

### ME 115(a): Homework #3

(Due Friday Feb. 14, 2014)

**Problem 1:** (20 points) Do Problem 6(a,b,d,e) in Chapter 2 of the MLS text.

**Problem 2:** (15 points) Do Problem 11(a,b,d) in Chapter 2 of the MLS text.

**Problem 3:** (15 points) Consider  $2 \times 2$  complex matrices of the form:

$$M = \begin{bmatrix} z & w \\ -w^* & z^* \end{bmatrix} = \begin{bmatrix} (a+ib) & (c+id) \\ -(c-id) & (a-ib) \end{bmatrix}$$

where:

$$\det(M) = zz^* + ww^* = 1$$

and  $z, w \in \mathbb{C}$ , and  $*$  denotes complex conjugation. Such matrices form a matrix group termed the “special unitary matrices” of dimension 2,  $SU(2)$ .

- **Part (a):** Show that matrices:

$$\begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix} \quad \begin{bmatrix} i & 0 \\ 0 & -i \end{bmatrix} \quad \begin{bmatrix} 0 & 1 \\ -1 & 0 \end{bmatrix} \quad \begin{bmatrix} 0 & i \\ i & 0 \end{bmatrix}$$

form a basis for  $SU(2)$ . The element  $i$  is  $\sqrt{-1}$ . I.e., all elements of  $SU(2)$  can be expressed as some combination of these elements. Next show that elements of  $SU(2)$  are isomorphic to the unit quaternions. That is, there is a one-to-one correspondence between each element of  $SU(2)$  and a unit quaternion.

- **Part (b):** Show that the special unitary representation of a rotation in terms of z-y-x Euler Angles can be computed as :

$$\begin{bmatrix} \cos \frac{\psi}{2} & i \sin \frac{\psi}{2} \\ i \sin \frac{\psi}{2} & \cos \frac{\psi}{2} \end{bmatrix} \begin{bmatrix} \cos \frac{\phi}{2} & \sin \frac{\phi}{2} \\ -\sin \frac{\phi}{2} & \cos \frac{\phi}{2} \end{bmatrix} \begin{bmatrix} e^{i\frac{\gamma}{2}} & 0 \\ 0 & e^{-i\frac{\gamma}{2}} \end{bmatrix}$$

where  $\psi$ ,  $\phi$ , and  $\gamma$  are respectively the rotations about the z, y, and x axes.

- **Part (c):** Suppose a rotation is represented by a special unitary matrix of the form:

$$\begin{bmatrix} z & w \\ -w^* & z^* \end{bmatrix}$$

determine the angle of rotation,  $\phi$ , and the axis of rotation,  $\hat{s}$ .

**Problem 4:** (10 points) Find the three z-y-x Euler angles from a given rotation matrix