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LIE POINT TRANSFORMATIONS ADMITTED BY E. WITTEN
EQUATIONST. HALLAP, K. KIIRANEN. E. WITTENI VÖRRANDITE POOLT LUBATUD LIE PUNKTTEISEN-
DUSEDT. ХАЛЛАП, К. КИИРАНЕН. ТОЧЕЧНЫЕ ПРЕОБРАЗОВАНИЯ ЛИ, ДОПУСКАЕМЫЕ УРАВ-
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(Presented by H. Keres)

The Yang—Mills equations are nonlinear second order partial differential equations for 12 scalar functions $\overset{a}{A}_\mu(x)$ [1]:

$$\partial_\mu \overset{a}{F}_{\mu\nu} + \varepsilon^{abc} \overset{b}{A}_\mu \overset{c}{F}_{\mu\nu} = 0, \quad (1)$$

where $\overset{a}{F}_{\mu\nu} \equiv \partial_\mu \overset{a}{A}_\nu - \partial_\nu \overset{a}{A}_\mu + \varepsilon^{abc} \overset{b}{A}_\mu \overset{c}{A}_\nu$.

If the functions $\overset{a}{A}_\mu(x)$ satisfy the so-called self-dual Yang—Mills equations

$$\overset{a}{F}_{\mu\nu} - \frac{1}{2} \varepsilon_{\mu\nu\alpha\beta} \overset{a}{F}_{\alpha\beta} = 0, \quad (2)$$

then they satisfy equations (1) as well. Note that the system of nonlinear first order partial differential equations (2) contains 9 equations and is thereby an underdeterminate system.

E. Witten has searched for possible solutions for equations (2) in cylindrical form [2]:

$$\begin{aligned} \overset{a}{A}_0 &= \frac{A_0 x_a}{r}, \\ \overset{a}{A}_i &= \frac{1 + \varphi_2}{r^2} \varepsilon_{iah} x_h + \frac{\varphi_1}{r^3} (\delta_{ia} r^2 - x_i x_a) + A_1 \frac{x_i x_a}{r^2}, \end{aligned} \quad (3)$$

where scalar functions $A_0, A_1, \varphi_1, \varphi_2$ depend only on two variables t and r , where $r^2 \equiv x_h x_h$. This ansatz gives the model which is very similar to the Abelian Higgs model in space with constant negative curvature.

When we take

$$\begin{aligned} A_0 &= u_3 + \frac{1}{r}, & A_1 &= u_4, \\ \varphi_1 &= r u_1, & \varphi_2 &= -r u_2 \end{aligned} \quad (4)$$

* Here the sum convention is observed. The Greek indices take values from 1 to 4, the Latin ones — from 1 to 3. Only SU(2) gauge group is considered and constant $g=1$ for simplicity's sake.

and note $t \equiv x_0$, $r \equiv x_1$ and $\partial_0 \equiv \frac{\partial}{\partial t}$, $\partial_1 \equiv \frac{\partial}{\partial r}$, then we get the following system of equations for functions u_1, u_2, u_3, u_4 :

$$\begin{aligned} u_{,0}^1 + u_{,1}^2 + u^1 u^4 - u^2 u^3 &= 0 \\ u_{,0}^2 - u_{,1}^1 + u^1 u^3 + u^2 u^4 &= 0 \\ u_{,0}^4 - u_{,1}^3 + u^1 u^1 + u^2 u^2 &= 0. \end{aligned} \quad (5)$$

We call these E. Witten equations. Such equations arise also in the theory of minimal surfaces as Gauss-Codazzi equations [3]. In fact, in this case there is one more equation:

$$u_{,0}^3 + u_{,1}^4 = 0 \quad \text{or} \quad \partial_0 A_0 + \partial_1 A_1 = 0. \quad (6)$$

E. Witten uses this equation in searching for possible solutions of system (5). The system of equations (5)–(6) is a determinate one.

The results of the calculations following method [4] indicate that the generators of Lie point transformations group admitted by the equations (5) form an infinite-dimensional algebra L_∞ :

$$\begin{aligned} X = & f \frac{\partial}{\partial x_0} + g \frac{\partial}{\partial x_1} - u_1 f_{,0} \frac{\partial}{\partial u_1} - u_2 g_{,1} \frac{\partial}{\partial u_2} + \\ & + (u_4 f_{,1} - u_3 f_{,0} - f_{,01}) \frac{\partial}{\partial u_3} + (u_3 g_{,0} - u_4 g_{,1} + g_{,01}) \frac{\partial}{\partial u_4}, \end{aligned} \quad (7)$$

$$Y = h \left(u_2 \frac{\partial}{\partial u_1} - u_1 \frac{\partial}{\partial u_2} \right) + h_{,0} \frac{\partial}{\partial u_4} + h_{,1} \frac{\partial}{\partial u_4}, \quad (8)$$

where $f_{,1} + g_{,0} = 0$, $f_{,0} = g_{,1} = 0$ and $h(x_0, x_1)$ is an arbitrary function. If we take into account equation (6) as well, then

$$h_{,00} + h_{,11} = 0.$$

The generators of Lie point transformations group for equations (1) and (2) were computed in [5]. The result obtained was the algebra $L_\infty = L_{15} \oplus L^0$ in both cases where L_{15} is the algebra of the conformal group and L^0 contains the gauge transformations:

$$\begin{aligned} X = & \xi^\mu \frac{\partial}{\partial x^\mu} - \xi_{,\mu}^{\nu} \frac{\partial}{\partial A_\mu^a}, \\ Y = & \zeta_\mu^a \frac{\partial}{\partial A_\mu^a}, \end{aligned} \quad (9)$$

where

$$\xi_\mu(x) = k_\mu + d \cdot x_\mu + a_{\mu\nu} x_\nu + 2c_\nu x_\nu x_\mu - c_\mu x_\nu x_\nu$$

is the Killing vector and

$$\zeta_\mu^a(x, A) = \theta_{,\mu}^a - \varepsilon^{abc} \theta A_\mu^c. \quad (10)$$

$\theta^a(x)$ denote arbitrary functions of x_μ and $d, k_\mu, c_\mu, a_{\mu\nu} = -a_{\nu\mu}$ are arbitrary constants.

In the two-dimensional case ($n=2$) $f \equiv \xi^0$ and $g \equiv \xi^1$ from (7)–(8) are arbitrary functions of variables $x_0 \pm ix_1$, whereas in the general $n > 2$ (here $n=4$) the functions $\xi^\mu(x)$ are second order polynomials.

The generator Y describes the gauge transformations in both cases and it is the ideal of the algebra since

$$[X, Y] = Y.$$

However, when the functions $\overset{a}{A}_\mu$ satisfy the Lorentz gauge condition

$$\partial_\mu \overset{a}{A}_\mu = 0, \quad (11)$$

then in transformations (9)—(10)

$$\overset{a}{\theta}_{,\mu} = 0 \quad \text{and} \quad \overset{a}{A}_\mu c_\mu = 0. \quad (12)$$

Consequently, the special conformal transformation will disappear and in place of gauge transformations only rotations $SO(3) \simeq SU(2)$ in isotopic space will remain:

$$Y_{ab} = \overset{a}{A}_\mu \frac{\partial}{\partial \overset{b}{A}_\mu} - \overset{b}{A}_\mu \frac{\partial}{\partial \overset{a}{A}_\mu}. \quad (13)$$

In this case the finite algebra $L_{14} = L_{11} \oplus L_3$ [6].

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