

1.

(a)

Represent the operation using 4×4 matrices that shows the mapping between the nodes.

$$\begin{aligned}
 T_1 &= \begin{pmatrix} 1 & & & \\ & 1 & & \\ & & 1 & \\ & & & 1 \end{pmatrix} & T_2 &= \begin{pmatrix} 1 & & & \\ & & 1 & \\ & 1 & & \\ & & & 1 \end{pmatrix} & T_3 &= \begin{pmatrix} 1 & & & \\ & 1 & & \\ & & 1 & \\ & & & 1 \end{pmatrix} \\
 T_4 &= \begin{pmatrix} & 1 & & \\ 1 & & & \\ & & 1 & \\ & & & 1 \end{pmatrix} & T_5 &= \begin{pmatrix} & 1 & & \\ & & 1 & \\ 1 & & & \\ & & & 1 \end{pmatrix} & T_6 &= \begin{pmatrix} & 1 & & \\ & & 1 & \\ & 1 & & \\ 1 & & & \end{pmatrix} \\
 T_7 &= \begin{pmatrix} & & 1 & \\ 1 & & & \\ & 1 & & \\ & & 1 & \end{pmatrix} & T_8 &= \begin{pmatrix} & & 1 & \\ & 1 & & \\ 1 & & & \\ & & 1 & \end{pmatrix} & T_9 &= \begin{pmatrix} & & 1 & \\ & & & 1 \\ 1 & & 1 & \\ & 1 & & \end{pmatrix} \\
 T_{10} &= \begin{pmatrix} & & & 1 \\ 1 & & & \\ & 1 & & \\ & & 1 & \end{pmatrix} & T_{11} &= \begin{pmatrix} & & & 1 \\ & 1 & & \\ 1 & & & \\ & & 1 & \end{pmatrix} & T_{12} &= \begin{pmatrix} & & & 1 \\ & 1 & & \\ 1 & & & \\ & & 1 & \end{pmatrix}
 \end{aligned}$$

(b)

$$\begin{aligned}
 g_{123} &= \begin{pmatrix} & & 1 & \\ 1 & & & \\ & 1 & & \\ & & & 1 \end{pmatrix} \\
 g_{234} &= \begin{pmatrix} 1 & & & \\ & 1 & & \\ & & 1 & \\ & & & 1 \end{pmatrix} \\
 g_{234}g_{123} &= \begin{pmatrix} & 1 & & \\ 1 & & & \\ & & 1 & \\ & & & 1 \end{pmatrix} = T_4
 \end{aligned}$$

(180° rotation around the the axis connecting the middle of 1-2 and 3-4)

$$g_{123}g_{234} = \begin{pmatrix} & & 1 & \\ 1 & & & \\ & 1 & & \\ & & & 1 \end{pmatrix} = T_9 \neq T_4$$

(c)

See (a)

(d)

$$H = \begin{pmatrix} \varepsilon_0 & -t & -t & -t \\ -t & \varepsilon_0 & -t & -t \\ -t & -t & \varepsilon_0 & -t \\ -t & -t & -t & \varepsilon_0 \end{pmatrix}$$

Eigenvalues are $\varepsilon_0 - 3t$ for eigenvector $\left(\frac{1}{2}, \frac{1}{2}, \frac{1}{2}, \frac{1}{2}\right)$ and $\varepsilon_0 + t$ for eigenvectors, $\left(\frac{1}{2}, \frac{1}{2}, -\frac{1}{2}, -\frac{1}{2}\right)$, $\left(\frac{1}{2}, -\frac{1}{2}, \frac{1}{2}, -\frac{1}{2}\right)$, $\left(\frac{1}{2}, -\frac{1}{2}, -\frac{1}{2}, \frac{1}{2}\right)$.

2.

(a)

$$H = \begin{pmatrix} \varepsilon_0 & -t & & & -t & & -t \\ -t & \varepsilon_0 & -t & & -t & & \\ & -t & \varepsilon_0 & -t & & & -t \\ & & -t & \varepsilon_0 & -t & & \\ & -t & & -t & \varepsilon_0 & -t & \\ -t & & & -t & -t & \varepsilon_0 & -t \\ -t & & -t & & -t & \varepsilon_0 & \end{pmatrix}$$

(b)

(c)

3.

The constrains is that the angular momentum cannot perfectly point in a certain direction and there will always be some fluctuations. This uncertain comes from,

$$\begin{aligned} \langle \Delta L_x, \Delta L_y \rangle &\geq \frac{1}{2i} \langle [L_x, L_y] \rangle \\ &= \frac{\hbar}{2} \langle L_z \rangle \\ &= \frac{\hbar^2 m}{2} \end{aligned}$$

Which can only be 0 when $m = 0$.

4.

(a)

Define $g(\phi, \phi_0) \equiv e^{-iL_z\phi_0/\hbar} f(\phi)$

$$\begin{aligned}\frac{\partial g}{\partial \phi_0} &= -\frac{iL_z}{\hbar} e^{-iL_z\phi_0/\hbar} f(\phi) \\ &= -\frac{\partial}{\partial \phi} e^{-iL_z\phi_0/\hbar} f(\phi) \\ &= -\frac{\partial g}{\partial \phi} \\ dg &= \frac{\partial g}{\partial \phi_0} d\phi_0 + \frac{\partial g}{\partial \phi} d\phi \\ &= \frac{\partial g}{\partial \phi} (d\phi - d\phi_0)\end{aligned}$$

Therefore $g = g(\phi - \phi_0)$ (since it has 0 gradient in this direction). Since $g(\phi) = f(\phi)$ (when $\phi_0 = 0$), $g(\phi, \phi_0) = f(\phi - \phi_0)$ for all ϕ_0

(b)

(c)

(d)

(e)

5.

(a)

(b)

(c)