

Polynomials associated to graphs, matroids, and configurations

Mathias Schulze

joint work with

Graham Denham, Delphine Pol, Uli Walther

AG Algebra Geometry and Computer Algebra
FB Mathematik, TU Kaiserslautern

March 22, 2019

“The Mathematics of Linear Relations between Feynman Integrals”
workshop at MITP

Graphs and spanning trees

We consider (connected) **graphs** $G = (V, E)$ with **vertex** set V and **edge** set E .

Graphs and spanning trees

We consider (connected) **graphs** $G = (V, E)$ with **vertex** set V and **edge** set E .
Multiple edges and **loops** are allowed.

Graphs and spanning trees

We consider (connected) **graphs** $G = (V, E)$ with **vertex** set V and **edge** set E . **Multiple edges** and **loops** are allowed. Subgraphs are edge-induced.

Graphs and spanning trees

We consider (connected) **graphs** $G = (V, E)$ with **vertex** set V and **edge** set E . **Multiple edges** and **loops** are allowed. Subgraphs are edge-induced.

Definition

- A **tree** T is an acyclic connected graph.

Graphs and spanning trees

We consider (connected) **graphs** $G = (V, E)$ with **vertex** set V and **edge** set E . **Multiple edges** and **loops** are allowed. Subgraphs are edge-induced.

Definition

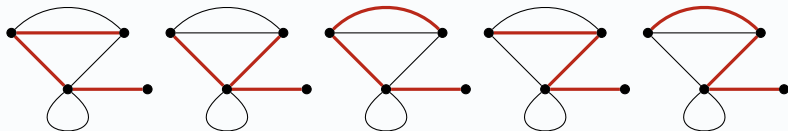
- A **tree** T is an acyclic connected graph.
- A **spanning tree** is a tree subgraph T of G with same vertex set V .

Graphs and spanning trees

We consider (connected) **graphs** $G = (V, E)$ with **vertex** set V and **edge** set E . **Multiple edges** and **loops** are allowed. Subgraphs are edge-induced.

Definition

- A **tree** T is an acyclic connected graph.
- A **spanning tree** is a tree subgraph T of G with same vertex set V .

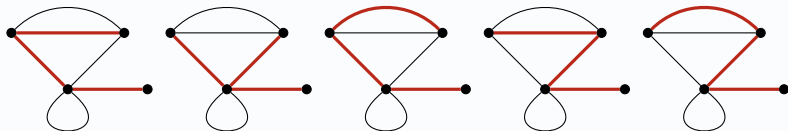


Graphs and spanning trees

We consider (connected) **graphs** $G = (V, E)$ with **vertex** set V and **edge** set E . **Multiple edges** and **loops** are allowed. Subgraphs are edge-induced.

Definition

- A **tree** T is an acyclic connected graph.
- A **spanning tree** is a tree subgraph T of G with same vertex set V .



- Write \mathcal{T}_G for the set of all spanning trees of G .

Kirchhoff's theorem

Definition

Let $G = (V, E)$ be a graph.

Kirchhoff's theorem

Definition

Let $G = (V, E)$ be a graph. Choose an **orientation** of the edges.

Kirchhoff's theorem

Definition

Let $G = (V, E)$ be a graph. Choose an **orientation** of the edges.

- The **incidence matrix** $\delta \in \mathbb{Z}^{V \times E}$ records ± 1 for head/tail of each edge.

Kirchhoff's theorem

Definition

Let $G = (V, E)$ be a graph. Choose an **orientation** of the edges.

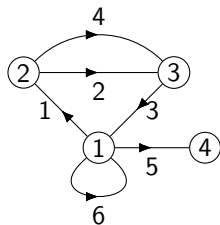
- The **incidence matrix** $\delta \in \mathbb{Z}^{V \times E}$ records ± 1 for head/tail of each edge.
- The **Laplacian matrix** is $L = \delta \delta^t \in \mathbb{Z}^{V \times V}$.

Kirchhoff's theorem

Definition

Let $G = (V, E)$ be a graph. Choose an **orientation** of the edges.

- The **incidence matrix** $\delta \in \mathbb{Z}^{V \times E}$ records ± 1 for head/tail of each edge.
- The **Laplacian matrix** is $L = \delta \delta^t \in \mathbb{Z}^{V \times V}$.

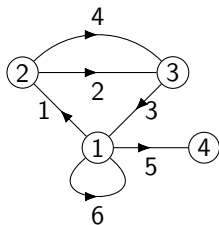


Kirchhoff's theorem

Definition

Let $G = (V, E)$ be a graph. Choose an **orientation** of the edges.

- The **incidence matrix** $\delta \in \mathbb{Z}^{V \times E}$ records ± 1 for head/tail of each edge.
- The **Laplacian matrix** is $L = \delta \delta^t \in \mathbb{Z}^{V \times V}$.



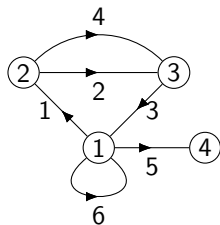
$$\delta = \begin{pmatrix} -1 & 0 & 1 & 0 & -1 & 0 \\ 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix}$$

Kirchhoff's theorem

Definition

Let $G = (V, E)$ be a graph. Choose an **orientation** of the edges.

- The **incidence matrix** $\delta \in \mathbb{Z}^{V \times E}$ records ± 1 for head/tail of each edge.
- The **Laplacian matrix** is $L = \delta \delta^t \in \mathbb{Z}^{V \times V}$.



$$\delta = \begin{pmatrix} -1 & 0 & 1 & 0 & -1 & 0 \\ 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix}$$

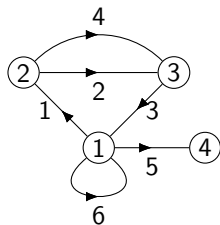
$$L = \begin{pmatrix} 3 & -1 & -1 & -1 \\ -1 & 3 & -2 & 0 \\ -1 & -2 & 3 & 0 \\ -1 & 0 & 0 & 1 \end{pmatrix}$$

Kirchhoff's theorem

Definition

Let $G = (V, E)$ be a graph. Choose an **orientation** of the edges.

- The **incidence matrix** $\delta \in \mathbb{Z}^{V \times E}$ records ± 1 for head/tail of each edge.
- The **Laplacian matrix** is $L = \delta\delta^t \in \mathbb{Z}^{V \times V}$.



$$\delta = \begin{pmatrix} -1 & 0 & 1 & 0 & -1 & 0 \\ 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix} =: \begin{pmatrix} * \\ * \\ A \\ * \end{pmatrix}$$

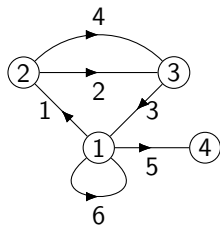
$$L = \begin{pmatrix} 3 & -1 & -1 & -1 \\ -1 & 3 & -2 & 0 \\ -1 & -2 & 3 & 0 \\ -1 & 0 & 0 & 1 \end{pmatrix} = \begin{pmatrix} * & * \\ * & AA^t \end{pmatrix}$$

Kirchhoff's theorem

Definition

Let $G = (V, E)$ be a graph. Choose an **orientation** of the edges.

- The **incidence matrix** $\delta \in \mathbb{Z}^{V \times E}$ records ± 1 for head/tail of each edge.
- The **Laplacian matrix** is $L = \delta\delta^t \in \mathbb{Z}^{V \times V}$.



$$\delta = \begin{pmatrix} -1 & 0 & 1 & 0 & -1 & 0 \\ 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix} =: \begin{pmatrix} * \\ A \end{pmatrix}$$

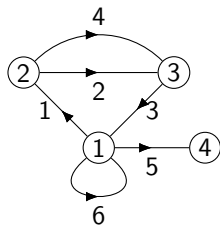
$$L = \begin{pmatrix} 3 & -1 & -1 & -1 \\ -1 & 3 & -2 & 0 \\ -1 & -2 & 3 & 0 \\ -1 & 0 & 0 & 1 \end{pmatrix} = \begin{pmatrix} * & * \\ * & AA^t \end{pmatrix}, \det AA^t = 5.$$

Kirchhoff's theorem

Definition

Let $G = (V, E)$ be a graph. Choose an **orientation** of the edges.

- The **incidence matrix** $\delta \in \mathbb{Z}^{V \times E}$ records ± 1 for head/tail of each edge.
- The **Laplacian matrix** is $L = \delta\delta^t \in \mathbb{Z}^{V \times V}$.



$$\delta = \begin{pmatrix} -1 & 0 & 1 & 0 & -1 & 0 \\ 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix} =: \begin{pmatrix} * \\ * \\ A \\ * \end{pmatrix}$$

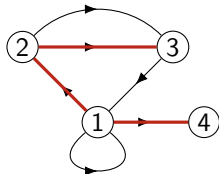
$$L = \begin{pmatrix} 3 & -1 & -1 & -1 \\ -1 & 3 & -2 & 0 \\ -1 & -2 & 3 & 0 \\ -1 & 0 & 0 & 1 \end{pmatrix} = \begin{pmatrix} * & * & * & * \\ * & AA^t & * & * \end{pmatrix}, \det AA^t = 5.$$

Kirchhoff's matrix-tree theorem

The number of spanning trees of G equals $\det AA^t$.

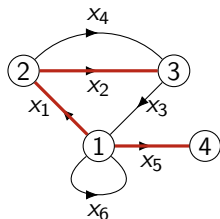
Graph polynomial

To see the individual spanning trees



Graph polynomial

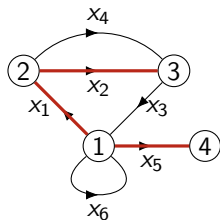
To see the **individual spanning trees**, associate **variables** with the edges.



Graph polynomial

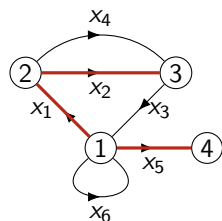
To see the **individual spanning trees**, associate **variables** with the edges.

$$X := \begin{pmatrix} x_1 & & 0 \\ & \ddots & \\ 0 & & x_6 \end{pmatrix}$$



Graph polynomial

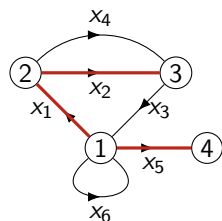
To see the **individual spanning trees**, associate **variables** with the edges.



$$X := \begin{pmatrix} x_1 & & 0 \\ & \ddots & \\ 0 & & x_6 \end{pmatrix}, \quad A = \begin{pmatrix} 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix}$$

Graph polynomial

To see the **individual spanning trees**, associate **variables** with the edges.

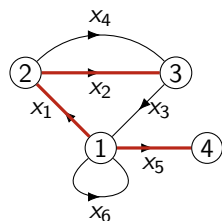


$$X := \begin{pmatrix} x_1 & & 0 \\ & \ddots & \\ 0 & & x_6 \end{pmatrix}, \quad A = \begin{pmatrix} 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix}$$

$$Q := AXA^t$$

Graph polynomial

To see the **individual spanning trees**, associate **variables** with the edges.

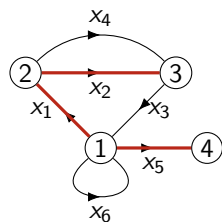


$$X := \begin{pmatrix} x_1 & & 0 \\ & \ddots & \\ 0 & & x_6 \end{pmatrix}, \quad A = \begin{pmatrix} 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix}$$

$$Q := AXA^t = \begin{pmatrix} x_1 + x_2 + x_4 & -x_2 - x_4 & 0 \\ -x_2 - x_4 & x_2 + x_3 + x_4 & 0 \\ 0 & 0 & x_5 \end{pmatrix}$$

Graph polynomial

To see the **individual spanning trees**, associate **variables** with the edges.



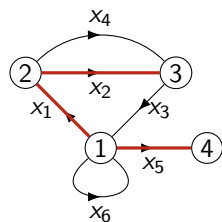
$$X := \begin{pmatrix} x_1 & & 0 \\ & \ddots & \\ 0 & & x_6 \end{pmatrix}, \quad A = \begin{pmatrix} 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix}$$

$$Q := AXA^t = \begin{pmatrix} x_1 + x_2 + x_4 & -x_2 - x_4 & 0 \\ -x_2 - x_4 & x_2 + x_3 + x_4 & 0 \\ 0 & 0 & x_5 \end{pmatrix}$$

$$\psi_G := \det Q$$

Graph polynomial

To see the **individual spanning trees**, associate **variables** with the edges.



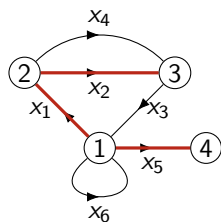
$$X := \begin{pmatrix} x_1 & & 0 \\ & \ddots & \\ 0 & & x_6 \end{pmatrix}, \quad A = \begin{pmatrix} 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix}$$

$$Q := AXA^t = \begin{pmatrix} x_1 + x_2 + x_4 & -x_2 - x_4 & 0 \\ -x_2 - x_4 & x_2 + x_3 + x_4 & 0 \\ 0 & 0 & x_5 \end{pmatrix}$$

$$\psi_G := \det Q = (x_1 x_2 + x_1 x_3 + x_1 x_4 + x_2 x_3 + x_3 x_4) x_5$$

Graph polynomial

To see the **individual spanning trees**, associate **variables** with the edges.



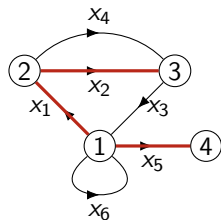
$$X := \begin{pmatrix} x_1 & & 0 \\ & \ddots & \\ 0 & & x_6 \end{pmatrix}, \quad A = \begin{pmatrix} 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix}$$

$$Q := AXA^t = \begin{pmatrix} x_1 + x_2 + x_4 & -x_2 - x_4 & 0 \\ -x_2 - x_4 & x_2 + x_3 + x_4 & 0 \\ 0 & 0 & x_5 \end{pmatrix}$$

$$\begin{aligned} \psi_G &:= \det Q = (x_1 x_2 + x_1 x_3 + x_1 x_4 + x_2 x_3 + x_3 x_4) x_5 \\ &= \sum_{T \in \mathcal{T}_G} x^T \end{aligned}$$

Graph polynomial

To see the **individual spanning trees**, associate **variables** with the edges.



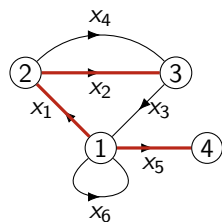
$$X := \begin{pmatrix} x_1 & & 0 \\ & \ddots & \\ 0 & & x_6 \end{pmatrix}, \quad A = \begin{pmatrix} 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix}$$

$$Q := AXA^t = \begin{pmatrix} x_1 + x_2 + x_4 & -x_2 - x_4 & 0 \\ -x_2 - x_4 & x_2 + x_3 + x_4 & 0 \\ 0 & 0 & x_5 \end{pmatrix}$$

$$\begin{aligned} \psi_G &:= \det Q = (x_1 x_2 + x_1 x_3 + x_1 x_4 + x_2 x_3 + x_3 x_4) x_5 \\ &= \sum_{T \in \mathcal{T}_G} x^T = (x_1 x'_2 + x_1 x_3 + x'_2 x_3) x_5, \quad x'_2 = x_2 + x_4 \end{aligned}$$

Graph polynomial

To see the **individual spanning trees**, associate **variables** with the edges.



$$X := \begin{pmatrix} x_1 & & 0 \\ & \ddots & \\ 0 & & x_6 \end{pmatrix}, \quad A = \begin{pmatrix} 1 & -1 & 0 & -1 & 0 & 0 \\ 0 & 1 & -1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \end{pmatrix}$$

$$Q := AXA^t = \begin{pmatrix} x_1 + x_2 + x_4 & -x_2 - x_4 & 0 \\ -x_2 - x_4 & x_2 + x_3 + x_4 & 0 \\ 0 & 0 & x_5 \end{pmatrix}$$

$$\begin{aligned} \psi_G &:= \det Q = (x_1 x_2 + x_1 x_3 + x_1 x_4 + x_2 x_3 + x_3 x_4) x_5 \\ &= \sum_{T \in \mathcal{T}_G} x^T = (x_1 x'_2 + x_1 x_3 + x'_2 x_3) x_5, \quad x'_2 = x_2 + x_4 \end{aligned}$$

Definition

ψ_G is the (first) graph polynomial or Kirchhoff polynomial of G .

Motivation

Fact

Graph polynomials are important in the case of [Feynman diagrams](#).

Motivation

Fact

Graph polynomials are important in the case of [Feynman diagrams](#).

Goal

Understand the [elementary algebraic geometry](#) of the [graph hypersurface](#) defined by the graph polynomial.

Motivation

Fact

Graph polynomials are important in the case of **Feynman diagrams**.

Goal

Understand the **elementary algebraic geometry** of the **graph hypersurface** defined by the graph polynomial.

Question

What is the **singular locus** of the graph hypersurface?

Motivation

Fact

Graph polynomials are important in the case of **Feynman diagrams**.

Goal

Understand the **elementary algebraic geometry** of the **graph hypersurface** defined by the graph polynomial.

Question

What is the **singular locus** of the graph hypersurface?

Marcolli:

“Graph hypersurfaces tend to have **singularity loci of small codimension**.”

Approach

Generalization

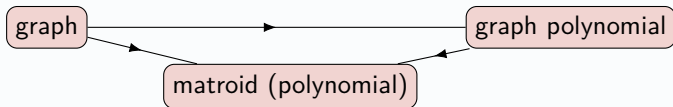
graph



graph polynomial

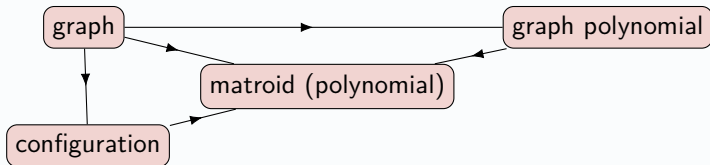
Approach

Generalization



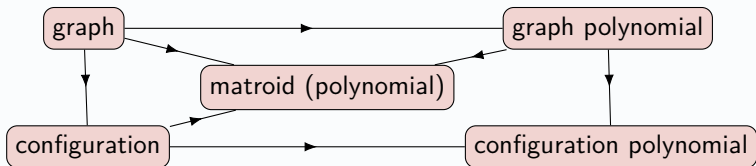
Approach

Generalization



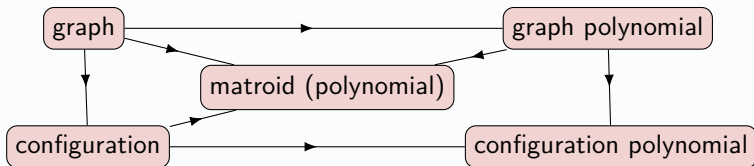
Approach

Generalization



Approach

Generalization

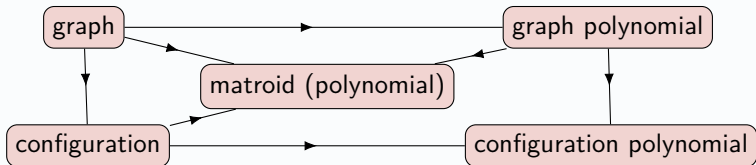


Reasoning

- Matroids have **richer structure** than graphs such as **matroid duality**. (Only plane graphs have a dual graph.)

Approach

Generalization

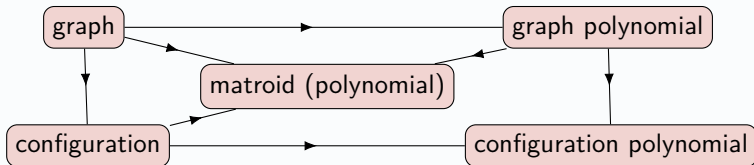


Reasoning

- Matroids have **richer structure** than graphs such as **matroid duality**. (Only plane graphs have a dual graph.)
- The (first) **Symanzik polynomial** is the dual matroid polynomial of ψ_G .

Approach

Generalization

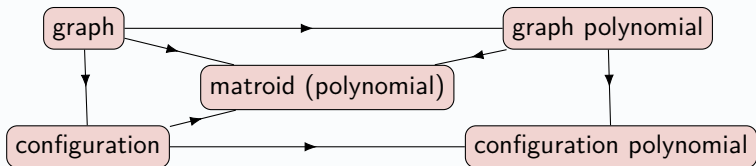


Reasoning

- Matroids have **richer structure** than graphs such as **matroid duality**. (Only plane graphs have a dual graph.)
- The **(first) Symanzik polynomial** is the dual matroid polynomial of ψ_G .
- Configuration hypersurfaces have **better geometric features**.

Approach

Generalization



Reasoning

- Matroids have **richer structure** than graphs such as **matroid duality**. (Only plane graphs have a dual graph.)
- The **(first) Symanzik polynomial** is the dual matroid polynomial of ψ_G .
- Configuration hypersurfaces have **better geometric features**.
- The **second “graph polynomial”** is only a configuration polynomial.

From graphs to configurations

Fix a field \mathbb{K} .

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & &
 \end{array}$$

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & & \\
 \\
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & & & \swarrow & & \swarrow & & & & \\
 & & & & & & W_G & & & &
 \end{array}$$

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & & \\
 \\
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & & & \swarrow & & \downarrow & & \swarrow & & \\
 & & & & & & W_G & \xleftarrow[\mathbb{K}]{A^t} & \mathbb{K}^V \setminus \{v_1\} & & \\
 & & & & & & & & \swarrow & & \\
 & & & & & & & & 0 & &
 \end{array}$$

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & & \\
 \\
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & & & \downarrow & & \downarrow & & \swarrow & & \\
 & & & & \mathbb{K}^T & \xleftarrow{\varphi_T} & W_G & \xleftarrow{\frac{A^t}{\mathbb{R}}} & \mathbb{K}^V \setminus \{v_1\} & & \\
 & & & & & & & & \swarrow & & \\
 & & & & & & & & 0 & &
 \end{array}$$

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & & \\
 \\
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & & & \downarrow & & \downarrow & & \swarrow & & \\
 & & & & \mathbb{K}^T & \xleftarrow{\varphi_T} & W_G & \xleftarrow{\frac{A^t}{\mathbb{R}}} & \mathbb{K}^{V \setminus \{v_1\}} & & \\
 & & & & & & & & \swarrow & & \\
 & & & & & & & & 0 & &
 \end{array}$$

Then $T \subseteq E$ is acyclic

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & &
 \end{array}$$

$$\begin{array}{ccccccc}
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & & & \downarrow & \swarrow & \downarrow & \swarrow & \searrow & & \\
 & & & & \mathbb{K}^T & \xleftarrow{\varphi_T} & W_G & \xleftarrow{\frac{A^t}{\mathbb{R}}} & \mathbb{K}^V \setminus \{v_1\} & & \\
 & & & & & & & & \swarrow & & \\
 & & & & & & & & 0 & &
 \end{array}$$

Then $T \subseteq E$ is acyclic $\iff H_1 \cap \mathbb{K}^T = 0$

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & &
 \end{array}$$

$$\begin{array}{ccccccccccc}
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & \downarrow & & \downarrow & \swarrow & \downarrow & \swarrow & \searrow & & \\
 0 & \longleftarrow & (H_1 \cap \mathbb{K}^T)^\vee & \longleftarrow & \mathbb{K}^T & \xleftarrow{\varphi_T} & W_G & \xleftarrow{\frac{A^t}{\mathbb{R}}} & \mathbb{K}^V \setminus \{v_1\} & \xleftarrow{0} &
 \end{array}$$

Then $T \subseteq E$ is acyclic $\iff H_1 \cap \mathbb{K}^T = 0$

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & &
 \end{array}$$

$$\begin{array}{ccccccccccc}
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & \downarrow & & \downarrow & \swarrow & \downarrow & \swarrow & \downarrow & \searrow & \\
 0 & \longleftarrow & (H_1 \cap \mathbb{K}^T)^V & \longleftarrow & \mathbb{K}^T & \xleftarrow{\varphi_T} & W_G & \xleftarrow[\cong]{A^t} & \mathbb{K}^V \setminus \{v_1\} & \xleftarrow{0} &
 \end{array}$$

Then $T \subseteq E$ is acyclic $\iff H_1 \cap \mathbb{K}^T = 0 \iff \varphi_T$ surjective.

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & & \\
 \\
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & \downarrow & & \downarrow & \swarrow & \downarrow & \swarrow & \downarrow & & \\
 0 & \longleftarrow & (H_1 \cap \mathbb{K}^T)^\vee & \longleftarrow & \mathbb{K}^T & \xleftarrow{\varphi_T} & W_G & \xleftarrow[\cong]{A^t} & \mathbb{K}^{\setminus \{v_1\}} & \xleftarrow{0} & 0
 \end{array}$$

Then $T \subseteq E$ is acyclic $\iff H_1 \cap \mathbb{K}^T = 0 \iff \varphi_T$ surjective.

Definition (Bloch-Esnault-Kreimer)

- We call a subspace $W \subseteq \mathbb{K}^E$ of a based vector space a **configuration**.

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & &
 \end{array}$$

$$\begin{array}{ccccccccccc}
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & \downarrow & & \downarrow & \swarrow & \downarrow & \swarrow & \downarrow & & \\
 0 & \longleftarrow & (H_1 \cap \mathbb{K}^T)^V & \longleftarrow & \mathbb{K}^T & \xleftarrow{\varphi_T} & W_G & \xleftarrow[\cong]{A^t} & \mathbb{K}^{\setminus \{v_1\}} & \xleftarrow{0} & 0
 \end{array}$$

Then $T \subseteq E$ is acyclic $\iff H_1 \cap \mathbb{K}^T = 0 \iff \varphi_T$ surjective.

Definition (Bloch-Esnault-Kreimer)

- We call a subspace $W \subseteq \mathbb{K}^E$ of a based vector space a **configuration**.
- Define a **matroid** M_W :

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & &
 \end{array}$$

$$\begin{array}{ccccccc}
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & \downarrow & & \downarrow & \swarrow & \downarrow & \swarrow & \searrow & & \\
 0 & \longleftarrow & (H_1 \cap \mathbb{K}^T)^V & \longleftarrow & \mathbb{K}^T & \xleftarrow{\varphi_T} & W_G & \xleftarrow[\cong]{A^t} & \mathbb{K}^{V \setminus \{v_1\}} & \xleftarrow{0} &
 \end{array}$$

Then $T \subseteq E$ is acyclic $\iff H_1 \cap \mathbb{K}^T = 0 \iff \varphi_T$ surjective.

Definition (Bloch-Esnault-Kreimer)

- We call a subspace $W \subseteq \mathbb{K}^E$ of a based vector space a **configuration**.
- Define a **matroid** M_W : $I \subseteq E$ independent $\iff \varphi_I: W \rightarrow \mathbb{K}^I$ surjective.

From graphs to configurations

Fix a field \mathbb{K} . There is a short exact sequence, and its (exact) dual sequence:

$$\begin{array}{ccccccc}
 0 & \longrightarrow & H_1 & \longrightarrow & \mathbb{K}^E & \xrightarrow{\delta} & \mathbb{K}^V & \longrightarrow & H_0 & \longrightarrow & 0 \\
 & & \parallel & & \cup & & \cup & & \parallel & & \\
 & & \langle 1_C \mid C \text{ cycle} \rangle_{\mathbb{K}} & & (s \rightarrow t) & \longmapsto & t - s & & \mathbb{K} & & \\
 & & & & & & \cup & & \cup & & \\
 & & & & & & v & \longmapsto & 1 & &
 \end{array}$$

$$\begin{array}{ccccccc}
 0 & \longleftarrow & H^1 & \longleftarrow & \mathbb{K}^E & \xleftarrow{\delta^V} & \mathbb{K}^V & \xleftarrow{v_1} & \mathbb{K} & \longleftarrow & 0 \\
 & & \downarrow & & \downarrow & \swarrow & \downarrow & \searrow & \downarrow & & \\
 0 & \longleftarrow & (H_1 \cap \mathbb{K}^T)^V & \longleftarrow & \mathbb{K}^T & \xleftarrow{\varphi_T} & W_G & \xleftarrow{\cong} & \mathbb{K}^{\setminus \{v_1\}} & \xleftarrow{0} &
 \end{array}$$

Then $T \subseteq E$ is acyclic $\iff H_1 \cap \mathbb{K}^T = 0 \iff \varphi_T$ surjective.

Definition (Bloch-Esnault-Kreimer)

- We call a subspace $W \subseteq \mathbb{K}^E$ of a based vector space a **configuration**.
- Define a **matroid** M_W : $I \subseteq E$ independent $\iff \varphi_I: W \rightarrow \mathbb{K}^I$ surjective.
- Conversely, we call W a **realization** of M_W over \mathbb{K} .

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

- $r(A \cup B) + r(A \cap B) \leq r(A) + r(B)$ (**submodularity**),

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

- $r(A \cup B) + r(A \cap B) \leq r(A) + r(B)$ (**submodularity**),
- $A \subseteq B \implies r(A) \leq r(B) \leq r(E) =: \text{rk } M$ (**monotony**).

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

- $r(A \cup B) + r(A \cap B) \leq r(A) + r(B)$ (**submodularity**),
- $A \subseteq B \implies r(A) \leq r(B) \leq r(E) =: \text{rk } M$ (**monotony**).

Each of the following pieces of data equivalently defines the matroid:

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

- $r(A \cup B) + r(A \cap B) \leq r(A) + r(B)$ (**submodularity**),
- $A \subseteq B \implies r(A) \leq r(B) \leq r(E) =: \text{rk } M$ (**monotony**).

Each of the following pieces of data equivalently defines the matroid:

- $\mathcal{I}_M = \{I \subseteq E \mid \text{rk}_M(I) = |I|\}$ (**independent sets**)

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

- $r(A \cup B) + r(A \cap B) \leq r(A) + r(B)$ (**submodularity**),
- $A \subseteq B \implies r(A) \leq r(B) \leq r(E) =: \text{rk } M$ (**monotony**).

Each of the following pieces of data equivalently defines the matroid:

- $\mathcal{I}_M = \{I \subseteq E \mid \text{rk}_M(I) = |I|\}$ (**independent sets**)
- $\mathcal{B}_M = \text{Max } \mathcal{I}_M = \{B \in \mathcal{I}_M \mid \text{rk}_M(B) = \text{rk } M\}$ (**bases**)

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

- $r(A \cup B) + r(A \cap B) \leq r(A) + r(B)$ (**submodularity**),
- $A \subseteq B \implies r(A) \leq r(B) \leq r(E) =: \text{rk } M$ (**monotony**).

Each of the following pieces of data equivalently defines the matroid:

- $\mathcal{I}_M = \{I \subseteq E \mid \text{rk}_M(I) = |I|\}$ (**independent sets**)
- $\mathcal{B}_M = \text{Max } \mathcal{I}_M = \{B \in \mathcal{I}_M \mid \text{rk}_M(B) = \text{rk } M\}$ (**bases**)
- $\mathcal{C}_M = \text{Min}(2^E \setminus \mathcal{I}_M)$ (**circuits**)

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

- $r(A \cup B) + r(A \cap B) \leq r(A) + r(B)$ (**submodularity**),
- $A \subseteq B \implies r(A) \leq r(B) \leq r(E) =: \text{rk } M$ (**monotony**).

Each of the following pieces of data equivalently defines the matroid:

- $\mathcal{I}_M = \{I \subseteq E \mid \text{rk}_M(I) = |I|\}$ (**independent sets**)
- $\mathcal{B}_M = \text{Max } \mathcal{I}_M = \{B \in \mathcal{I}_M \mid \text{rk}_M(B) = \text{rk } M\}$ (**bases**)
- $\mathcal{C}_M = \text{Min}(2^E \setminus \mathcal{I}_M)$ (**circuits**)

Example

A graph G defines a **graphic matroid** $M_G := M_{W_G}$

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

- $r(A \cup B) + r(A \cap B) \leq r(A) + r(B)$ (**submodularity**),
- $A \subseteq B \implies r(A) \leq r(B) \leq r(E) =: \text{rk } M$ (**monotony**).

Each of the following pieces of data equivalently defines the matroid:

- $\mathcal{I}_M = \{I \subseteq E \mid \text{rk}_M(I) = |I|\}$ (**independent sets**)
- $\mathcal{B}_M = \text{Max } \mathcal{I}_M = \{B \in \mathcal{I}_M \mid \text{rk}_M(B) = \text{rk } M\}$ (**bases**)
- $\mathcal{C}_M = \text{Min}(2^E \setminus \mathcal{I}_M)$ (**circuits**)

Example

A graph G defines a **graphic matroid** $M_G := M_{W_G}$, where

$$\mathcal{I}_{M_G} = \{\text{acyclic subgraphs}\}$$

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

- $r(A \cup B) + r(A \cap B) \leq r(A) + r(B)$ (**submodularity**),
- $A \subseteq B \implies r(A) \leq r(B) \leq r(E) =: \text{rk } M$ (**monotony**).

Each of the following pieces of data equivalently defines the matroid:

- $\mathcal{I}_M = \{I \subseteq E \mid \text{rk}_M(I) = |I|\}$ (**independent sets**)
- $\mathcal{B}_M = \text{Max } \mathcal{I}_M = \{B \in \mathcal{I}_M \mid \text{rk}_M(B) = \text{rk } M\}$ (**bases**)
- $\mathcal{C}_M = \text{Min}(2^E \setminus \mathcal{I}_M)$ (**circuits**)

Example

A graph G defines a **graphic matroid** $M_G := M_{W_G}$, where

$$\mathcal{I}_{M_G} = \{\text{acyclic subgraphs}\}, \quad \mathcal{B}_{M_G} = \mathcal{T}_G$$

Matroid basics

Matroids axiomatize **finite sets of vectors (configurations)** in a vector space.

Definition

A **matroid** M on a finite set E is defined by a **rank function** $r = \text{rk}_M: 2^E \rightarrow \mathbb{N}$:

- $r(A \cup B) + r(A \cap B) \leq r(A) + r(B)$ (**submodularity**),
- $A \subseteq B \implies r(A) \leq r(B) \leq r(E) =: \text{rk } M$ (**monotony**).

Each of the following pieces of data equivalently defines the matroid:

- $\mathcal{I}_M = \{I \subseteq E \mid \text{rk}_M(I) = |I|\}$ (**independent sets**)
- $\mathcal{B}_M = \text{Max } \mathcal{I}_M = \{B \in \mathcal{I}_M \mid \text{rk}_M(B) = \text{rk } M\}$ (**bases**)
- $\mathcal{C}_M = \text{Min}(2^E \setminus \mathcal{I}_M)$ (**circuits**)

Example

A graph G defines a **graphic matroid** $M_G := M_{W_G}$, where
 $\mathcal{I}_{M_G} = \{\text{acyclic subgraphs}\}$, $\mathcal{B}_{M_G} = \mathcal{T}_G$, $\mathcal{C}_{M_G} = \{\text{simple cycles}\}$.

Matroid and configuration hypersurface

Let M be a matroid and $W \subseteq \mathbb{K}^E$.

Matroid and configuration hypersurface

Let M be a matroid and $W \subseteq \mathbb{K}^E$. Fix coordinates $x = (x_e)_{e \in E}$ by $x_e := e^\vee$.

Matroid and configuration hypersurface

Let M be a matroid and $W \subseteq \mathbb{K}^E$. Fix coordinates $x = (x_e)_{e \in E}$ by $x_e := e^\vee$.

Definition

- $\psi_M := \sum_{B \in \mathcal{B}_M} x^B$ is the **matroid polynomial** of M .

Matroid and configuration hypersurface

Let M be a matroid and $W \subseteq \mathbb{K}^E$. Fix coordinates $x = (x_e)_{e \in E}$ by $x_e := e^\vee$.

Definition

- $\psi_M := \sum_{B \in \mathcal{B}_M} x^B$ is the **matroid polynomial** of M .
- $c_B := (\det(W \rightarrow \mathbb{K}^B))^2 \in \mathbb{K}^*$ for $B \in \mathcal{B}_{M_W}$.

Matroid and configuration hypersurface

Let M be a matroid and $W \subseteq \mathbb{K}^E$. Fix coordinates $x = (x_e)_{e \in E}$ by $x_e := e^\vee$.

Definition

- $\psi_M := \sum_{B \in \mathcal{B}_M} x^B$ is the **matroid polynomial** of M .
- $c_B := (\det(W \rightarrow \mathbb{K}^B))^2 \in \mathbb{K}^*$ for $B \in \mathcal{B}_{M_W}$.
- $\psi_W := \sum_{B \in \mathcal{B}_{M_W}} c_B x^B$ is the **configuration polynomial** of W .

Matroid and configuration hypersurface

Let M be a matroid and $W \subseteq \mathbb{K}^E$. Fix coordinates $x = (x_e)_{e \in E}$ by $x_e := e^\vee$.

Definition

- $\psi_M := \sum_{B \in \mathcal{B}_M} x^B$ is the **matroid polynomial** of M .
- $c_B := (\det(W \rightarrow \mathbb{K}^B))^2 \in \mathbb{K}^*$ for $B \in \mathcal{B}_{M_W}$.
- $\psi_W := \sum_{B \in \mathcal{B}_{M_W}} c_B x^B$ is the **configuration polynomial** of W .

Remark

- $\psi_G = \psi_{M_G} = \psi_{W_G}$ is both a matroid and configuration polynomial.

Matroid and configuration hypersurface

Let M be a matroid and $W \subseteq \mathbb{K}^E$. Fix coordinates $x = (x_e)_{e \in E}$ by $x_e := e^\vee$.

Definition

- $\psi_M := \sum_{B \in \mathcal{B}_M} x^B$ is the **matroid polynomial** of M .
- $c_B := (\det(W \rightarrow \mathbb{K}^B))^2 \in \mathbb{K}^*$ for $B \in \mathcal{B}_{M_W}$.
- $\psi_W := \sum_{B \in \mathcal{B}_{M_W}} c_B x^B$ is the **configuration polynomial** of W .

Remark

- $\psi_G = \psi_{M_G} = \psi_{W_G}$ is both a matroid and configuration polynomial.
- More generally, $\psi_W = \psi_M$ for regular M (up to scaling variables).

Matroid and configuration hypersurface

Let M be a matroid and $W \subseteq \mathbb{K}^E$. Fix coordinates $x = (x_e)_{e \in E}$ by $x_e := e^\vee$.

Definition

- $\psi_M := \sum_{B \in \mathcal{B}_M} x^B$ is the **matroid polynomial** of M .
- $c_B := (\det(W \rightarrow \mathbb{K}^B))^2 \in \mathbb{K}^*$ for $B \in \mathcal{B}_{M_W}$.
- $\psi_W := \sum_{B \in \mathcal{B}_{M_W}} c_B x^B$ is the **configuration polynomial** of W .

Remark

- $\psi_G = \psi_{M_G} = \psi_{W_G}$ is both a matroid and configuration polynomial.
- More generally, $\psi_W = \psi_M$ for regular M (up to scaling variables).

Definition

- $X_M := \text{Spec}(\mathbb{K}[x]/\langle \psi_M \rangle)$ is the **matroid hypersurface** of M .

Matroid and configuration hypersurface

Let M be a matroid and $W \subseteq \mathbb{K}^E$. Fix coordinates $x = (x_e)_{e \in E}$ by $x_e := e^\vee$.

Definition

- $\psi_M := \sum_{B \in \mathcal{B}_M} x^B$ is the **matroid polynomial** of M .
- $c_B := (\det(W \rightarrow \mathbb{K}^B))^2 \in \mathbb{K}^*$ for $B \in \mathcal{B}_{M_W}$.
- $\psi_W := \sum_{B \in \mathcal{B}_{M_W}} c_B x^B$ is the **configuration polynomial** of W .

Remark

- $\psi_G = \psi_{M_G} = \psi_{W_G}$ is both a matroid and configuration polynomial.
- More generally, $\psi_W = \psi_M$ for regular M (up to scaling variables).

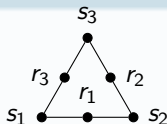
Definition

- $X_M := \text{Spec}(\mathbb{K}[x]/\langle \psi_M \rangle)$ is the **matroid hypersurface** of M .
- $X_W := \text{Spec}(\mathbb{K}[x]/\langle \psi_W \rangle)$ is the **configuration hypersurface** of W .

Configuration polynomial vs. matroid polynomial

Example

The 3-whirl matroid W^3 is realized by 6 points in \mathbb{P}^2 with depicted collinearities.

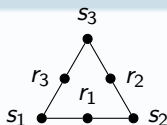


Configuration polynomial vs. matroid polynomial

Example

The 3-whirl matroid W^3 is realized by 6 points in \mathbb{P}^2 with depicted collinearities.

It is connected but not regular (since $U_{2,4}$ is a minor).

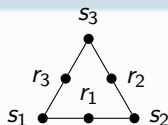


Configuration polynomial vs. matroid polynomial

Example

The 3-whirl matroid W^3 is realized by 6 points in \mathbb{P}^2 with depicted collinearities.

It is connected but not regular (since $U_{2,4}$ is a minor).



A realization $W \subseteq \mathbb{K}\{s_1, s_2, s_3, r_1, r_2, r_3\}$ of W^3 is given by the row span of

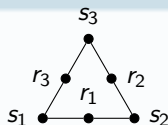
$$A = \begin{pmatrix} 1 & 0 & 0 & 1 & 0 & +1 \\ 0 & 1 & 0 & -1 & 1 & 0 \\ 0 & 0 & 1 & 0 & -1 & 1 \end{pmatrix}$$

Configuration polynomial vs. matroid polynomial

Example

The **3-whirl matroid** W^3 is realized by 6 points in \mathbb{P}^2 with depicted collinearities.

It is connected but not regular (since $U_{2,4}$ is a minor).



A realization $W \subseteq \mathbb{K}\{s_1, s_2, s_3, r_1, r_2, r_3\}$ of W^3 is given by the row span of

$$A = \begin{pmatrix} 1 & 0 & 0 & 1 & 0 & +1 \\ 0 & 1 & 0 & -1 & 1 & 0 \\ 0 & 0 & 1 & 0 & -1 & 1 \end{pmatrix}$$

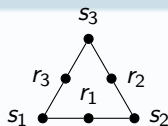
Replacing $+$ by $-$
makes a (graphic)
3-wheel matroid W_3 .

Configuration polynomial vs. matroid polynomial

Example

The **3-whirl matroid** W^3 is realized by 6 points in \mathbb{P}^2 with depicted collinearities.

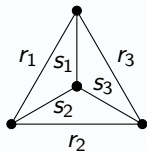
It is connected but not regular (since $U_{2,4}$ is a minor).



A realization $W \subseteq \mathbb{K}\{s_1, s_2, s_3, r_1, r_2, r_3\}$ of W^3 is given by the row span of

$$A = \begin{pmatrix} 1 & 0 & 0 & 1 & 0 & +1 \\ 0 & 1 & 0 & -1 & 1 & 0 \\ 0 & 0 & 1 & 0 & -1 & 1 \end{pmatrix}$$

Replacing $+$ by $-$ makes a (graphic) **3-wheel matroid** W_3 .

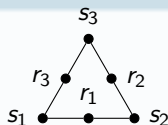


Configuration polynomial vs. matroid polynomial

Example

The **3-whirl matroid** W^3 is realized by 6 points in \mathbb{P}^2 with depicted collinearities.

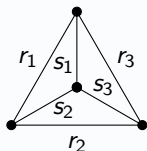
It is connected but not regular (since $U_{2,4}$ is a minor).



A realization $W \subseteq \mathbb{K}\{s_1, s_2, s_3, r_1, r_2, r_3\}$ of W^3 is given by the row span of

$$A = \begin{pmatrix} 1 & 0 & 0 & 1 & 0 & +1 \\ 0 & 1 & 0 & -1 & 1 & 0 \\ 0 & 0 & 1 & 0 & -1 & 1 \end{pmatrix}$$

Replacing $+$ by $-$ makes a (graphic) **3-wheel matroid** W_3 .



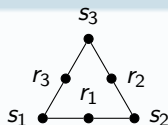
$$\psi_W = x_1x_2x_3 + x_1x_3x_4 + x_2x_3x_4 + x_1x_2x_5 + x_1x_3x_5 + x_1x_4x_5 + x_2x_4x_5 + x_3x_4x_5 + x_1x_2x_6 + x_2x_3x_6 + x_1x_4x_6 + x_2x_4x_6 + x_3x_4x_6 + x_1x_5x_6 + x_2x_5x_6 + x_3x_5x_6 + 4x_4x_5x_6$$

Configuration polynomial vs. matroid polynomial

Example

The **3-whirl matroid** W^3 is realized by 6 points in \mathbb{P}^2 with depicted collinearities.

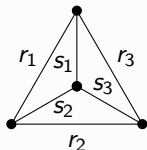
It is connected but not regular (since $U_{2,4}$ is a minor).



A realization $W \subseteq \mathbb{K}\{s_1, s_2, s_3, r_1, r_2, r_3\}$ of W^3 is given by the row span of

$$A = \begin{pmatrix} 1 & 0 & 0 & 1 & 0 & +1 \\ 0 & 1 & 0 & -1 & 1 & 0 \\ 0 & 0 & 1 & 0 & -1 & 1 \end{pmatrix}$$

Replacing $+$ by $-$ makes a (graphic) **3-wheel matroid** W_3 .



$$\psi_W = x_1x_2x_3 + x_1x_3x_4 + x_2x_3x_4 + x_1x_2x_5 + x_1x_3x_5 + x_1x_4x_5 + x_2x_4x_5 + x_3x_4x_5 + x_1x_2x_6 + x_2x_3x_6 + x_1x_4x_6 + x_2x_4x_6 + x_3x_4x_6 + x_1x_5x_6 + x_2x_5x_6 + x_3x_5x_6 + 4x_4x_5x_6$$

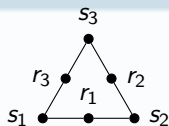
W^3 is not realizable over \mathbb{F}_2 .

Configuration polynomial vs. matroid polynomial

Example

The **3-whirl matroid** W^3 is realized by 6 points in \mathbb{P}^2 with depicted collinearities.

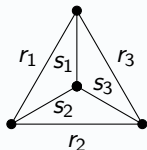
It is connected but not regular (since $U_{2,4}$ is a minor).



A realization $W \subseteq \mathbb{K}\{s_1, s_2, s_3, r_1, r_2, r_3\}$ of W^3 is given by the row span of

$$A = \begin{pmatrix} 1 & 0 & 0 & 1 & 0 & +1 \\ 0 & 1 & 0 & -1 & 1 & 0 \\ 0 & 0 & 1 & 0 & -1 & 1 \end{pmatrix}$$

Replacing $+$ by $-$ makes a (graphic) **3-wheel matroid** W_3 .



$$\psi_W = x_1x_2x_3 + x_1x_3x_4 + x_2x_3x_4 + x_1x_2x_5 + x_1x_3x_5 + x_1x_4x_5 + x_2x_4x_5 + x_3x_4x_5 + x_1x_2x_6 + x_2x_3x_6 + x_1x_4x_6 + x_2x_4x_6 + x_3x_4x_6 + x_1x_5x_6 + x_2x_5x_6 + x_3x_5x_6 + 4x_4x_5x_6$$

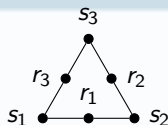
W^3 is not realizable over \mathbb{F}_2 . ψ_{W^3} looks the same with **4** replaced by **1**.

Configuration polynomial vs. matroid polynomial

Example

The 3-whirl matroid W^3 is realized by 6 points in \mathbb{P}^2 with depicted collinearities.

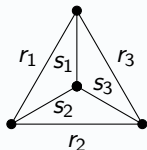
It is connected but not regular (since $U_{2,4}$ is a minor).



A realization $W \subseteq \mathbb{K}\{s_1, s_2, s_3, r_1, r_2, r_3\}$ of W^3 is given by the row span of

$$A = \begin{pmatrix} 1 & 0 & 0 & 1 & 0 & +1 \\ 0 & 1 & 0 & -1 & 1 & 0 \\ 0 & 0 & 1 & 0 & -1 & 1 \end{pmatrix}$$

Replacing $+$ by $-$ makes a (graphic) 3-wheel matroid W_3 .



$$\psi_W = x_1x_2x_3 + x_1x_3x_4 + x_2x_3x_4 + x_1x_2x_5 + x_1x_3x_5 + x_1x_4x_5 + x_2x_4x_5 + x_3x_4x_5 + x_1x_2x_6 + x_2x_3x_6 + x_1x_4x_6 + x_2x_4x_6 + x_3x_4x_6 + x_1x_5x_6 + x_2x_5x_6 + x_3x_5x_6 + 4x_4x_5x_6$$

W^3 is not realizable over \mathbb{F}_2 . ψ_{W^3} looks the same with 4 replaced by 1.

X_W has (maximal) codimension 3 singular locus in \mathbb{K}^6 , for X_M it is 4.

Matroid connectivity and irreducibility

Definition

A matroid M on E is **connected** if it is not a proper direct sum of matroids.

Matroid connectivity and irreducibility

Definition

A matroid M on E is **connected** if it is not a proper direct sum of matroids.

Remark

- Connectivity is the equivalence relation **induced by circuits** on E .

Matroid connectivity and irreducibility

Definition

A matroid M on E is **connected** if it is not a proper direct sum of matroids.

Remark

- Connectivity is the equivalence relation **induced by circuits** on E .
- M_G is connected $\iff G$ has **no loops** and **no cut vertices**.

Matroid connectivity and irreducibility

Definition

A matroid M on E is **connected** if it is not a proper direct sum of matroids.

Remark

- Connectivity is the equivalence relation **induced by circuits** on E .
- M_G is connected $\iff G$ has **no loops** and **no cut vertices**.

Proposition (Denham-S.-Walther)

M is connected $\iff \psi_W$ irreducible and M has no loops

Matroid connectivity and irreducibility

Definition

A matroid M on E is **connected** if it is not a proper direct sum of matroids.

Remark

- Connectivity is the equivalence relation **induced by circuits** on E .
- M_G is connected $\iff G$ has **no loops** and **no cut vertices**.

Proposition (Denham-S.-Walther)

M is connected $\iff \psi_W$ irreducible and M has no loops
 $\iff X_W$ is **integral** and M has no loops.

Matroid connectivity and irreducibility

Definition

A matroid M on E is **connected** if it is not a proper direct sum of matroids.

Remark

- Connectivity is the equivalence relation **induced by circuits** on E .
- M_G is connected $\iff G$ has **no loops** and **no cut vertices**.

Proposition (Denham-S.-Walther)

M is connected $\iff \psi_W$ irreducible and M has no loops
 $\iff X_W$ is **integral** and M has no loops.

Remark

The analogous statement holds for X_M .

Configuration form

Definition

The **configuration form** of $W \subseteq \mathbb{K}^E$ is $Q_W := \sum_{e \in E} x_e \cdot e^\vee \cdot e^\vee : W \times W \rightarrow \langle x \rangle$.

Configuration form

Definition

The **configuration form** of $W \subseteq \mathbb{K}^E$ is $Q_W := \sum_{e \in E} x_e \cdot e^\vee \cdot e^\vee : W \times W \rightarrow \langle x \rangle$.

Remark

For any basis w^1, \dots, w^r of W , $r = \dim W = \text{rk } M_W$, and $A := \begin{pmatrix} w^1 \\ \vdots \\ w^r \end{pmatrix}$,

Configuration form

Definition

The **configuration form** of $W \subseteq \mathbb{K}^E$ is $Q_W := \sum_{e \in E} x_e \cdot e^\vee \cdot e^\vee : W \times W \rightarrow \langle x \rangle$.

Remark

For any basis w^1, \dots, w^r of W , $r = \dim W = \text{rk } M_W$, and $A := \begin{pmatrix} w^1 \\ \vdots \\ w^r \end{pmatrix}$,

$$Q_W = AXA^t = (\langle x, w^i \star w^j \rangle)_{i,j},$$

where \star is the **Hadamard product** (component-wise vector multiplication).

Configuration form

Definition

The **configuration form** of $W \subseteq \mathbb{K}^E$ is $Q_W := \sum_{e \in E} x_e \cdot e^\vee \cdot e^\vee : W \times W \rightarrow \langle x \rangle$.

Remark

For any basis w^1, \dots, w^r of W , $r = \dim W = \text{rk } M_W$, and $A := \begin{pmatrix} w^1 \\ \vdots \\ w^r \end{pmatrix}$,

$$Q_W = AXA^t = (\langle x, w^i \star w^j \rangle)_{i,j},$$

where \star is the **Hadamard product** (component-wise vector multiplication).

Lemma (Bloch-Esnault-Kreimer)

$$\psi_W = \det Q_W$$

Configuration form

Definition

The **configuration form** of $W \subseteq \mathbb{K}^E$ is $Q_W := \sum_{e \in E} x_e \cdot e^\vee \cdot e^\vee : W \times W \rightarrow \langle x \rangle$.

Remark

For any basis w^1, \dots, w^r of W , $r = \dim W = \text{rk } M_W$, and $A := \begin{pmatrix} w^1 \\ \vdots \\ w^r \end{pmatrix}$,

$$Q_W = AXA^t = (\langle x, w^i \star w^j \rangle)_{i,j},$$

where \star is the **Hadamard product** (component-wise vector multiplication).

Lemma (Bloch-Esnault-Kreimer)

$\psi_W = \det Q_W$, generalizing $\psi_{W_G} = \psi_G = \det Q = \det Q_{W_G}$.

Configuration hypersurface vs. matroid

Example

The **uniform matroid** $U_{3,6}$ is realized by the row span $W = \langle w^1, w^2, w^3 \rangle$ of

$$A = \begin{pmatrix} w^1 \\ w^2 \\ w^3 \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 & 1 & 2 & 3 \\ 0 & 1 & 0 & 2 & 3 & 4 \\ 0 & 0 & 1 & 2 & 6 & 12 \end{pmatrix}$$

Configuration hypersurface vs. matroid

Example

The [uniform matroid](#) $U_{3,6}$ is realized by the row span $W = \langle w^1, w^2, w^3 \rangle$ of

$$A = \begin{pmatrix} w^1 \\ w^2 \\ w^3 \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 & 1 & 2 & 3 \\ 0 & 1 & 0 & 2 & 3 & 4 \\ 0 & 0 & 1 & 2 & 6 & 12 \end{pmatrix}$$

The [Hadamard products](#) $w^i \star w^j$ are [linearly dependent](#),

Configuration hypersurface vs. matroid

Example

The **uniform matroid** $U_{3,6}$ is realized by the row span $W = \langle w^1, w^2, w^3 \rangle$ of

$$A = \begin{pmatrix} w^1 \\ w^2 \\ w^3 \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 & 1 & 2 & 3 \\ 0 & 1 & 0 & 2 & 3 & 4 \\ 0 & 0 & 1 & 2 & 6 & 12 \end{pmatrix}$$

The **Hadamard products** $w^i \star w^j$ are **linearly dependent**, so ψ_W depends only on 5 coordinates.

Configuration hypersurface vs. matroid

Example

The **uniform matroid** $U_{3,6}$ is realized by the row span $W = \langle w^1, w^2, w^3 \rangle$ of

$$A = \begin{pmatrix} w^1 \\ w^2 \\ w^3 \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 & 1 & 2 & 3 \\ 0 & 1 & 0 & 2 & 3 & 4 \\ 0 & 0 & 1 & 2 & 6 & 12 \end{pmatrix}$$

The **Hadamard products** $w^i \star w^j$ are **linearly dependent**, so ψ_W depends only on 5 coordinates. But ψ_W depends on 6 coordinates for generic W .

Configuration hypersurface vs. matroid

Example

The **uniform matroid** $U_{3,6}$ is realized by the row span $W = \langle w^1, w^2, w^3 \rangle$ of

$$A = \begin{pmatrix} w^1 \\ w^2 \\ w^3 \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 & 1 & 2 & 3 \\ 0 & 1 & 0 & 2 & 3 & 4 \\ 0 & 0 & 1 & 2 & 6 & 12 \end{pmatrix}$$

The **Hadamard products** $w^i \star w^j$ are **linearly dependent**, so ψ_W depends only on 5 coordinates. But ψ_W depends on 6 coordinates for generic W . Thus, M does not determine X_W .

Configuration hypersurface vs. matroid

Example

The **uniform matroid** $U_{3,6}$ is realized by the row span $W = \langle w^1, w^2, w^3 \rangle$ of

$$A = \begin{pmatrix} w^1 \\ w^2 \\ w^3 \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 & 1 & 2 & 3 \\ 0 & 1 & 0 & 2 & 3 & 4 \\ 0 & 0 & 1 & 2 & 6 & 12 \end{pmatrix}$$

The **Hadamard products** $w^i \star w^j$ are **linearly dependent**, so ψ_W depends only on 5 coordinates. But ψ_W depends on 6 coordinates for generic W . Thus, M does not determine X_W .

Conversely, a linear coordinate change and deleting a column of A makes ψ_W a configuration polynomial for $U_{3,5}$.

Configuration hypersurface vs. matroid

Example

The **uniform matroid** $U_{3,6}$ is realized by the row span $W = \langle w^1, w^2, w^3 \rangle$ of

$$A = \begin{pmatrix} w^1 \\ w^2 \\ w^3 \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 & 1 & 2 & 3 \\ 0 & 1 & 0 & 2 & 3 & 4 \\ 0 & 0 & 1 & 2 & 6 & 12 \end{pmatrix}$$

The **Hadamard products** $w^i \star w^j$ are **linearly dependent**, so ψ_W depends only on 5 coordinates. But ψ_W depends on 6 coordinates for generic W . Thus, M does not determine X_W .

Conversely, a linear coordinate change and deleting a column of A makes ψ_W a configuration polynomial for $U_{3,5}$.

Proposition (Delphine Pol)

rk M	1	2	3	4	where $X \sim X'$ if $X' = X \times \mathbb{K}$.
$\#\{X_W\}/\sim$	1	2	6	$\infty?$	

Jacobian and degeneracy schemes

Definition

- $J_W := \langle \psi_W, \partial_e \psi_W \mid e \in E \rangle \trianglelefteq \mathbb{K}[x]$ (Jacobian ideal)

Jacobian and degeneracy schemes

Definition

- $J_W := \langle \psi_W, \partial_e \psi_W \mid e \in E \rangle \trianglelefteq \mathbb{K}[x]$ (Jacobian ideal)
- $\Sigma_W := \text{Spec}(\mathbb{K}[x]/J_W) \subseteq \mathbb{K}^E$ (Jacobian scheme)

Jacobian and degeneracy schemes

Definition

- $J_W := \langle \psi_W, \partial_e \psi_W \mid e \in E \rangle \trianglelefteq \mathbb{K}[x]$ (Jacobian ideal)
- $\Sigma_W := \text{Spec}(\mathbb{K}[x]/J_W) \subseteq \mathbb{K}^E$ (Jacobian scheme)
- $M_W := \langle \text{submaximal minors of } Q_W \rangle \trianglelefteq \mathbb{K}[x]$ (2nd degeneracy ideal)

Jacobian and degeneracy schemes

Definition

- $J_W := \langle \psi_W, \partial_e \psi_W \mid e \in E \rangle \trianglelefteq \mathbb{K}[x]$ (Jacobian ideal)
- $\Sigma_W := \text{Spec}(\mathbb{K}[x]/J_W) \subseteq \mathbb{K}^E$ (Jacobian scheme)
- $M_W := \langle \text{submaximal minors of } Q_W \rangle \trianglelefteq \mathbb{K}[x]$ (2nd degeneracy ideal)
- $\Delta_W := \text{Spec}(\mathbb{K}[x]/M_W) \subseteq \mathbb{K}^E$ (2nd degeneracy scheme)

Jacobian and degeneracy schemes

Definition

- $J_W := \langle \psi_W, \partial_e \psi_W \mid e \in E \rangle \trianglelefteq \mathbb{K}[x]$ (Jacobian ideal)
- $\Sigma_W := \text{Spec}(\mathbb{K}[x]/J_W) \subseteq \mathbb{K}^E$ (Jacobian scheme)
- $M_W := \langle \text{submaximal minors of } Q_W \rangle \trianglelefteq \mathbb{K}[x]$ (2nd degeneracy ideal)
- $\Delta_W := \text{Spec}(\mathbb{K}[x]/M_W) \subseteq \mathbb{K}^E$ (2nd degeneracy scheme)

Theorem (Patterson)

$\Sigma_W^{\text{red}} = \Delta_W^{\text{red}}$ is the *non-smooth locus* of X_W .

Jacobian and degeneracy schemes

Definition

- $J_W := \langle \psi_W, \partial_e \psi_W \mid e \in E \rangle \trianglelefteq \mathbb{K}[x]$ (Jacobian ideal)
- $\Sigma_W := \text{Spec}(\mathbb{K}[x]/J_W) \subseteq \mathbb{K}^E$ (Jacobian scheme)
- $M_W := \langle \text{submaximal minors of } Q_W \rangle \trianglelefteq \mathbb{K}[x]$ (2nd degeneracy ideal)
- $\Delta_W := \text{Spec}(\mathbb{K}[x]/M_W) \subseteq \mathbb{K}^E$ (2nd degeneracy scheme)

Theorem (Patterson)

$\Sigma_W^{\text{red}} = \Delta_W^{\text{red}}$ is the *non-smooth locus* of X_W .

Remark

Non-smooth over an algebraically closed field \mathbb{K} means *singular*.

Jacobian and degeneracy schemes

Definition

- $J_W := \langle \psi_W, \partial_e \psi_W \mid e \in E \rangle \trianglelefteq \mathbb{K}[x]$ (Jacobian ideal)
- $\Sigma_W := \text{Spec}(\mathbb{K}[x]/J_W) \subseteq \mathbb{K}^E$ (Jacobian scheme)
- $M_W := \langle \text{submaximal minors of } Q_W \rangle \trianglelefteq \mathbb{K}[x]$ (2nd degeneracy ideal)
- $\Delta_W := \text{Spec}(\mathbb{K}[x]/M_W) \subseteq \mathbb{K}^E$ (2nd degeneracy scheme)

Theorem (Patterson)

$\Sigma_W^{\text{red}} = \Delta_W^{\text{red}}$ is the *non-smooth locus* of X_W .

Remark

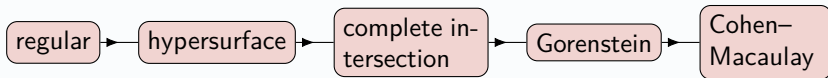
Non-smooth over an algebraically closed field \mathbb{K} means *singular*.

Theorem (Kutz)

$\text{codim}_{\mathbb{K}^E} \Delta_W \leq 3$ and equality makes Δ_W *Cohen–Macaulay*.

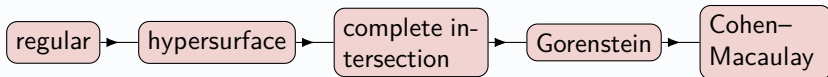
Cohen–Macaulay rings/schemes

Hierarchy of rings (commutative local/graded Noetherian)



Cohen–Macaulay rings/schemes

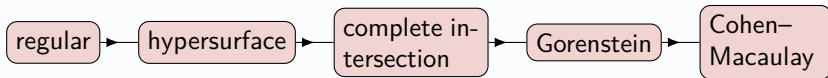
Hierarchy of rings (commutative local/graded Noetherian)



Cohen–Macaulayness \implies equidimensionality

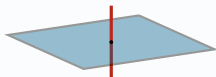
Cohen–Macaulay rings/schemes

Hierarchy of rings (commutative local/graded Noetherian)



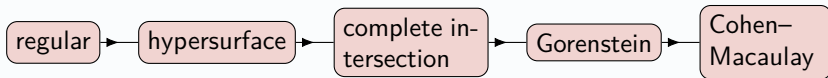
Cohen–Macaulayness \implies equidimensionality

$\mathbb{K}[x, y, z] / \underbrace{\langle xz, yz \rangle}_{\langle x, y \rangle \cap \langle z \rangle}$ is not Cohen–Macaulay.



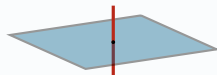
Cohen–Macaulay rings/schemes

Hierarchy of rings (commutative local/graded Noetherian)



Cohen–Macaulayness \implies equidimensionality

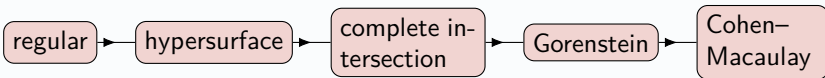
$\mathbb{K}[x, y, z] / \underbrace{\langle xz, yz \rangle}_{\langle x, y \rangle \cap \langle z \rangle}$ is not Cohen–Macaulay.



Cohen–Macaulayness \implies purity

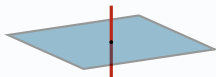
Cohen–Macaulay rings/schemes

Hierarchy of rings (commutative local/graded Noetherian)



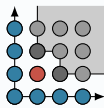
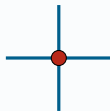
Cohen–Macaulayness \implies equidimensionality

$\mathbb{K}[x, y, z] / \underbrace{\langle xz, yz \rangle}_{\langle x, y \rangle \cap \langle z \rangle}$ is not Cohen–Macaulay.



Cohen–Macaulayness \implies purity

$\mathbb{K}[x, y] / \underbrace{\langle xy^2, x^2y \rangle}_{\langle x \rangle \cap \langle y \rangle \cap \langle x^2, y^2 \rangle}$ is not Cohen–Macaulay.



The main result

Theorem (Denham-S.-Walther)

Let M be a *(2-)connected* matroid with realization W .

The main result

Theorem (Denham-S.-Walther)

Let M be a *(2-)connected* matroid with realization W .

- Δ_W is *reduced* Cohen–Macaulay of codimension 3 in \mathbb{K}^E .

The main result

Theorem (Denham-S.-Walther)

Let M be a *(2-)connected* matroid with realization W .

- Δ_W is *reduced* Cohen–Macaulay of codimension 3 in \mathbb{K}^E .
- Σ_W is *generically reduced*, unless \mathbb{K} has characteristic 2.

The main result

Theorem (Denham-S.-Walther)

Let M be a *(2-)connected* matroid with realization W .

- Δ_W is *reduced* Cohen–Macaulay of codimension 3 in \mathbb{K}^E .
- Σ_W is *generically reduced*, unless \mathbb{K} has characteristic 2.
- If M is *3-connected*, then Δ_W is *integral* and Σ_W *irreducible*.

The main result

Theorem (Denham-S.-Walther)

Let M be a *(2-)connected* matroid with realization W .

- Δ_W is *reduced* Cohen–Macaulay of codimension 3 in \mathbb{K}^E .
- Σ_W is *generically reduced*, unless \mathbb{K} has characteristic 2.
- If M is *3-connected*, then Δ_W is *integral* and Σ_W *irreducible*.

Remark

- Δ_W is still reduced if M is connected after deleting all (co)loops.

The main result

Theorem (Denham-S.-Walther)

Let M be a *(2-)connected* matroid with realization W .

- Δ_W is *reduced* Cohen–Macaulay of codimension 3 in \mathbb{K}^E .
- Σ_W is *generically reduced*, unless \mathbb{K} has characteristic 2.
- If M is *3-connected*, then Δ_W is *integral* and Σ_W *irreducible*.

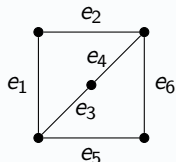
Remark

- Δ_W is still reduced if M is connected after deleting all (co)loops.
- The intersection of two different components of X_W yields components of Σ_W of codimension 2.

Embedded points in the Jacobian scheme

Example

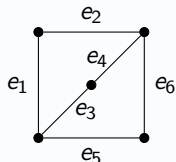
The **prism matroid** is associated to the graph



Embedded points in the Jacobian scheme

Example

The **prism matroid** is associated to the graph

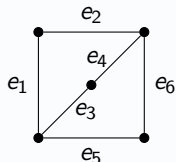


$$\begin{aligned} \psi_W = & x_1 x_2 (x_3 + x_4) (x_5 + x_6) \\ & + x_3 x_4 (x_1 + x_2) (x_5 + x_6) \\ & + x_5 x_6 (x_1 + x_2) (x_3 + x_4) \end{aligned}$$

Embedded points in the Jacobian scheme

Example

The **prism matroid** is associated to the graph



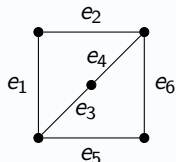
$$\begin{aligned} \psi_W = & x_1 x_2 (x_3 + x_4) (x_5 + x_6) \\ & + x_3 x_4 (x_1 + x_2) (x_5 + x_6) \\ & + x_5 x_6 (x_1 + x_2) (x_3 + x_4) \end{aligned}$$

Δ_W has 4 generic points:

Embedded points in the Jacobian scheme

Example

The **prism matroid** is associated to the graph



$$\begin{aligned} \psi_W = & x_1 x_2 (x_3 + x_4) (x_5 + x_6) \\ & + x_3 x_4 (x_1 + x_2) (x_5 + x_6) \\ & + x_5 x_6 (x_1 + x_2) (x_3 + x_4) \end{aligned}$$

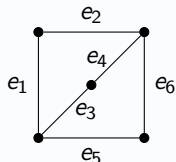
Δ_W has 4 **generic points**: $\langle x_1 + x_2, x_3 + x_4, x_5 + x_6 \rangle$ and 3 symmetric to

$$\langle x_1, x_2, \psi_{W \setminus \{1,2\}} \rangle.$$

Embedded points in the Jacobian scheme

Example

The **prism matroid** is associated to the graph



$$\begin{aligned} \psi_W &= x_1 x_2 (x_3 + x_4) (x_5 + x_6) \\ &\quad + x_3 x_4 (x_1 + x_2) (x_5 + x_6) \\ &\quad + x_5 x_6 (x_1 + x_2) (x_3 + x_4) \end{aligned}$$

Δ_W has 4 **generic points**: $\langle x_1 + x_2, x_3 + x_4, x_5 + x_6 \rangle$ and 3 symmetric to

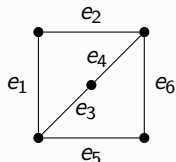
$$\langle x_1, x_2, \psi_{W \setminus \{1,2\}} \rangle.$$

In characteristic 2, Σ_W has 7 **embedded points**:

Embedded points in the Jacobian scheme

Example

The **prism matroid** is associated to the graph



$$\begin{aligned} \psi_W &= x_1 x_2 (x_3 + x_4) (x_5 + x_6) \\ &\quad + x_3 x_4 (x_1 + x_2) (x_5 + x_6) \\ &\quad + x_5 x_6 (x_1 + x_2) (x_3 + x_4) \end{aligned}$$

Δ_W has 4 **generic points**: $\langle x_1 + x_2, x_3 + x_4, x_5 + x_6 \rangle$ and 3 symmetric to

$$\langle x_1, x_2, \psi_{W \setminus \{1,2\}} \rangle.$$

In characteristic 2, Σ_W has 7 **embedded points**: 3 symmetric to each of

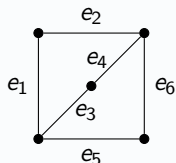
$$\langle x_3, x_4, x_5, x_6 \rangle \quad \text{and} \quad \langle x_1, x_2, x_3 + x_4, x_5 + x_6 \rangle$$

plus $\langle x_1, \dots, x_6 \rangle$.

Embedded points in the Jacobian scheme

Example

The **prism matroid** is associated to the graph



$$\begin{aligned} \psi_W &= x_1 x_2 (x_3 + x_4) (x_5 + x_6) \\ &\quad + x_3 x_4 (x_1 + x_2) (x_5 + x_6) \\ &\quad + x_5 x_6 (x_1 + x_2) (x_3 + x_4) \end{aligned}$$

Δ_W has 4 **generic points**: $\langle x_1 + x_2, x_3 + x_4, x_5 + x_6 \rangle$ and 3 symmetric to

$$\langle x_1, x_2, \psi_{W \setminus \{1,2\}} \rangle.$$

In characteristic 2, Σ_W has 7 **embedded points**: 3 symmetric to each of

$$\langle x_3, x_4, x_5, x_6 \rangle \quad \text{and} \quad \langle x_1, x_2, x_3 + x_4, x_5 + x_6 \rangle$$

plus $\langle x_1, \dots, x_6 \rangle$. Moreover, Σ_W is **not reduced** at any generic point.

Proof of the main result

Ingredients of the proof

Proof of the main result

Ingredients of the proof

- [handle decomposition](#) and lower bound for non-disconnective handles

Proof of the main result

Ingredients of the proof

- **handle decomposition** and lower bound for non-disconnective handles
- explicit calculation of **generic points**

Proof of the main result

Ingredients of the proof

- **handle decomposition** and lower bound for non-disconnective handles
- explicit calculation of **generic points**
- **Kutz's** and **Patterson's** theorems

Proof of the main result

Ingredients of the proof

- **handle decomposition** and lower bound for non-disconnective handles
- explicit calculation of **generic points**
- **Kutz's** and **Patterson's** theorems
- induction by **deletion/contraction**

Proof of the main result

Ingredients of the proof

- **handle decomposition** and lower bound for non-disconnective handles
- explicit calculation of **generic points**
- **Kutz's** and **Patterson's** theorems
- induction by **deletion/contraction**
- base cases: **circuits, prisms, wheels and whirls**

Proof of the main result

Ingredients of the proof

- **handle decomposition** and lower bound for non-disconnective handles
- explicit calculation of **generic points**
- **Kutz's** and **Patterson's** theorems
- induction by **deletion/contraction**
- base cases: **circuits**, **prisms**, **wheels and whirls**
- filtration, grading and **Rees algebra** techniques

Proof of the main result

Ingredients of the proof

- **handle decomposition** and lower bound for non-disconnective handles
- explicit calculation of **generic points**
- **Kutz's** and **Patterson's** theorems
- induction by **deletion/contraction**
- base cases: **circuits**, **prisms**, **wheels** and **whirls**
- filtration, grading and **Rees algebra** techniques
- **matroid duality**

Proof of the main result

Ingredients of the proof

- **handle decomposition** and lower bound for non-disconnective handles
- explicit calculation of **generic points**
- **Kutz's** and **Patterson's** theorems
- induction by **deletion/contraction**
- base cases: **circuits**, **prisms**, **wheels and whirls**
- filtration, grading and **Rees algebra** techniques
- **matroid duality**
- **Tutte's wheels and whirls theorem**


Proof of the main result

Ingredients of the proof


- handle decomposition and lower bound for non-disconnective handles
- explicit calculation of generic points
- Kutz's and Patterson's theorems
- induction by deletion/contraction
- base cases: circuits, prisms, wheels and whirls
- filtration, grading and Rees algebra techniques
- matroid duality
- Tutte's wheels and whirls theorem

Thank you for your attention!


Bibliography (incomplete)




Spencer Bloch, Hélène Esnault, and Dirk Kreimer. “On motives associated to graph polynomials.” In: *Comm. Math. Phys.* 267.1 (2006), pp. 181–225.



Graham Denham, Mathias Schulze, and Uli Walther. *Matroid connectivity and singularities of configuration hypersurfaces*. 2019. URL: <http://arxiv.org/abs/1902.06507>.



Ronald E. Kutz. “Cohen-Macaulay rings and ideal theory in rings of invariants of algebraic groups.” In: *Trans. Amer. Math. Soc.* 194 (1974), pp. 115–129.



Eric Patterson. “On the singular structure of graph hypersurfaces.” In: *Commun. Number Theory Phys.* 4.4 (2010), pp. 659–708.