



A DECOUPLED SOLUTION TO THE GENERALIZED EULER DECOMPOSITION PROBLEM IN \mathbb{R}^3 AND $\mathbb{R}^{2,1}$

DANAİL BREZOV, CLEMENTINA MLADENOVA AND IVAĬLO MLADENOV

Presented by Ivaĭlo M. Mladenov

Abstract. In this article we suggest a new method, partially based on earlier works of Wohlhart [15], Mladenova and Mladenov [11], Brezov et al [3], that resolves the generalized Euler decomposition problem (about arbitrary axes) using a system of quadratic equations. The main contribution made here is that we manage to decouple this system and express the solutions independently in a compact covariant form. We apply the same technique to the Lorentz group in $2+1$ dimensions and discuss certain complications related to the presence of isotropic directions in $\mathbb{R}^{2,1}$.

Contents

| | | |
|----------|--|-----------|
| 1 | Introduction | 48 |
| 2 | Quaternions and Vector-Parameters | 48 |
| 3 | The Decomposition Setting | 52 |
| 3.1 | Half-Turns | 53 |
| 3.2 | The Case of Two Axes | 54 |
| 3.3 | Signs and Orientation | 55 |
| 3.4 | Gimbal Lock | 55 |
| 3.5 | Two Familiar Examples | 56 |
| 4 | The Hyperbolic Case | 59 |
| 4.1 | Two-Axes Decompositions | 60 |
| 4.2 | Half-Turns, Time-Reversing Boosts and Locked Gimbals | 61 |
| 4.3 | Light Cone Singularities | 62 |
| 4.4 | Configurations of Axes | 65 |
| 5 | Transition to Moving Frames | 68 |
| 6 | Quaternion and split quaternion Decompositions | 69 |
| 7 | Numerical Examples | 75 |
| | References | 77 |
| | doi: 10.7546/jgsp-33-2014-47-78 | 47 |