| 0 | NOTATION-CONVENTIONS-HOW TO USE THIS BOOK | |
|---|---|----|
| 1 | INTRODUCTION | Ç |
| | The Rodrigues programme | 18 |
| | Rotations by 2π | 22 |
| | Spinor representations | 24 |
| 2 | | |
| | MATRICES, AND GROUPS | 29 |
| | 1 Symmetry operators in configuration space | 29 |
| | Description of the point-symmetry operations | 30 |
| | Specification of the symmetry operations | 32 |
| | Composition of symmetry operations | 33 |
| | 2 Eigenvectors of configuration space operators | 35 |
| | 3 Symmetry operators in function space | 36 |
| | 4 Matrices and operators | 38 |
| | 5 Groups | 42 |
| | 6 All about matrix properties | 50 |
| | Orthogonal matrices | 52 |
| | Unitary matrices | 55 |
| | Hermitian and skew-Hermitian matrices | 56 |
| | Supermatrices and the direct product | 56 |
| | Commutation of matrices | 58 |
| | Matrix functions | 58 |
| | 7 Quantal symmetry. Observables and infinitesimal operators | 60 |
| | Symmetries and observables | 62 |
| | Infinitesimal operators and observables | 63 |
| 3 | A PRIMER ON ROTATIONS AND ROTATION | |
| _ | MATRICES | 65 |
| | 1 Euler angles | 66 |
| | Rotation matrices in terms of the Euler angles | 69 |
| | 2 Angle and axis of an orthogonal matrix | 70 |
| | 3 The matrix of a rotation $R(\phi \mathbf{n})$ | 73 |
| | 4 Euler angles in terms of the angle and axis of rotation | 75 |
| | 5 A rotation in terms of rotations about orthogonal axes | 76 |
| | 6 Comments on the parametrization of rotations | 79 |

| 4 | ROTATIONS AND ANGULAR MOMENTUM | 80 |
|---|---|----------|
| | 1 Infinitesimal rotations | 80 82 |
| | 2 The infinitesimal generator: angular momentum | 84 |
| | 3 Rotation matrices | 85 |
| | 4 Commutation | 86 |
| | 5 Shift operators | |
| | 6 The eigenfunctions of I_z | 87 |
| | 7 The irreducible bases for SO(3) | 90 |
| | Spherical and solid harmonics | 93 |
| | 8 The Condon and Shortley convention | 94 |
| | 9 Applications. Matrices for $j = 1$ and $j = \frac{1}{2}$ (Pauli matrices) | 96 |
| | The Pauli matrices, $j = \frac{1}{2}$ | 98 |
| 5 | TENSOR BASES: INTRODUCTION TO SPINORS | 99 |
| | 1 Vectors and spherical vectors | 100 |
| | 2 Tensor bases and tensor products | 103 |
| | Symmetrization of tensors | 104 |
| | 3 Half-integral bases: spinors | 106 |
| _ | | |
| 6 | THE BILINEAR TRANSFORMATION: | |
| | INTRODUCTION TO SU(2), SU'(2), AND ROTATIONS. MORE ABOUT SPINORS | 109 |
| | 1 The bilinear transformation | 110 |
| | The inverse | 111 |
| | 2 Special unitary matrices. The SU(2) group | 112 |
| | 3 Rotations and SU(2): a first contact | 113 |
| | 4 Binary rotations as the group generators | 116 |
| | 5 Do we have a representation of SO(3)? | 117 |
| | 6 SU(2) plus the inversion: SU'(2) | 118 |
| | Inversion and parity | 120 |
| | 7 Spinors and their invariants | 121 |
| | 7 Spinors and their invariants | 121 |
| 7 | ROTATIONS AND SU(2). THE STEREOGRAPHIC | |
| | PROJECTION | 124 |
| | 1 The stereographic projection | 126 |
| | 2 Geometry and coordinates of the projection | 127 |
| | 3 The homomorphism between SU(2) and SO(3) | 128 |
| | The spinor components | 132 |
| 8 | PROJECTIVE REPRESENTATIONS | 135 |
| ~ | 1 The group \mathbf{D}_2 and its SU(2) matrices. Definition of projec- | |
| | tive representations | 135 |
| | 2 Bases of the projective representations | 138 |
| | Bases and energy levels | 140 |
| | 3 The factor system | 142 |

| | 4 The representations Characters | 144 144 |
|----|---|------------|
| | | 145 |
| | 5 Direct products of representations 6 The covering group | 146 |
| | Remarks | 149 |
| | Remarks | 145 |
| 9 | THE GEOMETRY OF ROTATIONS | 15 |
| | 1 The unit sphere and the rotation poles | 152 |
| | Conjugate poles | 154 |
| | Improper rotations | 154 |
| | 2 The Euler construction | 155 |
| | 3 Spherical trigonometry revisited | 157 |
| | 4 The Euler construction in formulae. The Euler-Rodrigues | |
| | parameters | 159 |
| | Remarks | 160 |
| | 5 The conical transformation | 162 |
| 10 | THE TOPOLOGY OF ROTATIONS | 164 |
| | 1 The parametric ball | 165 |
| | 2 Paths | 167 |
| | 3 Programme: continuity | 170 |
| | 4 Homotopy | 170 |
| | 5 The projective factors | 174 |
| | 6 Operations, turns, and connectivity | 174 |
| 11 | THE SPINOR REPRESENTATIONS | 17 |
| | 1 Determination of the projective factors | 177 |
| | 2 The intertwining theorem | 179 |
| | 3 The character theorem | 182 |
| | 4 The irreducible representations | 182 |
| | 5 The projective factors from the Euler-Rodrigues parameters | 183 |
| | 6 Inverses and conjugates in the Euler-Rodrigues parametri- | |
| | zation | 187 |
| | Conjugation and the choice of the positive hemisphere | 189 |
| | 7 The character theorem proved in the Euler-Rodrigues | 100 |
| | parametrization | 190 |
| | 8 The SU(2) representation of SO(3) | 19 |
| | 9 C_i and the irreducible representations of O(3). The SU'(2) | |
| | representation of O(3) | 194 |
| | The representations of \mathbf{C}_i | 194 |
| | The irreducible representations of O(3) | 196 |
| | The SU'(2) representation of O(3) | 19 |
| | The factor system for O(3) | 197 |
| | 10 Improper point groups | 199 |

| 12 | THE ALGEBRA OF ROTATIONS: QUATERNIONS | 201 |
|-----|---|-----|
| | 1 An entertainment on binary rotations | 201 |
| | 2 The definition of quaternions | 202 |
| | 3 Inversion of quaternions. Characterization of their scalar | |
| | and vector parts | 205 |
| | 4 Conjugate and normalized quaternions. Inverse quaternions | 206 |
| | 5 The quaternion units | 209 |
| | 6 SO(3), SU(2), and quaternions | 211 |
| | 7 Exponential form of quaternions | 213 |
| | 8 The conical transformation | 214 |
| | 9 The rectangular transformation | 217 |
| | 10 Quaternion algebra and the Clifford algebra | 219 |
| | In praise of mirrors | 221 |
| | 11 Applications: angle and axis of rotation and SU(2) matrices | |
| | in terms of Euler angles | 223 |
| 12 | DOUBLE CROUPS | 225 |
| 13 | DOUBLE GROUPS 1 Introduction and example | 226 |
| | 2 The double group in the quaternion parametrization | 230 |
| | | 231 |
| | 3 Notation and operational rules | 233 |
| | Intertwining 4 Class structure: Opechowski Theorem | 235 |
| | 4 Class structure. Opechowski Theorem | 255 |
| 14 | THE IRREDUCIBLE REPRESENTATIONS OF | |
| | SO(3) | 237 |
| | 1 More about spinor bases | 237 |
| | 2 The irreducible representation | 241 |
| | 3 The bases of the representations | 246 |
| 15 | EXAMPLES AND APPLICATIONS | 248 |
| 13 | 1 The choice of the positive hemisphere | 248 |
| | 2 Parametrization of the group elements for \mathbf{D}_6 , \mathbf{D}_3 , \mathbf{C}_{3v} . | |
| | Multiplication tables and factor systems | 251 |
| | 3 The standard representation | 253 |
| | 4 The irreducible projective and vector representations | 255 |
| | The representations of \mathbf{D}_3 | 259 |
| | The representations of \mathbf{C}_{3v} | 260 |
| | 5 The double group $\tilde{\mathbf{D}}_3$ | 261 |
| | 6 Some applications | 262 |
| | o bonne apprications | |
| 16 | SOLUTIONS TO PROBLEMS | 266 |
| Ref | erences | 298 |
| Ind | Index | |