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Factorization of Rotation and Lorentz Matrices via Euler– Olinde Rodrigues Parameters

Juan D. Bulnes[1], *Taekyun Kim*[2] *and José Luis López-Bonilla*[3,*]

[1]Departamento de Ciências Exatas e Tecnologia, Universidade Federal do Amapá, Jardim Marco Zero, 68903-419, Macapá, AP, Brazil
[2]Department of Mathematics, Kwangwoon University, Seoul 139 - 701, Republic of Korea
[3]ESIME-Zacatenco, Instituto Politécnico Nacional, Edif. 4, 1er. Piso, Col. Lindavista CP 07738, CDMX, México

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Abstract: In this paper, the factorization of 3-rotation matrices in terms of the Euler-Olinde Rodrigues parameters from the generation of Lorentz transformations through quaternions is obtained.

Keywords: Dirac equation, Euler-Olinde Rodrigues parameters, Lorentz transformations, quaternions, 3-rotations

1 Introduction

The Lorentz matrix $L = (L^{\nu}{}_{\mu})$ between the frames of reference $(x^{\mu}) = (ct, x, y, z)$ and $(\tilde{x}^{\nu})$ has six degrees of freedom:

$$\tilde{x}^{\nu} = L^{\nu}{}_{\mu}\, x^{\mu}, \tag{1}$$

and it can be generated using quaternions [1,2,3,4] via the expression [5,6,7,8,9,10]:

$$\tilde{\mathbf{X}} = \mathbf{A}\mathbf{X}\bar{\mathbf{A}}^{*}, \qquad \mathbf{X} = \frac{1}{\sqrt{2}}\left(ct - ix\mathbf{I} - iy\mathbf{J} - iz\mathbf{K}\right),$$

$$\mathbf{A} = a_0 + a_1\mathbf{I} + a_2\mathbf{J} + a_3\mathbf{K},$$

$$\bar{\mathbf{A}}^{*} = a_0^{*} - a_1^{*}\mathbf{I} - a_2^{*}\mathbf{J} - a_3^{*}\mathbf{K}, \quad a_0^2 + a_1^2 + a_2^2 + a_3^2 = 1. \tag{2}$$

The Lorentz matrix $(L^{\mu}{}_{\nu})$ accepts an interesting factorization [11] in terms of the Cayley-Klein parameters [12]. Matrix factorization is a mathematical procedure used in various situations and contexts; for example, in relation to the Helmholtz operator in mathematical physics and in the theory of differential equations [13,14,15]. Here we are interested in the factorization of an arbitrary 3-rotation matrix [16,17,18] using the Euler-Olinde Rodrigues parameters [19,20,21,22] a_{μ}, $\mu = 0, \ldots, 3$. In fact, if all a_{ν} are real, then (2) implies $\tilde{t} = t$ and:

$$\begin{pmatrix} \tilde{x} \\ \tilde{y} \\ \tilde{z} \end{pmatrix} = R \begin{pmatrix} x \\ y \\ z \end{pmatrix}, \qquad R\,R^{T} = I, \tag{3}$$

where the matrix R represents a passive rotation (in the terminology of Ryder [23]):

$$R = \begin{pmatrix} 1 - 2(a_2^2 + a_3^2) & 2(a_1a_2 - a_0a_3) & 2(a_1a_3 + a_0a_2) \\ 2(a_1a_2 + a_0a_3) & 1 - 2(a_1^2 + a_3^2) & 2(a_2a_3 - a_0a_1) \\ 2(a_1a_3 - a_0a_2) & 2(a_0a_1 + a_2a_3) & 1 - 2(a_1^2 + a_2^2) \end{pmatrix}. \tag{4}$$

2 3-Rotations

With any quaternion we can associate a 4×4 matrix, for example [24]:

$$\mathbf{X} \quad \longleftrightarrow \quad \frac{1}{\sqrt{2}} \begin{pmatrix} ct & -ix & -iy & -iz \\ ix & ct & iz & -iy \\ iy & -iz & ct & ix \\ iz & iy & -ix & ct \end{pmatrix},$$

$$\mathbf{A} \quad \longleftrightarrow \quad \begin{pmatrix} a_0 & a_1 & a_2 & a_3 \\ -a_1 & a_0 & -a_3 & a_2 \\ -a_2 & a_3 & a_0 & -a_1 \\ -a_3 & -a_2 & a_1 & a_0 \end{pmatrix}, \tag{5}$$

* Corresponding author e-mail: jlopezb@ipn.mx

then (2), in the form $\bar{\mathbf{A}}\tilde{\mathbf{X}} = \mathbf{X}\bar{\mathbf{A}}$, and (5) imply:

$$\begin{pmatrix} a_0 & -a_1 & -a_2 & -a_3 \\ a_1 & a_0 & a_3 & -a_2 \\ a_2 & -a_3 & a_0 & a_1 \\ a_3 & a_2 & -a_1 & a_0 \end{pmatrix} \begin{pmatrix} ct & -i\tilde{x} & -i\tilde{y} & -i\tilde{z} \\ i\tilde{x} & ct & i\tilde{z} & -i\tilde{y} \\ i\tilde{y} & -i\tilde{z} & ct & i\tilde{x} \\ i\tilde{z} & i\tilde{y} & -i\tilde{x} & ct \end{pmatrix} =$$

$$= \begin{pmatrix} ct & -ix & -iy & -iz \\ ix & ct & iz & -iy \\ iy & -iz & ct & ix \\ iz & iy & -ix & ct \end{pmatrix} \begin{pmatrix} a_0 & -a_1 & -a_2 & -a_3 \\ a_1 & a_0 & a_3 & -a_2 \\ a_2 & -a_3 & a_0 & a_1 \\ a_3 & a_2 & -a_1 & a_0 \end{pmatrix}, \quad (6)$$

that is:

$$a_1\tilde{x} + a_2\tilde{y} + a_3\tilde{z} = a_1 x + a_2 y + a_3 z, \quad (7)$$

$$a_0\tilde{x} + a_3\tilde{y} - a_2\tilde{z} = a_0 x - a_3 y + a_2 z, \quad (8)$$

$$a_3\tilde{x} - a_0\tilde{y} - a_1\tilde{z} = -a_3 x - a_0 y + a_1 z, \quad (9)$$

$$a_2\tilde{x} - a_1\tilde{y} + a_0\tilde{z} = -a_2 x + a_1 y + a_0 z, \quad (10)$$

If $a_0 \neq 0$, then (8), (9), (10) imply (7), thus the solution of the linear system (8, 9, 10) has the structure (3) such that:

$$R = \frac{1}{a_0} \begin{pmatrix} a_0a_2 + a_1a_3 & a_0^2 + a_1^2 & a_0a_3 - a_1a_2 \\ -a_0a_1 + a_2a_3 & a_0a_3 + a_1a_2 & -a_0^2 - a_2^2 \\ a_0^2 + a_3^2 & -a_0a_2 + a_1a_3 & -a_0a_1 - a_2a_3 \end{pmatrix}$$

$$\times \begin{pmatrix} -a_2 & a_1 & a_0 \\ a_0 & -a_3 & a_2 \\ -a_3 & -a_0 & a_1 \end{pmatrix}, \quad (11)$$

which is a factorization of the matrix of rotation (4) in terms of the Euler-Olinde Rodrigues parameters.

Similarly, if $a_1 \neq 0$, then (7), (9), (10) generate to (8), therefore:

$$R = \frac{1}{a_1} \begin{pmatrix} a_0^2 + a_1^2 & -a_0a_3 + a_1a_2 & a_0a_2 + a_1a_3 \\ a_0a_3 + a_1a_2 & -a_1^2 - a_3^2 & -a_0a_1 + a_2a_3 \\ -a_0a_2 + a_1a_3 & a_0a_1 + a_2a_3 & -a_1^2 - a_2^2 \end{pmatrix}$$

$$\times \begin{pmatrix} a_1 & a_2 & a_3 \\ -a_2 & a_1 & a_0 \\ -a_3 & -a_0 & a_1 \end{pmatrix}, \quad (12)$$

for the case $a_2 \neq 0$ the relations (7), (8), (10) imply (9), thus:

$$R = \frac{1}{a_2} \begin{pmatrix} -a_0a_3 + a_1a_2 & a_2^2 + a_3^2 & a_0a_2 + a_1a_3 \\ a_0^2 + a_2^2 & -a_0a_3 - a_1a_2 & -a_0a_1 + a_2a_3 \\ a_0a_1 + a_2a_3 & a_0a_2 - a_1a_3 & -a_1^2 - a_2^2 \end{pmatrix}$$

$$\times \begin{pmatrix} a_1 & a_2 & a_3 \\ -a_2 & a_1 & a_0 \\ a_0 & -a_3 & a_2 \end{pmatrix}, \quad (13)$$

and finally, if $a_3 \neq 0$ the expressions (7), (8), (9) generate to (10), hence:

$$R = \frac{1}{a_3} \begin{pmatrix} a_0a_2 + a_1a_3 & a_0a_3 - a_1a_2 & a_2^2 + a_3^2 \\ -a_0a_1 + a_2a_3 & a_1^2 + a_3^2 & -a_0a_3 - a_1a_2 \\ a_0^2 + a_3^2 & -a_0a_1 - a_2a_3 & a_0a_2 - a_1a_3 \end{pmatrix} \times$$

$$\times \begin{pmatrix} a_1 & a_2 & a_3 \\ a_0 & -a_3 & a_2 \\ -a_3 & -a_0 & a_1 \end{pmatrix}, \quad (14)$$

The relations (11), (12), (13) and (14) are factorizations of the matrix of rotation (4), and their possible geometrical meaning, is an open problem.

3 Lorentz transformation

The quaternionic relation (2) gives the following components for an arbitrary Lorentz matrix:

$$L^0_{\ 0} = a_0^* a_0 + a_1^* a_1 + a_2^* a_2 + a_3^* a_3, \; L^0_{\ 1} = i\left(a_0^* a_1 + a_3^* a_2\right) + cc,$$

$$L^0_{\ 2} = i\left(a_0^* a_2 + a_1^* a_3\right) + cc, \; L^0_{\ 3} = i\left(a_0^* a_3 + a_2^* a_1\right) + cc,$$

$$L^1_{\ 0} = i\left(a_0^* a_1 + a_2^* a_3\right) + cc, \; L^1_{\ 1} = a_0^* a_0 + a_1^* a_1 - a_2^* a_2 - a_3^* a_3,$$

$$L^1_{\ 2} = -a_0^* a_3 + a_1^* a_2 + cc, \; L^1_{\ 3} = a_0^* a_2 + a_1^* a_3 + cc,$$

$$L^2_{\ 0} = i\left(a_0^* a_2 + a_3^* a_1\right) + cc, \; L^2_{\ 1} = a_1^* a_2 + a_3^* a_2 + cc,$$

$$L^2_{\ 2} = a_0^* a_0 - a_1^* a_1 + a_2^* a_2 - a_3^* a_3, \; L^2_{\ 3} = -a_0^* a_1 + a_2^* a_3 + cc,$$

$$L^3_{\ 0} = i\left(a_0^* a_3 + a_1^* a_2\right) + cc, \; L^3_{\ 1} = -a_0^* a_2 + a_1^* a_3 + cc,$$

$$L^3_{\ 2} = a_0^* a_1 + a_2^* a_3 + cc, \; L^3_{\ 3} = a_0^* a_0 - a_1^* a_1 - a_2^* a_2 + a_3^* a_3, \quad (15)$$

where cc means the complex conjugate of all the previous terms; therefore, any Lorentz transformations accepts the splitting:

$$(L^\mu_{\ \nu}) = \begin{pmatrix} -ia_0^* & -ia_1^* & -ia_2^* & -ia_3^* \\ -a_1^* & a_0^* & -a_3^* & a_2^* \\ -a_2^* & a_3^* & a_0^* & -a_1^* \\ -a_3^* & -a_2^* & a_1^* & a_0^* \end{pmatrix} \begin{pmatrix} ia_0 & -a_1 & -a_2 & -a_3 \\ ia_1 & a_0 & -a_3 & a_2 \\ ia_2 & a_3 & a_0 & -a_1 \\ ia_3 & -a_2 & a_1 & a_0 \end{pmatrix}, \quad (16)$$

in terms of the Euler−Olinde Rodrigues parameters. For example, for a boost with arbitrary direction [25]:

$$a_0 = \cosh\left(\frac{\phi}{2}\right), \quad a_1 = i\frac{v_x}{v}\sinh\left(\frac{\phi}{2}\right),$$

$$a_2 = i\frac{v_y}{v}\sinh\left(\frac{\phi}{2}\right), \quad a_3 = i\frac{v_z}{v}\sinh\left(\frac{\phi}{2}\right), \tag{17}$$

where ϕ is determined by the relative speed between the frames of reference:

$$\cosh\phi = \tilde{\gamma} = \frac{1}{\sqrt{1-\frac{v^2}{c^2}}}, \quad \sinh\phi = \frac{v}{c}\tilde{\gamma}, \quad v^2 = v_x^2+v_y^2+v_z^2,$$

$$\mathbf{p} = m\mathbf{v} = m_0\tilde{\gamma}\,\mathbf{v}, \quad |\mathbf{p}| = p = mv,$$

$$E^2 = p^2c^2+m_0^2c^4, \quad \cosh\left(\frac{\phi}{2}\right) = \sqrt{\frac{E+m_0c^2}{2\,m_0\,c^2}},$$

$$\sinh\left(\frac{\phi}{2}\right) = \sqrt{\frac{E-m_0c^2}{2\,m_0\,c^2}}, \quad \tanh\phi = \frac{v}{c},$$

$$\tanh\left(\frac{\phi}{2}\right) = \frac{\sinh\phi}{1+\cosh\phi} = \frac{pc}{E+m_0c^2},$$

$$2\sinh^2\left(\frac{\phi}{2}\right) = \cosh\phi - 1 = \tilde{\gamma}-1, \tag{18}$$

then the parameters (17) generate a proper Lorentz transformation future preserving $\tilde{x}^\mu = L^\mu_{\ \lambda}x^\lambda$ via the expressions (15). Thus, we obtain the following Lorentz symmetric matrix representing a boost in an arbitrary direction [25,26]:

$$(L^\mu_{\ \lambda}) = \begin{pmatrix} \tilde{\gamma} & -\frac{v_x}{c}\tilde{\gamma} & -\frac{v_y}{c}\tilde{\gamma} & -\frac{v_z}{c}\tilde{\gamma} \\ -\frac{v_x}{c}\tilde{\gamma} & 1+\frac{v_x^2}{v^2}(\tilde{\gamma}-1) & \frac{v_xv_y}{v^2}(\tilde{\gamma}-1) & \frac{v_xv_z}{v^2}(\tilde{\gamma}-1) \\ -\frac{v_y}{c}\tilde{\gamma} & \frac{v_xv_y}{v^2}(\tilde{\gamma}-1) & 1+\frac{v_y^2}{v^2}(\tilde{\gamma}-1) & \frac{v_yv_z}{v^2}(\tilde{\gamma}-1) \\ -\frac{v_z}{c}\tilde{\gamma} & \frac{v_xv_z}{v^2}(\tilde{\gamma}-1) & \frac{v_yv_z}{v^2}(\tilde{\gamma}-1) & 1+\frac{v_z^2}{v^2}(\tilde{\gamma}-1) \end{pmatrix}, \tag{19}$$

that is [26]:

$$\tilde{t} = \tilde{\gamma}\left(t-\frac{1}{c^2}\mathbf{v}\cdot\mathbf{x}\right), \quad \tilde{\mathbf{x}} = \mathbf{x}+\left(\frac{\tilde{\gamma}-1}{v^2}\mathbf{v}\cdot\mathbf{x}-\tilde{\gamma}t\right)\mathbf{v}. \tag{20}$$

Then the factorization (16) applied to (19) implies the splitting:

$$(L^\mu_{\ \nu}) = \frac{\tilde{\gamma}-1}{2v^2}\begin{pmatrix} -iQv & -v_x & -v_y & -v_z \\ iv_x & Qv & iv_z & -iv_y \\ iv_y & -iv_z & Qv & iv_x \\ iv_z & iv_y & -iv_x & Qv \end{pmatrix}$$

$$\times \begin{pmatrix} iQv & -iv_x & -iv_y & -iv_z \\ -v_x & Qv & -iv_z & iv_y \\ -v_y & iv_z & Qv & -iv_x \\ -v_z & -iv_y & iv_x & Qv \end{pmatrix} \tag{21}$$

such that:

$$Q = \coth\left(\frac{\phi}{2}\right) = \sqrt{\frac{E+m_0c^2}{E-m_0c^2}} = \frac{E+m_0c^2}{pc}$$

$$= \frac{v\tilde{\gamma}}{c(\tilde{\gamma}-1)} = \frac{c(\tilde{\gamma}+1)}{v\tilde{\gamma}},$$

$$\frac{\tilde{\gamma}-1}{2v^2} = \frac{E+m_0c^2}{2m_0c^2v^2}. \tag{22}$$

4 Dirac equation with zero mass

The quaternionic form of Dirac equation for spin 1/2 without the mass term is given by [27,28,29,30]:

$$\nabla\mathbf{D} = \mathbf{0}\,, \qquad \nabla = \frac{i}{c}\frac{\partial}{\partial t}+\mathbf{I}\frac{\partial}{\partial x}+\mathbf{J}\frac{\partial}{\partial y}+\mathbf{K}\frac{\partial}{\partial z}\,, \tag{23}$$

$$\mathbf{D} = i(\eta^1+\xi^2)+(\eta^2+\xi^1)\mathbf{I}+i(\eta^2-\xi^1)\mathbf{J}+(\eta^1-\xi^2)\mathbf{K}\,, \tag{24}$$

where:

$$\xi^1 = \psi_2-\psi_4, \qquad \xi^2 = \psi_3-\psi_1,$$

$$\eta^1 = \psi_1^*+\psi_3^*, \qquad \eta^2 = \psi_2^*+\psi_4^*, \tag{25}$$

in terms of the components of Dirac spinor, in the standard representation of the gamma matrices [23,26,31,32]. Thus (23-24), under the association (5), is equivalent to the matrix relation:

$$\begin{pmatrix} \frac{1}{c}\partial_t & \partial_x & \partial_y & \partial_z \\ -\partial_x & \frac{1}{c}\partial_t & -\partial_z & \partial_y \\ -\partial_y & \partial_z & \frac{1}{c}\partial_t & -\partial_x \\ -\partial_z & -\partial_y & \partial_x & \frac{1}{c}\partial_t \end{pmatrix} \times$$

$$\begin{pmatrix} i(\eta^1+\xi^2) & (\eta^2+\xi^1) & i(\eta^2-\xi^1) & (\eta^1-\xi^2) \\ -(\eta^2+\xi^1) & i(\eta^1+\xi^2) & -(\eta^1-\xi^2) & i(\eta^2-\xi^1) \\ i(-\eta^2+\xi^1) & (\eta^1-\xi^2) & i(\eta^1+\xi^2) & -(\eta^2+\xi^1) \\ (-\eta^1+\xi^2) & i(-\eta^2+\xi^1) & (\eta^2+\xi^1) & i(\eta^1+\xi^2) \end{pmatrix}$$

$$= 0, \tag{26}$$

which implies four independent equations:

$$\eta^1_{\ ,1\dot{1}}+\eta^2_{\ ,2\dot{1}}+\xi^1_{\ ,1\dot{2}}+\xi^2_{\ ,2\dot{2}} = 0, \ \eta^1_{\ ,1\dot{1}}+\eta^2_{\ ,2\dot{1}}-\xi^1_{\ ,1\dot{2}}-\xi^2_{\ ,2\dot{2}} = 0,$$

$$\eta^1_{\ ,1\dot{2}}+\eta^2_{\ ,2\dot{2}}+\xi^1_{\ ,1\dot{1}}+\xi^2_{\ ,2\dot{1}} = 0, \ \eta^1_{\ ,1\dot{2}}+\eta^2_{\ ,2\dot{2}}-\xi^1_{\ ,1\dot{1}}-\xi^2_{\ ,2\dot{1}} = 0, \tag{27}$$

such that:

$$\partial_{1\dot{1}} = \frac{1}{c}\partial_t+\partial_z, \quad \partial_{1\dot{2}} = \partial_x-i\partial_y,$$

$$\partial_{2\dot{1}} = \partial_x+i\partial_y, \quad \partial_{2\dot{2}} = \frac{1}{c}\partial_t-\partial_z, \tag{28}$$

then from (27) are immediate the Weyl spinor equations [23,33,34]:

$$\partial_{A\dot{B}}\,\eta^{\dot{B}} = 0, \qquad \partial_{B\dot{A}}\,\xi^B = 0. \tag{29}$$

5 Conclusion

Lorentz transformations can arise through quaternions; which here has given rise to the factorization of an arbitrary 3-rotation matrix, as well as to the factorization of Lorentz matrices, in terms of the Euler-Olinde Rodrigues parameters. The quaternionic form of the Dirac equation, without the mass term, together with the mathematical fact that a 4×4 matrix can be associated with any quaternion, led to a set of independent relations from which the Weyl spinor equations arose.

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Conflicts of interest

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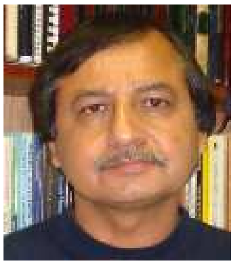
Juan Bulnes Received a M.Sc and a Ph.D in Physics from the Brazilian Center for Physics Research of Rio de Janeiro. He then moved to Belo Horizonte (UFMG), Rio de Janeiro (ON) and Campos dos Goytacazes (UENF) for post-doctoral periods from 2006 to 2011. He is currently associate professor in Federal University of Amapá, Brazil.

Taekyun Kim is mainly researching number theory in the field of algebra, and it is worth mentioning that he was also named the World's Most Influential Researcher in 2016 by Clarivate Analytics, an academic information service. Kwangwoon University Prof. T. Kim from the Department of Mathematics was selected as the Best Scientist in the field of mathematics announced in 2022 by Research.com, an authoritative academic information service platform. https://www.kw.ac.kr/en/life/notice.jsp?BoardMode=view&DUID=38714



José Luis Lopez-Bonilla Professor and Scientific Researcher at Instituto Politécnico Nacional in México City. He received his masters and Ph.D degrees from the Superior School of Physics and Mathematics of the Instituto Politécnico Nacional. Specialist in Mathematical Methods Applied to Engineering, and Theoretical Physics.