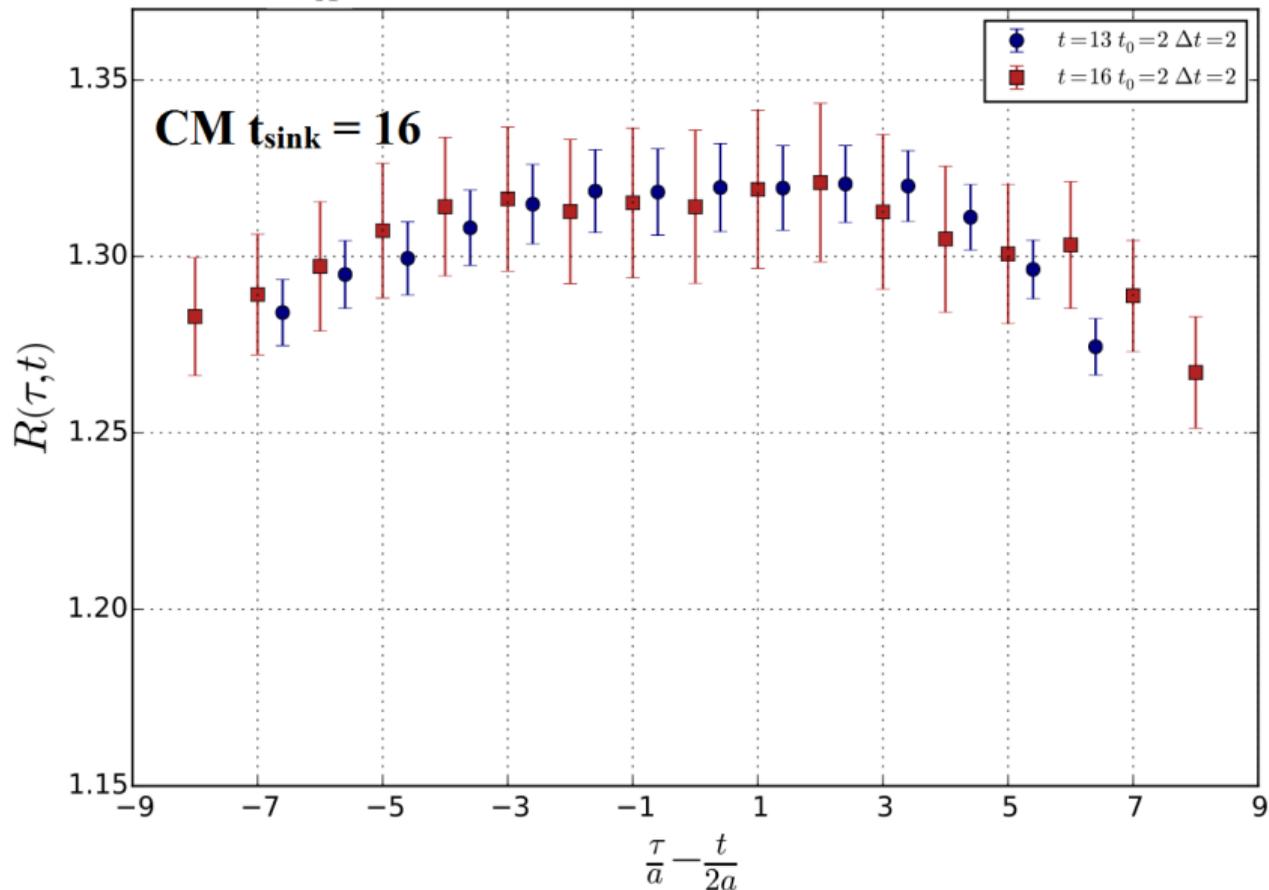
\tilde{g}_A Summary

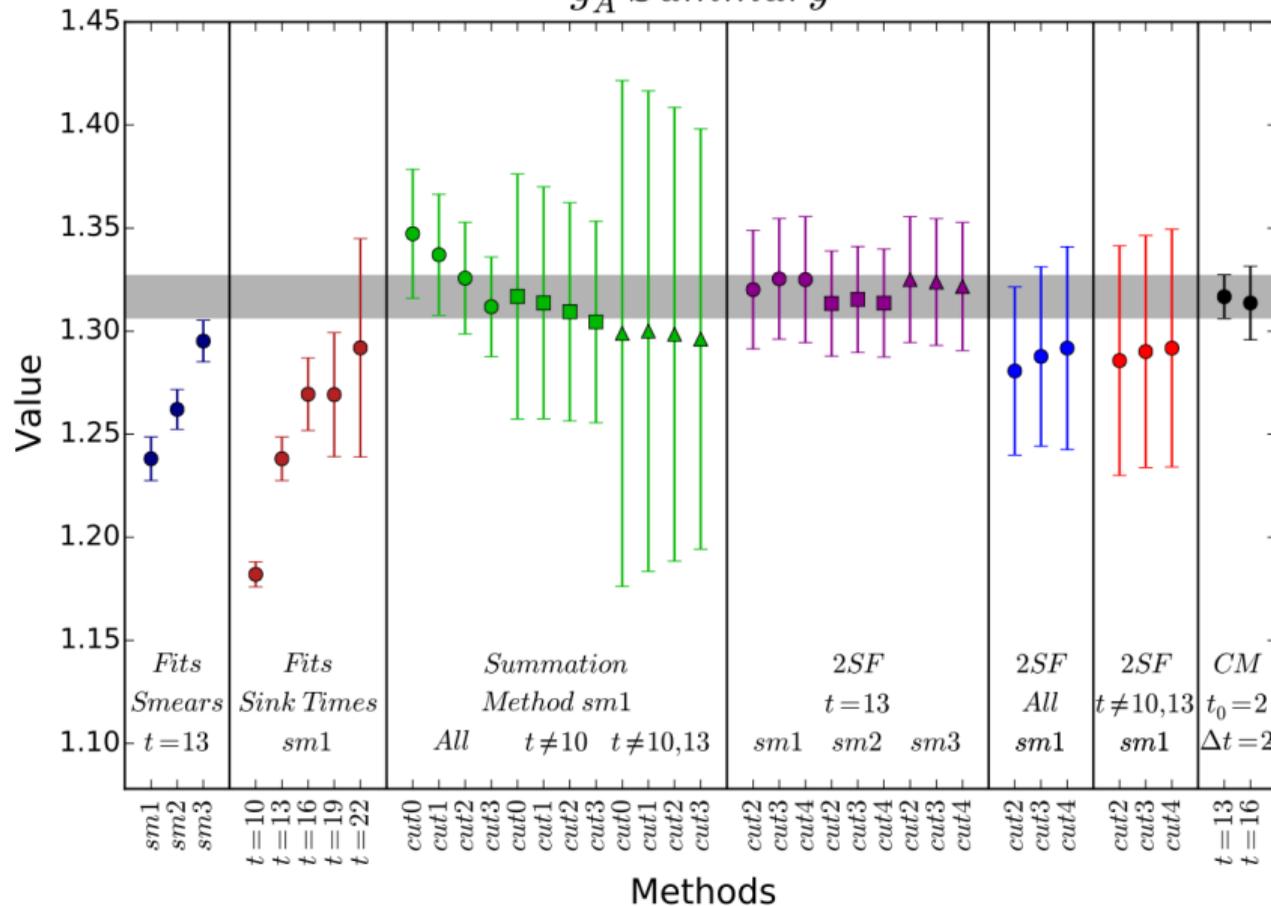


\tilde{g}_A Variational Sink Time Comparison

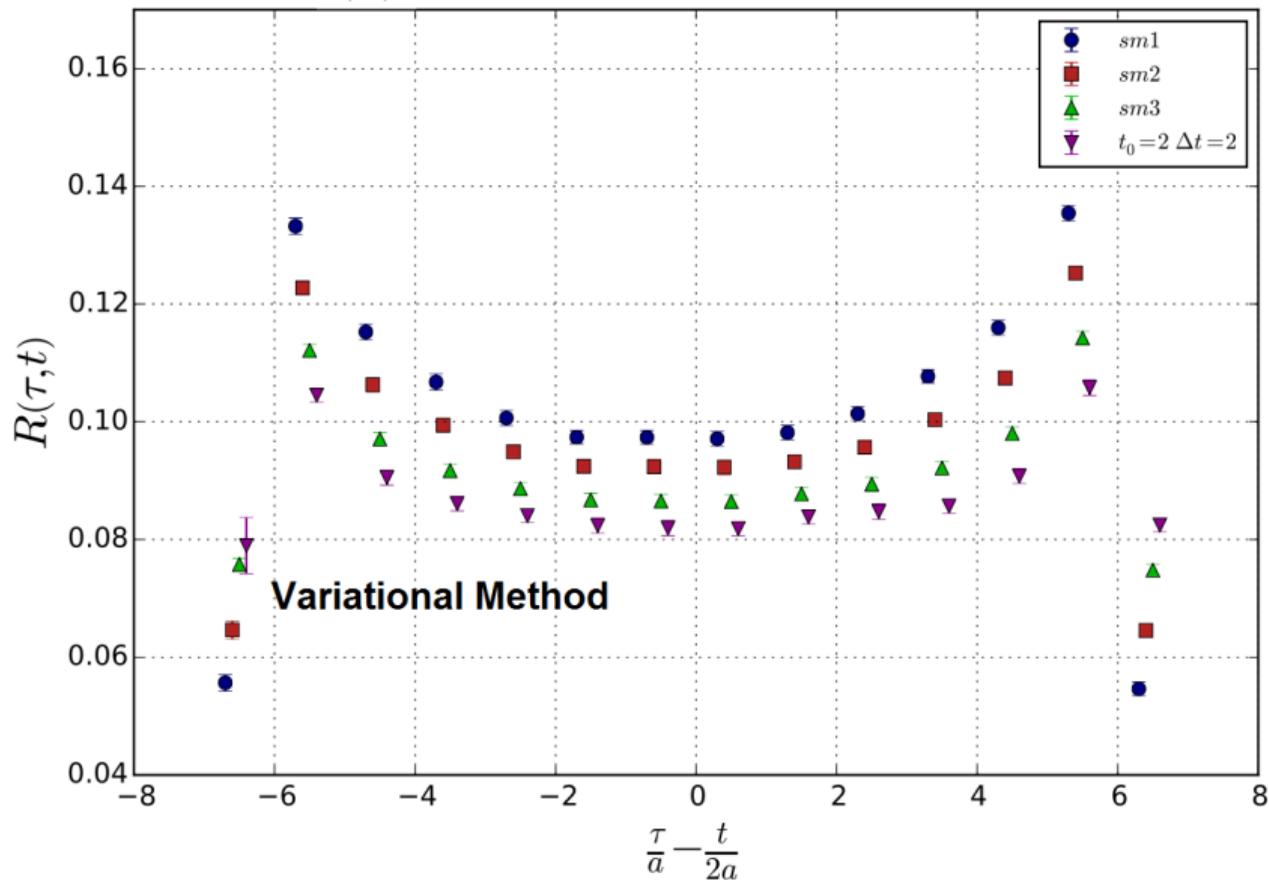


\tilde{g}_A Variational Sink Time Comparison

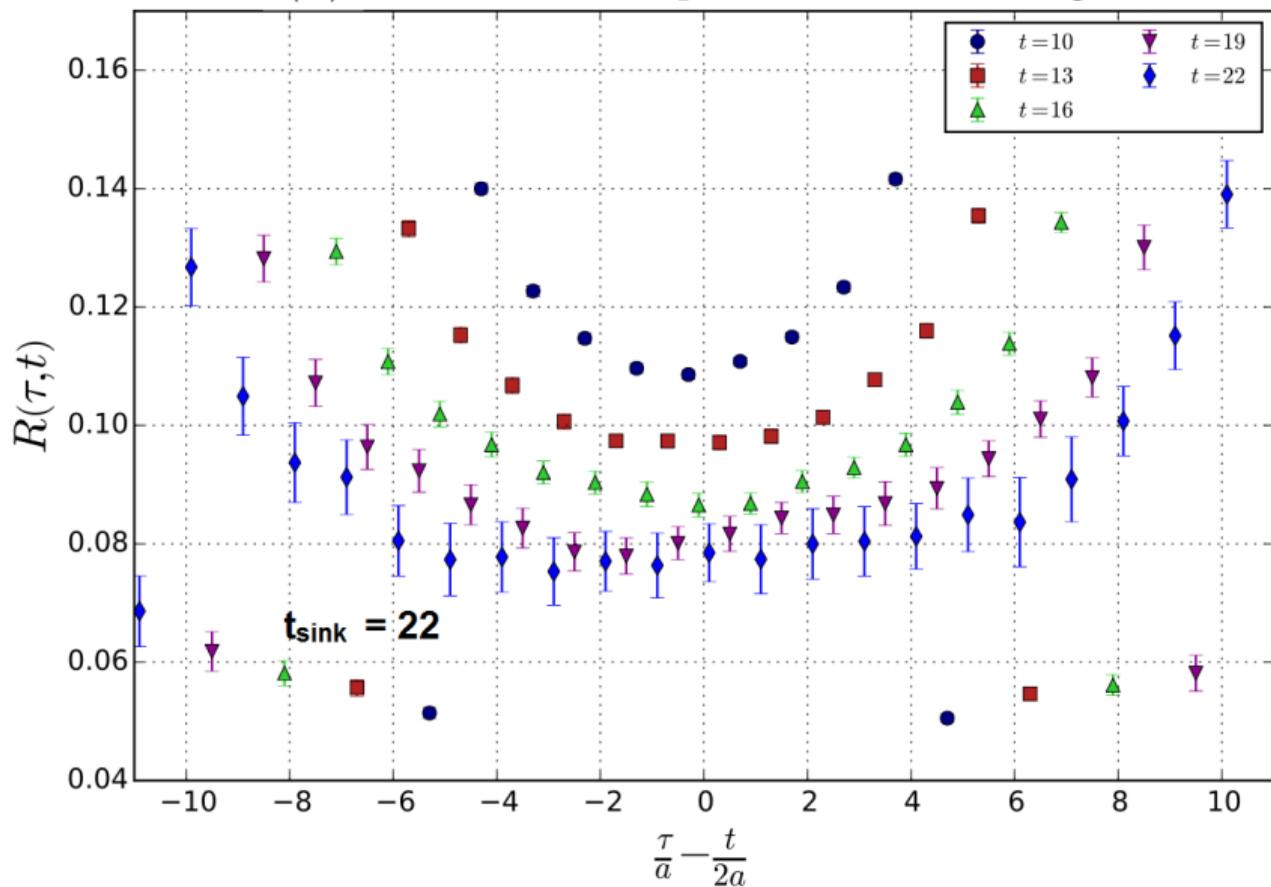


\tilde{g}_A Summary

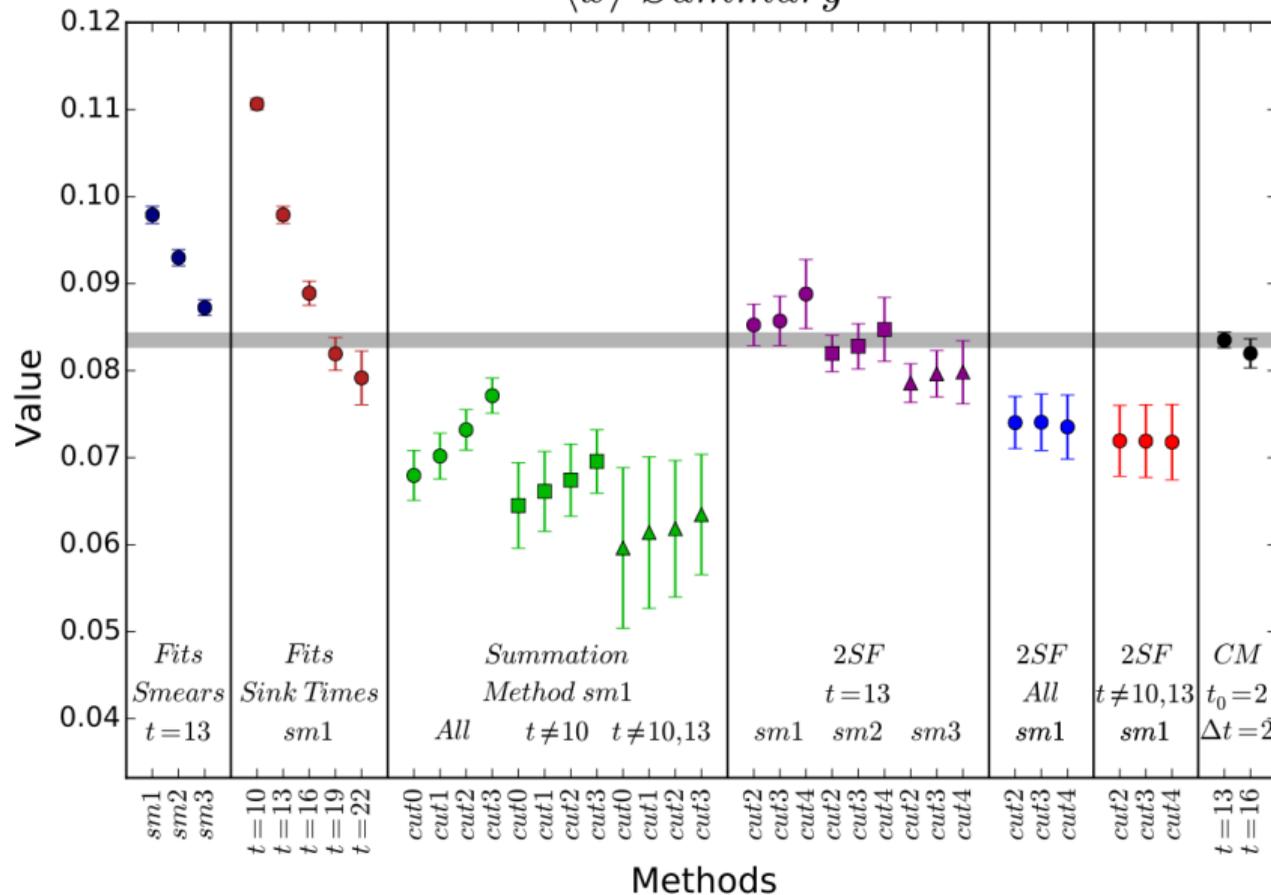
$\langle \tilde{x} \rangle$ Variational Comparison $t=13$

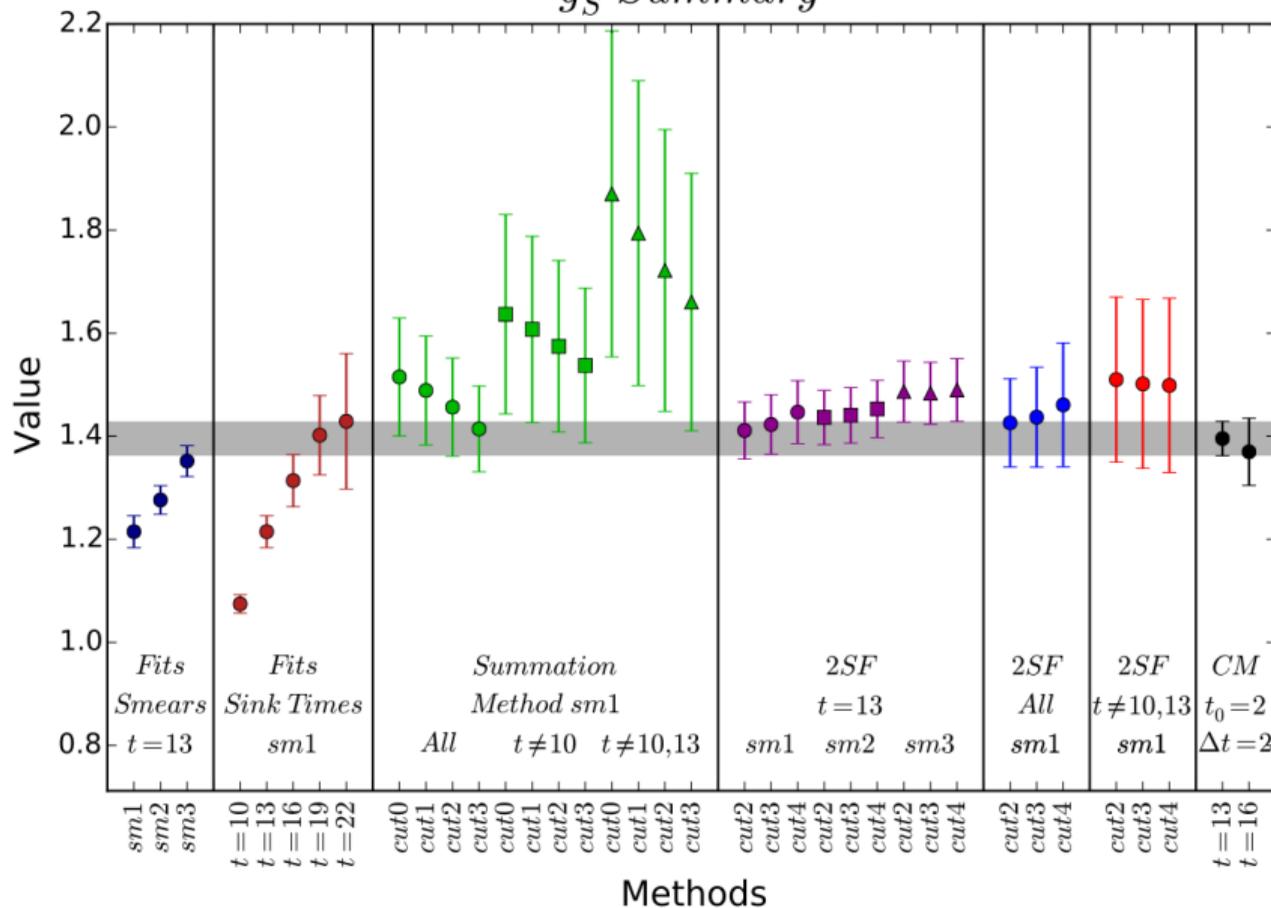


$\langle \tilde{x} \rangle$ Sink Time Comparison 32Smearing



$\langle \tilde{x} \rangle$ Summary



\tilde{g}_S Summary

Form Factors

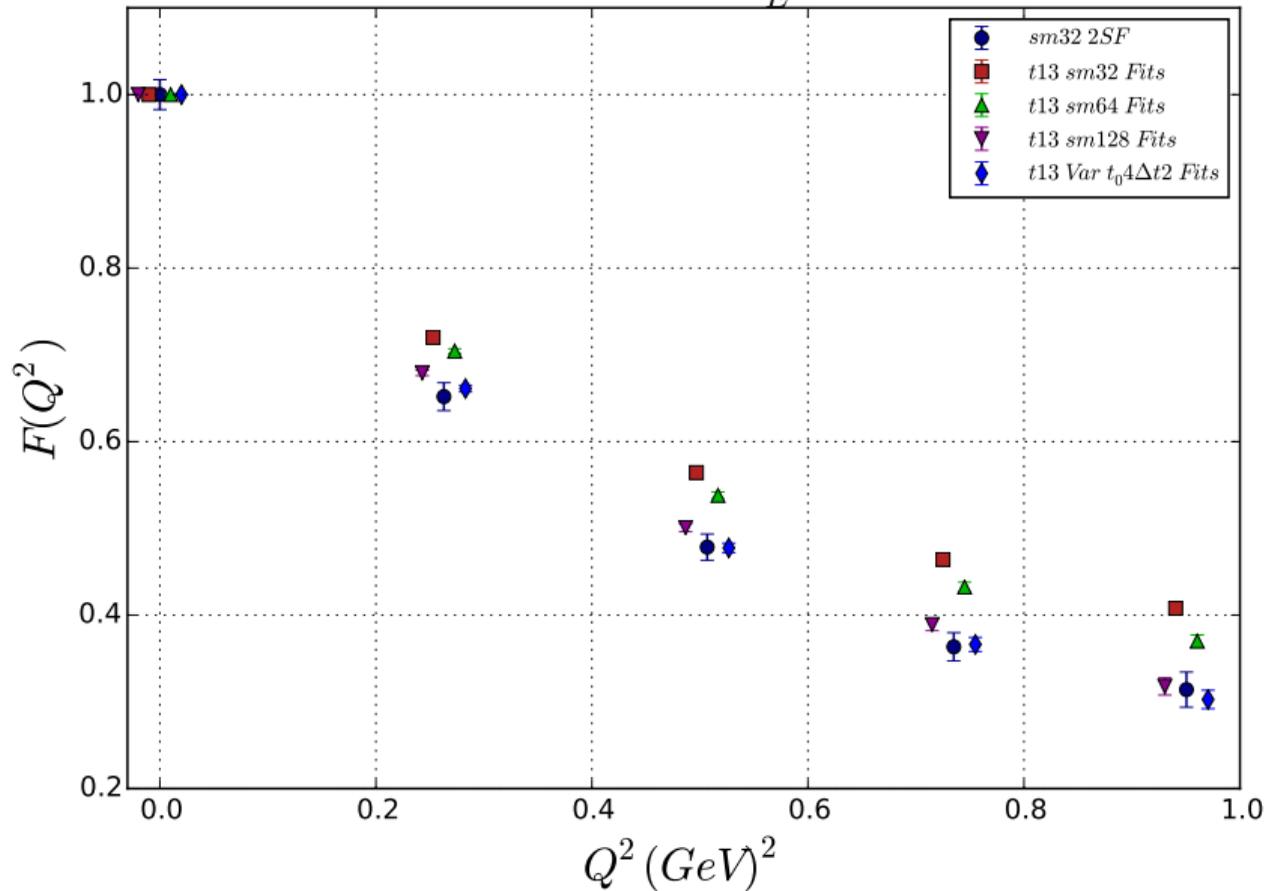
- No disconnected quark loop contributions for proton and neutron combinations.
- Solve system of equations for $\gamma_\mu / \gamma_5\gamma_\mu$, Γ and \vec{q} in q^2

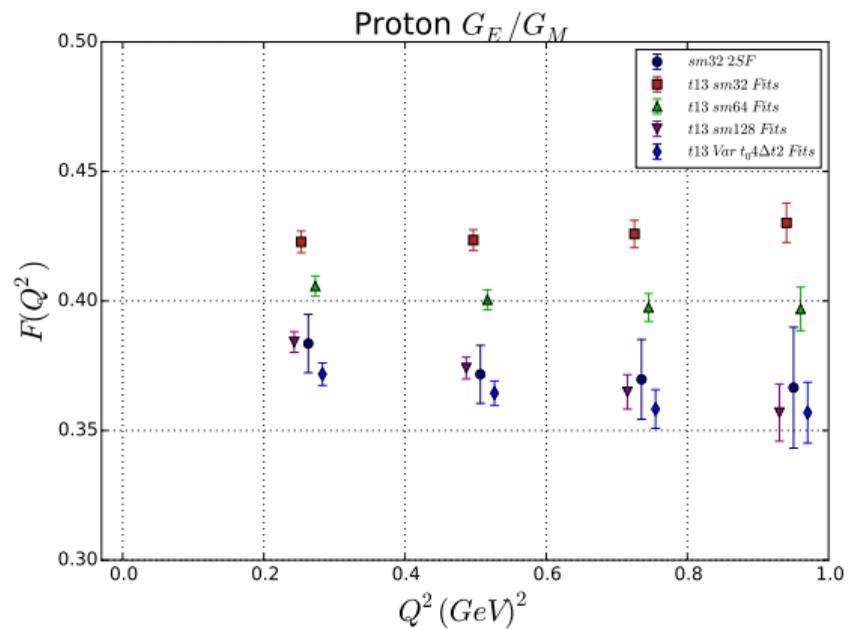
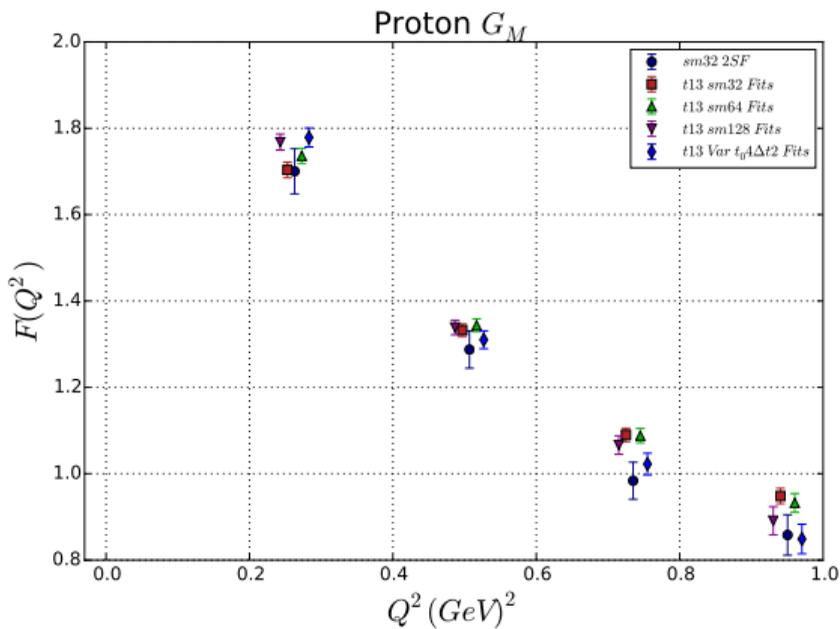
$$\mathcal{A}_E G_E(q^2) + \mathcal{A}_M G_M(q^2) = R(\Gamma; \vec{0}, t; \vec{q}, \tau; \bar{u}\gamma_\mu u),$$

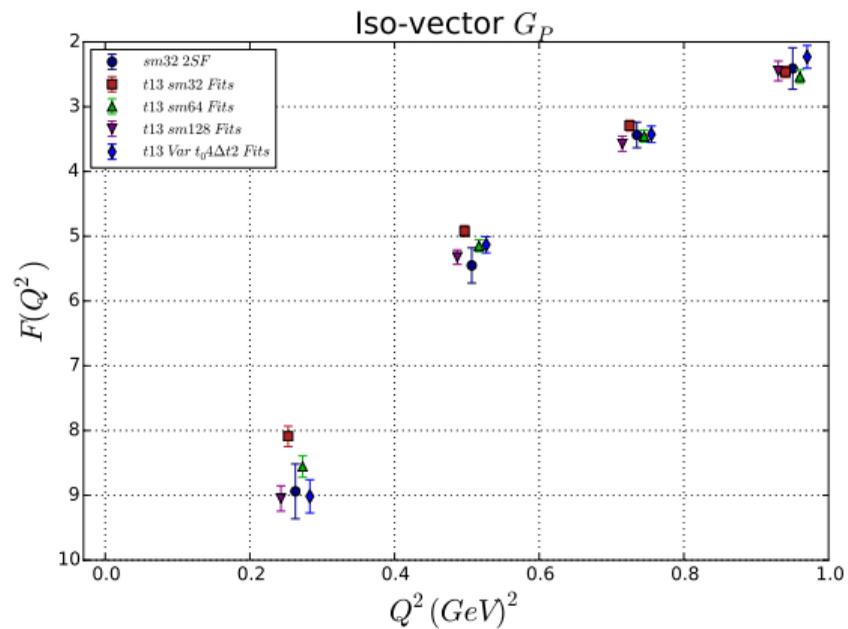
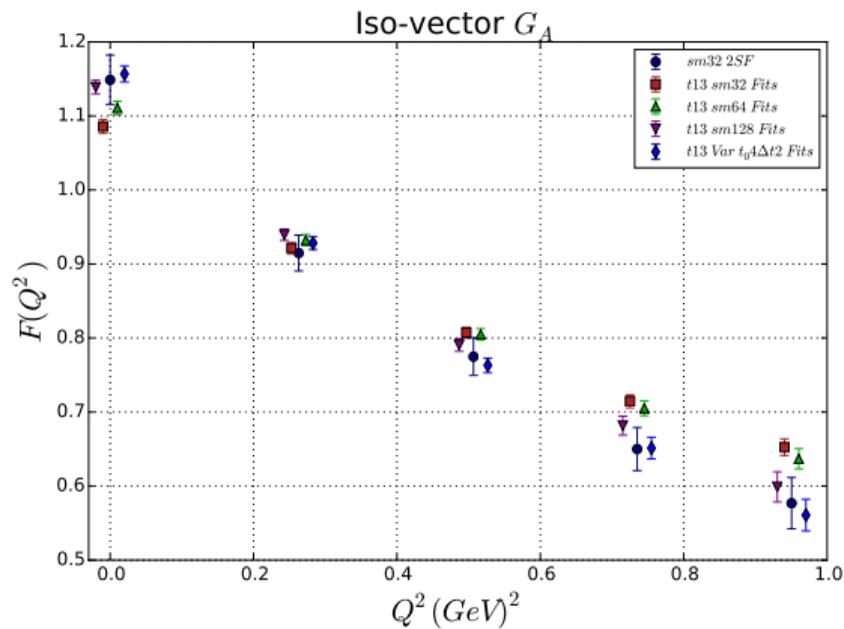
$$\mathcal{A}_A G_A(q^2) + \mathcal{A}_P G_P(q^2) = R(\Gamma; \vec{0}, t; \vec{q}, \tau; \bar{u}\gamma_5\gamma_\mu u),$$

- Comparing the excited-state contamination effects by comparing:
 - ▶ 32, 64, 128 sweeps of smearing at $t = 13$
 - ▶ Variational method at $t = 13$
 - ▶ Two-exponential fit method over 32 sweeps of smearing using $t = 10, 13, 16, 19, 22$

Proton G_E







Summary

- We have systematically undertaken all 3 methods in this analysis.
- Variational method can reach the ground state solution by optimising our interpolating fields.
- The two-state fit and summation methods are sufficient for removing “*minimal*” excited-state contamination.
- Careful consideration is needed when analysing correlators with insufficient source-sink separations.
- Excited-state systematics is crucial if we hope to undertake precise calculations of:
 - ▶ Form factors at larger Q^2
 - ▶ Complicated operators $O^{(q)} = \bar{q}\gamma_{\mu_1} D_{\mu_2} \cdots D_{\mu_n} q$

Cost/Benefit Discussion

- The biggest contributor to calculation time is associated with matrix inversions.
- Assume we use the same number of gauge fields per calculation.
- Creating a G_2 requires 1 set of inversion for a point to all propagator.
- Creating a G_3 requires $4\vec{p}'$ sets of inversions to account for up/down quark contributions and spin projections.

Create	Standard	2exp & SM (over n_t)	CM (over n_{basis})
C_2	1	1	n_{basis}
C_3	4	$4n_t$	$4n_{basis}$
Total	5	$1 + 4n_t$	$5n_{basis}$
This Work	5	21	15

Pencil of Function

- A Pencil of Function can be utilised as shown in Phys. Rev. D 90, 074507 (2014) J. R. Green et al.
- As done in the variational method, we create a matrix of 2 point correlators of the form:

$$G_2(\vec{p}, t) = \begin{bmatrix} (G_2)_{ij}(\vec{p}, t) & (G_2)_{ij}(\vec{p}, t + \delta) \\ (G_2)_{ij}(\vec{p}, t + \delta) & (G_2)_{ij}(\vec{p}, t + 2\delta) \end{bmatrix}_{kl} .$$

- We can visualise the above equation as a block matrix equation, with indices running over both the sink shifts kl and the smearings ij .

