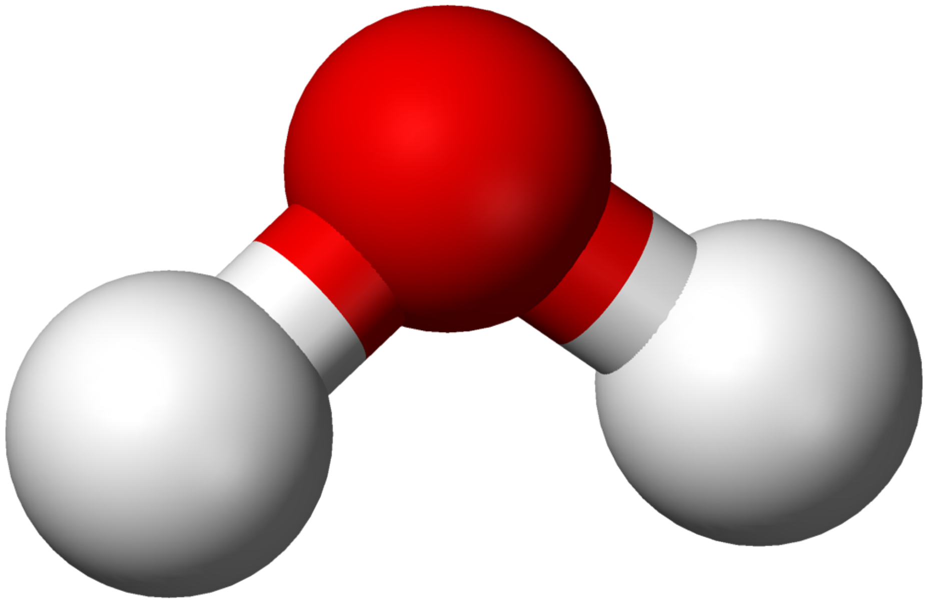

Representation Theory Notes and Exercises

With 0 Figures

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TODOs

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Contents

1 Generalities on Linear Representations 1

List of Definitions

1.1 Linear Representation, Representation Space 1
1.2 Degree 1
1.3 Matrix of a Representation 1
1.4 Similar/Isomorphic Representations 2
1.8 Stable/Invariant Subspaces, Subrepresentation 3
1.11 Direct Sum of Representations 4

List of Examples and Counterexamples

1.5 Unit/Trivial Representation 2

1.6 Regular Representation 2

1.7 Permutation Representation 3

1.9 Subrepresentations of the Regular Representation 3

Preface

This is a set of notes on group representation theory mainly based on J.P. Serre's text *Linear Representations of Finite Groups* [Ser77]. Occasionally, other sources may be used, such as the set of notes by Charles Rezk created for Math 427 [Rez20]. The goal of these notes is to eventually work towards algebraic combinatorics such as Fulton's text *Young Tableaux* [Ful96], as much of algebraic combinatorics is motivated by questions stemming from representation theory. At the time of writing this, another goal is the applications of representation theory to computational complexity: see [Pan23] for a recent survey on this connection.

Chapter 1

Generalities on Linear Representations

Unless otherwise specified, V will denote a vector space, usually over the field $\mathbb{C}$. We will restrict ourselves to finite dimensional vector spaces. Similarly, we will restrict ourselves to finite groups.

Definition 1.1 (Linear Representation, Representation Space): Let G be a group with identity e. A *linear representation* of G in V is a homomorphism $\rho : G \to \mathrm{GL}(V)$. We will frequently, and often interchangeably, write $\rho_s := \rho(s)$. Given ρ, we will say that V is a *representation space* or *representation* of G.

Definition 1.2 (Degree): Let $\rho : G \to V$ be a representation of G in a vector space V. Then the *degree* of ρ is $\dim(V)$.

Let $\rho : G \to V$ be a representation of G in a vector space V with $n := \dim(V)$. Fix a basis (e_j) of V. Then since each ρ_s is an invertible linear transformation of V, we may define an $n \times n$ matrix $R_s \equiv (r_{ij}(s))$ where each $r_{ij}(s)$ is defined by the identity

$$\rho_s(e_j) = \sum_{i=1}^{n} r_{ij}(s) e_i.$$

Definition 1.3 (Matrix of a Representation): We call $R_s = (r_{ij}(s))$ above the *matrix of* ρ_s with respect to the basis (e_j).

Note that R_s satisfies the following:

$$\det(R_s) \neq 0, \qquad R_{st} = R_s \cdot R_t \equiv r_{ij}(st) = \sum_{k=1}^{n} r_{ik}(s) \cdot r_{kj}(s) \quad \forall s, t \in G.$$

Recall that two $n \times n$ matrices A, A' are *similar* if there exists an invertible matrix T such that $TA = A'T$. We may extend this notion to representations.

Definition 1.4 (Similar/Isomorphic Representations): Let ρ and ρ' be two representations of the same group G in vector spaces V and V' respectively. We say ρ and ρ' are *similar* or *isomorphic* if there exists an isomorphism $\tau : V \to V'$ such that for all $s \in G$, τ satisfies $\tau \circ \rho(s) = \rho'(s) \circ \tau$. If R_s, R'_s are the corresponding matrices then this is equivalent to saying there exists an invertible matrix T such that $TR_s = R'_s T$ for all $s \in G$.

Note that if ρ and ρ' are isomorphic, then they must have the same degree.

We now give some examples of these things.

Example 1.5 (Unit/Trivial Representation): Let G be a finite group. Representations of degree 1 must be of the form $\rho : G \to \mathbb{C}^\times$. Since elements s of G are of finite order, $\rho(s)$ must also be of finite order. Thus, for all $s \in G$, $\rho(s)$ is a root of unity. If we take $\rho(s) = 1$ for all $s \in G$, we obtain the *unit* or *trivial* representation of G. This also means that $R_s = 1$ for all s.

Example 1.6 (Regular Representation): Let g be the order of G, and let V be a vector space of dimension g with a basis $(e_t)_{t \in G}$. For each $s \in G$, define ρ_s as the linear map $\rho_s : V \to V$ such that $\rho_s(e_t) = e_{st}$. This is a linear representation of G called the *regular* representation of G. Since for each $s \in G$, $e_s = \rho_s(e_1)$ and thus the images of e_1 form a basis of V. Conversely, let W be a representation of G with a vector w satisfying the collection of all $\rho_s(w)$, $s \in G$, forms a basis of W. Then W is isomorphic to the regular representation of G by the isomorphism $\tau(e_s) = \rho_s(w)$.

For example, let $G = \mathbb{Z}_3$ and $V = \mathbb{C}^3$ with $e_0 = (1, 0, 0)$, $e_1 = (0, 1, 0)$, and $e_2 = (0, 0, 1)$. Then for example, $\rho_0, \rho_1, \rho_2 : \mathbb{C}^3 \to \mathbb{C}^3$ are the linear maps such that

$$\begin{array}{lll} \rho_0(e_0) = e_{0+0} = e_0 & \rho_0(e_1) = e_{0+1} = e_1 & \rho_0(e_2) = e_{0+2} = e_2 \\ \rho_1(e_0) = e_{1+0} = e_1 & \rho_1(e_1) = e_{1+1} = e_2 & \rho_1(e_2) = e_{1+2} = e_0 \\ \rho_2(e_0) = e_{2+0} = e_2 & \rho_2(e_1) = e_{2+1} = e_0 & \rho_2(e_2) = e_{2+2} = e_1 \end{array}$$

With this, the matrix representations of ρ_0, ρ_1 and ρ_2 is similarly straightforward:

$$R_0 = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{pmatrix} \qquad R_1 = \begin{pmatrix} 0 & 0 & 1 \\ 1 & 0 & 0 \\ 0 & 1 & 0 \end{pmatrix} \qquad R_2 = \begin{pmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ 1 & 0 & 0 \end{pmatrix}$$

Example 1.7 (Permutation Representation): We may generalize the regular representation to any group action $G \curvearrowright X$, X a finite set. Recall that for such an action, the map $x \mapsto sx$ for each $s \in G$ is a permutation $X \longleftrightarrow X$. Let V be a vector space with dimension the size of X, and so a basis $(e_x)_{x \in X}$. Define a representation ρ of G by defining ρ_s as the linear map sending $e_x \mapsto e_{sx}$. This representation is known as the *Permutation* representation of G associated with X. If we consider $X = [n]$ and $G = S_n$, then take $V = \mathbb{C}^n$ as our vector space and e_i as the standard basis vector. Then $\rho_\sigma(e_j) = e_{\sigma_j}$. Thus for each $\sigma \in S_n$, we have that $R_\sigma = (r_{ij}(\sigma))$ where entry $r_{ij}(\sigma) = 1$ if $i = \sigma_j$ and 0 otherwise.

Definition 1.8 (Stable/Invariant Subspaces, Subrepresentation): Let $\rho : G \to \mathrm{GL}(V)$ be a linear representation and $W \subseteq V$ a subspace of V. We say that W is *stable* under the action of G if $x \in W$ implies that $\rho_s(x) \in W$ for all $s \in G$., Thus, the restriction $\rho_s^W := \rho_s |_W$ is an isomorphism of W onto itself. Restrictions satisfy the property that $\rho_s^W \circ \rho_t^W = \rho_{st}^W$. Thus, $\rho^W : G \to \mathrm{GL}(W)$ is a linear representation of G in W and we say that W is a *subrepresentation* of V.

Example 1.9 (Subrepresentations of the Regular Representation): Let G be a group. Recall the regular representation V given in Example 1.6. Let W be the 1 dimensional subspace of V generated by the element $x = \sum_{s \in G} e_s$. Then note that $\rho_s(x) = x$ for all $s \in G$ and thus W is a subrepresentation of V. Furthermore, this is isomorphic to the unit representation Example 1.5 with $\tau : C^\times \to W$ such that $\tau(1) = x$. For example, let $G = Z_3$ and $\rho : Z_3 \to \mathbb{C}^3$ the representation given in Example 1.6. Then $x = (1, 1, 1)$ and for example we have that

$$\rho_1(x) = \rho(1)(e_0) + \rho_1(e_1) + \rho_1(e_2) = e_1 + e_2 + e_0 = x.$$

Theorem 1.10: Let $\rho : G \to \mathrm{GL}(V)$ be a linear representation of G in V and let W be a subspace of V stable under G. Then there exists a complement W^0 of W in V which is stable under G.

Proof: Let W' be an arbitrary complement of W in V, and let $p : V \to W$ be the projection. Then we form the average p^0 of conjugates of p by elements in G:

$$p^0 := \frac{1}{|G|} \sum_{t \in G} \rho_t \circ p \circ \rho_t^{-1}.$$

Since $p : V \to W$ and ρ_t preserves W, we have that p^0 maps V onto W. Furthermore, note that ρ_t^{-1} also preserves W.

Thus we have that

$$(p \circ \rho_t^{-1})(x) = \rho_t^{-1}(x), \qquad (\rho_t \circ p \circ \rho_t^{-1})(x) = x, \qquad p^0(x) = x.$$

Thus, p^0 is a projection of V onto W, corresponding to some complement W^0 of W. Moreover, we have that $\rho_s \circ p^0 = p^0 \circ \rho_s$ for all $s \in G$ because

$$\rho_s \circ p^0 \circ \rho_s^{-1} = \frac{1}{|G|} \sum_{t \in G} \rho_s \circ \rho_t \circ p \circ \rho_t^{-1} \circ \rho_s^{-1} = \frac{1}{|G|} \sum_{t \in G} \rho_{st} \circ p \rho_{st}^{-1} = p^0.$$

Now suppose that $x \in W^0$ and $s \in G$, we have that $p^0(x) = 0$ and hence $(p^0 \circ \rho_s)(x) = (\rho_s \circ p^0)(x) = 0$, meaning that $\rho_s(x) \in W^0$. This, W^0 is stable under G. □

Suppose that V had an innerproduct $\langle x, y \rangle$, and furthermore suppose this inner product was invariant under G meaning that for all $s \in G$, $\langle \rho_s(x), \rho_s(y) \rangle = \langle x, y \rangle$. We may also reduce to this case by replacing $\langle x, y \rangle$ with $\sum_{t \in G} \langle \rho_t(x), \rho_t(y) \rangle$. With this, the orthogonal complement $W^\perp$ of W in V is a complement of W stable under G. Note that the invariance of $\langle x, y \rangle$ means that if (e_i) is an orthonormal basis of V, then R_s is a unitary matrix **⟨⟨ proof? ⟩⟩** .

Using the notation of Theorem 1.10, let $x \in V$ and w, w^0 be the projections of x on W and W^0 respectively. Thus for all $s \in G$, $\rho_s(x) = \rho_s(w) + \rho_s(w^0)$. Since W and W^0 are stable under G, we have that $\rho_s(w) \in W$ and $\rho_s(w^0) \in W^0$. This means that $\rho_s(w)$ and $\rho_s(w^0)$ are the projections of $\rho_s(x)$ and in turn the representations of W and W^0 determine the representations of V.

Definition 1.11 (Direct Sum of Representations): Given the above, we write $V = W \oplus W^0$ as the *direct sum* of W and W^0. We identify elements $v \in V$ as pairs (w, w^0) given by their projections.

If the representations W and W^0 are given in matrices R_s and R_s^0, then the matrix form of the representation V is given by

$$\begin{pmatrix} R_s & 0 \\ 0 & R_s^0 \end{pmatrix}.$$

Similar results hold for arbitrarily many, but finite, direct sums of representations.

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