

Let  $\mathbf{V}$  denote the matrix to define the normal mode, i.e.,

$$\boldsymbol{U} = \mathbf{V}\boldsymbol{u} \,,$$

where  $\boldsymbol{U} = (X, P_x, Y, P_y, Z, P_z)$  and  $\boldsymbol{u} = (x, p_x, y, p_y, z, \delta \equiv p - 1)$  are the normal and physical coordinates, respectively, expressed as

$$\mathbf{V} = \mathbf{PBR}_6\mathbf{H} \,,$$

where

$$\mathbf{H} = \begin{pmatrix} \left(1 - \frac{\det \mathbf{H}_x}{1 + a}\right)\mathbf{I} & \frac{\mathbf{H}_x\mathbf{J}_2\mathbf{H}_y^T\mathbf{J}_2}{1 + a} & -\mathbf{H}_x \\ \frac{\mathbf{H}_y\mathbf{J}_2\mathbf{H}_x^T\mathbf{J}_2}{1 + a} & \left(1 - \frac{\det \mathbf{H}_y}{1 + a}\right)\mathbf{I} & -\mathbf{H}_y \\ -\mathbf{J}_2\mathbf{H}_x^T\mathbf{J}_2 & -\mathbf{J}_2\mathbf{H}_y^T\mathbf{J}_2 & a\mathbf{I} \end{pmatrix} \,,$$

$$\mathbf{R}_6 = \begin{pmatrix} \mathbf{R} & 0 & 0 \\ 0 & 0 & \mathbf{I} \end{pmatrix} = \begin{pmatrix} b\mathbf{I} & \mathbf{J}_2\mathbf{r}^T\mathbf{J}_2 & 0 \\ \mathbf{r} & b\mathbf{I} & 0 \\ 0 & 0 & \mathbf{I} \end{pmatrix} \,,$$

$$\mathbf{PB} = \begin{pmatrix} \mathbf{P}_x\mathbf{B}_x & 0 & 0 \\ 0 & \mathbf{P}_y\mathbf{B}_y & 0 \\ 0 & 0 & \mathbf{P}_z\mathbf{B}_z \end{pmatrix} \,,$$

with

$$\begin{aligned} a^2 + \det \mathbf{H}_x + \det \mathbf{H}_y &= 1 \,, \\ b^2 + \det \mathbf{R} &= 1 \, . \end{aligned}$$

Symbols  $\mathbf{I}, \mathbf{J}_2, \mathbf{H}_{x,y}, \mathbf{r}, \mathbf{B}_{x,y,z}, \mathbf{P}_{x,y,z}$  above are 2 by 2 matrices:

$$\begin{aligned} \mathbf{I} &\equiv \begin{pmatrix} 1 & 0 \\ 0 & 1 \end{pmatrix} \,, \\ \mathbf{J}_2 &\equiv \begin{pmatrix} 0 & 1 \\ -1 & 0 \end{pmatrix} \,, \\ \mathbf{r} &\equiv \begin{pmatrix} \mathbf{R1} & \mathbf{R2} \\ \mathbf{R3} & \mathbf{R4} \end{pmatrix} \,, \\ \mathbf{B}_{x,y} &\equiv \begin{pmatrix} \frac{1}{\sqrt{\beta_{x,y}}} & 0 \\ \frac{\alpha_{x,y}}{\sqrt{\beta_{x,y}}} & \sqrt{\beta_{x,y}} \end{pmatrix} \,, \\ \mathbf{P}_{x,y,z} &\equiv \begin{pmatrix} \cos \psi_{x,y,z} & \sin \psi_{x,y,z} \\ -\sin \psi_{x,y,z} & \cos \psi_{x,y,z} \end{pmatrix} \, . \end{aligned}$$

Matrices  $\mathbf{H}_{x,y}$  define dispersions as

$$\begin{pmatrix} \mathbf{ZX} & \mathbf{EX} \\ \mathbf{ZPX} & \mathbf{EPX} \\ \mathbf{ZY} & \mathbf{EY} \\ \mathbf{ZPY} & \mathbf{EPY} \end{pmatrix} \equiv \mathbf{R} \begin{pmatrix} \mathbf{H}_x \\ \mathbf{H}_y \end{pmatrix} \, .$$