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# Quantum control by decomposition of $SU(1, 1)$

Jian-Wu Wu<sup>1</sup>, Chun-Wen Li<sup>1</sup>, Re-Bing Wu<sup>2</sup>, Tzyh-Jong Tarn<sup>3</sup>  
and Jing Zhang<sup>1</sup>

<sup>1</sup> Department of Automation, Tsinghua University, Beijing 100084, People's Republic of China

<sup>2</sup> Department of Chemistry, Princeton University, Princeton, NJ 08544, USA

<sup>3</sup> Department of Systems Science and Mathematics, Washington University, St. Louis, MO 63130, USA

E-mail: [wujw03@mails.tsinghua.edu.cn](mailto:wujw03@mails.tsinghua.edu.cn), [lcw@tsinghua.edu.cn](mailto:lcw@tsinghua.edu.cn), [rewu@Princeton.edu](mailto:rewu@Princeton.edu), [tarn@wuauto.wustl.edu](mailto:tarn@wuauto.wustl.edu) and [zhangjing97@mails.tsinghua.edu.cn](mailto:zhangjing97@mails.tsinghua.edu.cn)

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## Abstract

Constructive algorithms are presented for controlling quantum systems evolving on the  $SU(1, 1)$  Lie group. These procedures are performed via structured decomposition of  $SU(1, 1)$ , which achieve precise controls without any approximations or iterative computations, under the sufficient condition that examines the existence of such decomposition. The technique is applied to controlling transitions between  $SU(1, 1)$  coherent states. These results open up new perspectives on the control design of infinite-dimensional quantum systems involving discrete or continuous spectra.

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## 1. Introduction

Group theoretical techniques have been widely applied in quantum control systems whose propagators evolve on compact Lie groups [1–6]. An important method in the control design is to decompose the target system propagator into a relatively simple sequence of factors that can be directly implemented by piecewise constant or sinusoidal control pulses. This technique is quite useful for many two-level or multi-level quantum systems [7–9], e.g. the movement of spin- $\frac{1}{2}$  particles [4, 6], the manipulation of electronic states of rubidium and the Morse oscillator model of vibrational modes of hydrogen fluoride [5]. Among the existing studies, factorization algorithms for the simplest nontrivial compact Lie group  $SU(2)$  have been investigated in both classical and quantum cases [2, 3] under certain constraint.

In a wider context, many fundamental quantum systems possess noncompact dynamical groups, e.g.,  $SU(1, 1)$  for quantum systems with Poschl–Teller [10] or Morse [11] potential,  $SO(4, 2)$  for the hydrogen atoms [12–15]. Thus it is necessary to extend the study to noncompact cases. In the literature, much attention has been attracted on the analysis of

dynamical properties [16–24] with known quantum Hamiltonians. However, to the authors' knowledge, no studies published to date have examined the inverse problem, i.e. the design of proper Hamiltonian to realize desired dynamics for such quantum systems.

In this paper, we will initiate the study of the control pulses design for quantum control systems with noncompact symmetry groups. Here we consider the simplest class of quantum systems whose Hamiltonians can be written as linear combination of the  $su(1, 1)$  Lie algebra generators. The involved quantum control systems obey the following Schrödinger equation (setting  $\hbar = 1$ ):

$$i\dot{U}(t) = H_0U(t) + u(t)H_IU(t), \quad U(0) = I, \quad (1)$$

where  $H_0$  and  $H_I$  are the internal and interaction Hamiltonians, respectively, and they generate a  $su(1, 1)$  Lie algebra. The scalar control  $u(t)$  represents some adjustable external field coupled to the system that is to be designed in order to achieve certain system evolutions. Related physical examples can be seen in many situations such as coherent states in quantum optics [25–28], spin wave in solid-state physics [29], the quantized vibrational motion of a trapped ion [30], laser–plasma scattering [31] and so on. Here we assume that the admissible control is a piecewise constant function of time, which is widely used in laboratory directly or after rotating wave approximations. The system (1) has a ‘drift’ term  $H_0$  that is manipulated via switching on and off the only one ‘perturbation’  $H_I$ . According to the group representation theory [32, 12], the unitary propagator  $U(t)$  must act on an *infinite*-dimensional Hilbert space, hence carries an infinite-dimensional unitary irreducible representation (UIR) of  $SU(1, 1)$ . Nevertheless, since all faithful representations of  $SU(1, 1)$  are algebraically isomorphic on which the design of control functions does not rely, one can always focus the study on the simplest two-dimensional non-unitary representation to be described in section 2.

We ascribe the control design of the above  $SU(1, 1)$ -type quantum control systems to the following structured decomposition of the target system propagator  $U_f = U(T_f)$ :

$$U_f = \prod_{k=1}^Q e^{-it_k(H_0+u_kH_I)}, \quad (2)$$

where the  $su(1, 1)$  generators  $H_0$  and  $H_I$  are assumed linearly independent, and  $u_k$  is a constant with respect to  $t_k$ . A physical realistic decomposition should satisfy that (i) positive time durations **O1**:  $t_k > 0$ , and (ii) bounded control pulses **O2**:  $|u_k| \leq C$  for some prescribed constant  $C$ . Obviously, for a desired system propagator  $U_f$ , piecewise constant control laws can be naturally determined once a decomposition in the form of (2) is found to satisfy **O1** and **O2**. The idea here is parallel with those on the compact Lie group  $SU(2)$  studied in [2], however, the structured decomposition of  $SU(1, 1)$  is far more complicated and limited as will be seen in the following sections.

The balance of this paper is organized as follows. Section 2 gives preliminaries of the Lie group  $SU(1, 1)$  and its Euler parametrizations. Section 3 constructs main factorization algorithms subjected to **O1** and **O2**, along with a sufficient condition to examine the existence of such decomposition. Section 4 applies the algorithms to the control of transitions between  $SU(1, 1)$  coherent states. Finally, conclusions are drawn in section 5.

## 2. Preliminaries on $SU(1, 1)$

The Lie group  $SU(1, 1)$  consists of two-dimensional complex pseudo-unitary matrices parametrized by

$$\begin{pmatrix} a & b \\ \bar{b} & \bar{a} \end{pmatrix}, \quad |a|^2 - |b|^2 = 1, \quad (3)$$

where  $\bar{a}$  denotes the complex conjugate of  $a$ . The corresponding Lie algebra  $su(1, 1)$  has generators, say  $\{K_1, K_2, K_3\}$ , whose commutations read

$$[K_1, K_2] = -iK_3, \quad [K_2, K_3] = iK_1, \quad [K_3, K_1] = iK_2. \quad (4)$$

Suppose the Hilbert space of quantum states should carry a positive discrete UIR  $\mathcal{D}^+(k)$ , where  $k \in \mathbb{N}^+$  is the Bargmann index [12, 33]. Then one can choose an orthonormal basis  $\{|m, k\rangle, m = 0, 1, 2, \dots\}$  under which the Casimir operator  $C = K_3^2 - K_1^2 - K_2^2$  and the compact generator  $K_3$  are simultaneously diagonalized

$$C|m, k\rangle = k(k-1)|m, k\rangle, \quad K_3|m, k\rangle = (m+k)|m, k\rangle.$$

Correspondingly, the operators  $K_{\pm} = K_1 \pm iK_2$  will act as raising and lowering operators, i.e.,

$$\begin{aligned} K_+|m, k\rangle &= [(m+1)(m+2k)]^{1/2}|m+1, k\rangle, \\ K_-|m, k\rangle &= [m(m+2k-1)]^{1/2}|m-1, k\rangle. \end{aligned} \quad (5)$$

Therefore, the  $SU(1, 1)$  propagators of real quantum systems are represented by infinite-dimensional matrices under the above basis. However, as argued in section 1, one can adopt the simplest faithful non-unitary representation (3) for the purpose of control design, of which the algebra generators are identified as:

$$K_1 = \frac{i}{2}\sigma_y, \quad K_2 = -\frac{i}{2}\sigma_x, \quad K_3 = \frac{1}{2}\sigma_z, \quad (6)$$

where  $\sigma_{x,y,z}$  are Pauli matrices.  $K_1$  and  $K_2$  generate the noncompact one-parameter  $O(1, 1)$  subgroups of  $SU(1, 1)$ , respectively, as follows

$$\begin{aligned} \exp(-i\alpha K_1) &= \begin{pmatrix} \cosh \frac{\alpha}{2} & -i \sinh \frac{\alpha}{2} \\ i \sinh \frac{\alpha}{2} & \cosh \frac{\alpha}{2} \end{pmatrix}, \\ \exp(-i\beta K_2) &= \begin{pmatrix} \cosh \frac{\beta}{2} & -\sinh \frac{\beta}{2} \\ -\sinh \frac{\beta}{2} & \cosh \frac{\beta}{2} \end{pmatrix}, \end{aligned}$$

while  $K_3$  generates a compact  $O(2)$  subgroup

$$\exp(-i\gamma K_3) = \begin{pmatrix} e^{-i\frac{\gamma}{2}} & 0 \\ 0 & e^{i\frac{\gamma}{2}} \end{pmatrix}.$$

The  $SU(1, 1)$  matrices can be decomposed as products of the above factors, which are called Euler-type decompositions [34]. In this paper, two different Euler-type decompositions will be used. The first type is as follows:

$$g(\xi, \eta, \zeta) = e^{-i\xi K_3} e^{-i\eta K_2} e^{-i\zeta K_3}, \quad (7)$$

where  $-2\pi \leq \xi, \zeta \leq 2\pi$  and  $0 \leq \eta < \infty$ . Here the first and the third factors are  $O(2)$  transformations generated by  $K_3$ . Every  $SU(1, 1)$  element possesses this kind of decomposition.

The second kind of decomposition is achieved with its first and last factors generated by  $K_2$ , i.e.

$$h(\xi, \mu, \zeta) = e^{-i\xi K_2} e^{-i\mu K_3} e^{-i\zeta K_2}, \quad (8)$$

or

$$k_l(\xi, \nu, \zeta) = e^{-i\xi K_2} e^{-i\nu K_1} e^{-il\pi K_3} e^{-i\zeta K_2}, \quad (9)$$

where  $-\infty < \xi, \zeta, \nu < \infty$ ,  $-2\pi \leq \mu \leq 2\pi$ ,  $l = 0, 1, 2, 3$ . Almost every  $SU(1, 1)$  element has the second kind of decomposition except a set of exceptional elements with zero measure in  $SU(1, 1)$  [34].

In addition, the following formula will be frequently used throughout this paper

$$\exp[-i(xK_1 + yK_2 + zK_3)] = \begin{cases} \cos \frac{r}{2} I_2 - i \frac{2}{r} \sin \frac{r}{2} \times (xK_1 + yK_2 + zK_3), & (\text{if } z^2 \geq x^2 + y^2), \\ \cosh \frac{r}{2} I_2 - i \frac{2}{r} \sinh \frac{r}{2} \times (xK_1 + yK_2 + zK_3), & (\text{if } z^2 < x^2 + y^2), \end{cases} \quad (10)$$

where  $r = \sqrt{|z^2 - x^2 - y^2|}$ . The  $SU(1, 1)$  element  $e^{-i(xK_1 + yK_2 + zK_3)}$  is called elliptical when  $z^2 > x^2 + y^2$ , hyperbolic when  $z^2 < x^2 + y^2$ , and parabolic when  $z^2 = x^2 + y^2$ .

### 3. Main results

This section contains the main algorithms to compute the structured decomposition of  $SU(1, 1)$  matrices for two representative cases: (1)  $H_0 = K_3, H_I = K_2$  and (2)  $H_0 = K_2, H_I = K_3$  in subsections 3.1 and 3.2, respectively. The influence of the amplitude bound of the control pulses on the time duration will be investigated. In subsection 3.3, we extend the algorithms to systems with more general Hamiltonians, which can also be taken as a sufficient condition that guarantees the existence of a desired decomposition.

#### 3.1. The case $H_0 = K_3, H_I = K_2$

Given a target transformation parametrized in the Euler form (7), the factors like  $e^{-i\theta K_3}$  can be realized as free evolutions of system (1). Thus, it suffices to decompose an arbitrary  $SU(1, 1)$  element by finding the following class of decomposition:

$$e^{-i\theta K_2} = \prod_{k=1}^3 e^{-it_k(K_3 + u_k K_2)} \quad (11)$$

for arbitrary nonzero  $\theta$ , where  $t_k \geq 0, |u_k| \leq C, k = 1, 2, 3$ .

#### Proposition 1.

(1) If  $C > 1$ , then for any  $-1 < u_1, u_3 < 1$  and  $1 < |u_2| < C$ , the decomposition (11) can be realized with time durations

$$\begin{cases} t_1 = \frac{2}{r_1} \left[ \operatorname{arccot} \left( \frac{u_1 - u_2}{r_1} \coth \frac{\theta}{2} - \frac{1}{r_1} \sqrt{\Delta} \right) + m\pi \right], \\ t_2 = \frac{2}{r_2} \operatorname{arcoth} \left( \frac{1}{r_2} \sqrt{\Delta} \right), \\ t_3 = \frac{2}{r_3} \left[ \operatorname{arccot} \left( \frac{u_3 - u_2}{r_3} \coth \frac{\theta}{2} - \frac{1}{r_3} \sqrt{\Delta} \right) + n\pi \right], \end{cases} \quad (12)$$

where  $r_1 = \sqrt{1 - u_1^2}, r_2 = \sqrt{u_2^2 - 1}, r_3 = \sqrt{1 - u_3^2}$  and  $\Delta = (u_2 - u_1)(u_2 - u_3)(\coth^2 \frac{\theta}{2} - 1) + (u_2^2 - 1)$ . The integers  $m$  and  $n$  are chosen so that  $t_1$  and  $t_2$  are positive, and their parities are identical when  $(u_2 - u_1)\theta \geq 0$  and opposite when  $(u_2 - u_1)\theta < 0$ .

(2) If  $C \leq 1$ , then for any  $-C < u_1, u_3 < C$  the decomposition (11) exists if

$$|\theta| \leq 2 \max \left\{ \operatorname{arcoth} \sqrt{\frac{1 + u_1 u_3 - C u_1 - C u_3}{(C - u_1)(C - u_3)}}, \operatorname{arcoth} \sqrt{\frac{1 + u_1 u_3 + C u_1 + C u_3}{(C + u_1)(C + u_3)}} \right\}, \quad (13)$$

and  $u_2$  satisfies

$$\begin{cases} (u_2 - u_1)(u_2 - u_3) > 0, \\ \frac{1}{2\cosh^2\frac{\theta}{2}} \left| \sqrt{u_1^2 + u_3^2 - 2u_1u_3 \cosh\theta + \sinh^2\theta} + u_1 + u_3 \right| \leq |u_2| \leq C, \end{cases} \quad (14)$$

the corresponding time durations are given as

$$\begin{cases} t_1 = \frac{2}{r_1} \left[ \operatorname{arccot} \left( \frac{u_1 - u_2}{r_1} \coth \frac{\theta}{2} \pm \frac{1}{r_1} \sqrt{\Delta} \right) + m\pi \right], \\ t_2 = \frac{2}{r_2} \left[ \operatorname{arccot} \left( \mp \frac{1}{r_2} \sqrt{\Delta} \right) + l\pi \right], \\ t_3 = \frac{2}{r_3} \left[ \operatorname{arccot} \left( \frac{u_3 - u_2}{r_3} \coth \frac{\theta}{2} \pm \frac{1}{r_3} \sqrt{\Delta} \right) + n\pi \right], \end{cases} \quad (15)$$

where  $r_k = \sqrt{1 - u_k^2}$ , ( $k = 1, 2, 3$ );  $\Delta = (u_2 - u_1)(u_2 - u_3)(\coth^2\frac{\theta}{2} - 1) + (u_2^2 - 1)$ . The integers  $m, n$  and  $l$  are chosen so that  $t_1, t_2$  and  $t_3$  are positive, and the parities of  $m$  and  $n$  are identical when  $(u_2 - u_1)\theta \geq 0$  and opposite when  $(u_2 - u_1)\theta < 0$ .

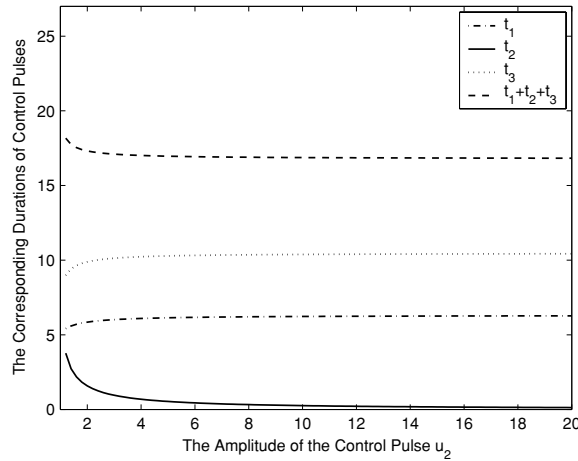
**Proof.** See appendix A. □

The above results provide a rather wide class of control laws for a special target evolution operator. For  $C > 1$ , the target  $e^{-i\theta K_2}$  can be constructed within three control pulses, of which the amplitudes of the first and the last terms are bounded by 1. Consequently, the two factors  $e^{-it_1(K_3+u_1K_2)}$  and  $e^{-it_3(K_3+u_3K_2)}$  are elliptical. They are periodic terms and thus can be used to keep  $t_1, t_2$  and  $t_3$  positive at the same time (see appendix A). In particular these two terms can be realized as pure free evolutions, i.e.,  $u_1 = u_3 = 0$ , resulting the time durations

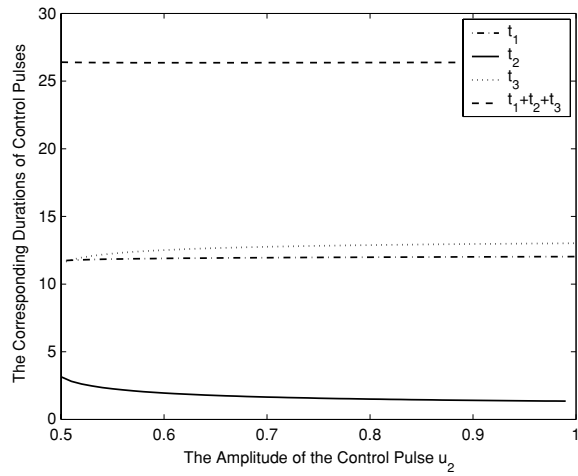
$$\begin{cases} t_1 = 2 \operatorname{arccot} \left( -u_2 \coth \frac{\theta}{2} - \sqrt{u_2^2 \coth^2 \frac{\theta}{2} - 1} \right) + 2m\pi, \\ t_2 = \frac{2}{r_2} \operatorname{arccoth} \left( \frac{1}{r_2} \sqrt{u_2^2 \coth^2 \frac{\theta}{2} - 1} \right), \\ t_3 = 2 \operatorname{arccot} \left( -u_2 \coth \frac{\theta}{2} - \sqrt{u_2^2 \coth^2 \frac{\theta}{2} - 1} \right) + 2n\pi. \end{cases} \quad (16)$$

Moreover, the formulae in (12) indicate that the control amplitude of the second pulse can take any value in  $(1, C]$ . The corresponding  $t_2$  decreases as  $|u_2|$  increases, implying a trade-off between the amplitude  $u_2$  and the time duration  $t_2$ , while  $t_1$  and  $t_3$  increase (see figure 1 for an example). As a result, the total evolution time of the employed three pulses in our scheme is always nonzero even when the control pulses are unbounded because

$$\begin{aligned} \lim_{\substack{|u_2| \rightarrow \infty \\ |u_1|, |u_3| < 1}} (t_1 + t_2 + t_3) &= \lim_{\substack{|u_2| \rightarrow \infty \\ |u_1|, |u_3| < 1}} \frac{2}{r_1} \left[ \operatorname{arccot} \left( \frac{u_1 - u_2}{r_1} \coth \frac{\theta}{2} - \frac{1}{r_1} \sqrt{\Delta} \right) \right] + \frac{2}{r_1} m\pi \\ &+ \lim_{\substack{|u_2| \rightarrow \infty \\ |u_1|, |u_3| < 1}} \frac{2}{r_3} \left[ \operatorname{arccot} \left( \frac{u_3 - u_2}{r_3} \coth \frac{\theta}{2} - \frac{1}{r_3} \sqrt{\Delta} \right) \right] + \frac{2}{r_3} n\pi \\ &= \frac{\pi}{4} \left\{ \frac{2}{r_1} [4m + 1 - \operatorname{sign}((u_2 - u_1)\theta)] + \frac{2}{r_3} [4n + 1 - \operatorname{sign}((u_2 - u_3)\theta)] \right\} \\ &\geq \min \left[ \left( \frac{3}{r_1} + \frac{1}{r_3} \right) \pi, \left( \frac{2}{r_1} + \frac{2}{r_3} \right) \pi, \left( \frac{1}{r_1} + \frac{3}{r_3} \right) \pi \right] > 0. \end{aligned}$$



**Figure 1.** The durations of the control pulse for achieving  $e^{-i2.5K_2}$  with respect to different  $u_2$  according to the formulae in (12), where  $u_1 = 0.1, u_3 = 0.8, m = n = 1$ .



**Figure 2.** The durations of the control pulse for achieving  $e^{-i0.2K_2}$  with respect to different  $u_2$  according to formula (15), where  $u_1 = 0, u_3 = 0.4, m = n = 1, l = 0$ .

The case of  $0 < C \leq 1$  is more complicated. However, one can still observe similar trade-off between the values of  $t_2$  and  $u_2$  when  $\theta$  satisfies the conditions in proposition 1 (see figure 2 for an example). Particularly,  $u_1 = u_3 = 0$  reduces equation (15) to

$$\begin{cases} t_1 = 2 \operatorname{arccot} \left( -u_2 \coth \frac{\theta}{2} \pm \sqrt{u_2^2 \coth^2 \frac{\theta}{2} - 1} \right) + 2m\pi, \\ t_2 = \frac{2}{r_2} \left[ \operatorname{arccot} \left( \mp \frac{1}{r_2} \sqrt{u_2^2 \coth^2 \frac{\theta}{2} - 1} \right) + l\pi \right], \\ t_3 = 2 \operatorname{arccot} \left( -u_2 \coth \frac{\theta}{2} \pm \sqrt{u_2^2 \coth^2 \frac{\theta}{2} - 1} \right) + 2n\pi. \end{cases} \quad (17)$$

The range of the realizable operators within three pulses is largely limited when the bound  $C < 1$ . Nevertheless, one can find an appropriate integer  $N$  such that  $\theta' = \frac{\theta}{N}$  satisfies (13) when  $\theta$  is beyond the region defined in (13), and find a decomposition  $e^{-i\frac{\theta}{N}K_2} = \prod_{k=1}^3 e^{-it_k(K_3+u_k K_2)}$  so that  $e^{-i\theta K_2}$  can be realized with repeated sequences, i.e.,  $e^{-i\theta K_2} = \left[ \prod_{k=1}^3 e^{-it_k(K_3+u_k K_2)} \right]^N$ .

Explicit structured decomposition algorithms for an arbitrary target  $g(\xi, \mu, \zeta)$  with a prescribed bound on the amplitude of the control pulses are summarized as follows:

*Algorithm (a).* The decomposing algorithm for  $C > 1$

- step 1. Select an appropriate control amplitude  $|u_2| \in (1, C]$ ;
- step 2. Determine the sign of  $u_2$  by the constraint  $u_2\mu \geq 0$ . Set  $u_1 = u_3 = 0$  and have  $(m, n) = (1, 1)$ . Use equation (16) to calculate  $t_1, t_2$  and  $t_3$ ;
- step 3. Modulo the parameters  $\xi + t_1$  and  $\zeta + t_3$  by  $2\pi$  so that they both fall in  $[0, 2\pi)$ ;
- step 4. The resulting factorization is  $g(\xi, \mu, \zeta) = e^{-i(\xi+t_1)K_3} e^{-it_2(K_3+u_2K_2)} e^{-i(\zeta+t_3)K_3}$ .

*Algorithm (b).* The decomposing algorithm for  $C \leq 1$

- step 1. Let  $N$  be the minimum integer such that  $N \geq \frac{|\eta|}{2 \operatorname{artanh} C}$ ;
- step 2. Select an appropriate  $u_2$  such that  $|u_2| \in \left[ \left| \tanh \frac{\eta}{2N} \right|, C \right]$ ;
- step 3. Determine the sign of  $u_2$  and let  $u_2\mu > 0$ . Set  $u_1 = u_3 = 0$  and have  $(m, n) = (1, 1)$ , then use equation (17) to calculate  $t_1, t_2$  and  $t_3$ ;
- step 4. Modulo the parameters  $\xi + t_1, \zeta + t_3$  and  $t_1 + t_3$  by  $2\pi$  so that they fall in  $[0, 2\pi)$ ;
- step 5. The resulting decomposition is  $e^{-i(\xi+t_1)K_3} \left[ e^{-it_2(K_3+u_2K_2)} e^{-i(t_1+t_3)K_3} \right]^{N-1} e^{-it_2(K_3+u_2K_2)} \times e^{-i(\zeta+t_3)K_3}$ .

**Example 1.** The hyperbolic type transformation  $e^{-i4K_2}$  can be realized with  $H_0 = K_3, H_1 = K_2$  and  $C = 0.6$ . One may choose  $N = \left\lceil \frac{4}{2 \operatorname{artanh}(0.6)} \right\rceil + 1 = 3, \theta = 4/N = 4/3, u_1 = u_3 = 0, u_2 = C = 0.6$ , then compute from formula (17) that  $t_1 = 4.4722, t_2 = 4.6696, t_3 = 4.4722$ . Thus a possible decomposition for  $e^{-i4K_2}$  is  $\prod_{k=1}^9 e^{-it_k(K_3+u_k K_2)}$ , with  $t_1 = t_3 = t_4 = t_6 = t_7 = t_9 = 4.4722, t_2 = t_5 = t_8 = 4.6696; u_1 = u_3 = u_4 = u_6 = u_7 = u_9 = 0, u_2 = u_5 = u_8 = 0.6$ .

### 3.2. The case $H_0 = K_2, H_1 = K_3$

In this case, the factors that can be realized by the free evolution of the quantum system (1) are those generated by  $K_2$ . Based on the Euler parametrization (7), similarly, the key to construct a structured decomposition for an arbitrary  $SU(1, 1)$  element is to decompose  $e^{-i\theta K_3}$  as

$$e^{-i\theta K_3} = \prod_{k=1}^3 e^{-it_k(K_2+u_k K_3)}, \tag{18}$$

where  $t_k \geq 0, |u_k| \leq C, k = 1, 2, 3$ .

According to [34], however, it is more convenient to use the Euler parametrization (8) and (9), where the generator  $K_2$  is diagonalized, to compute the representation matrix (or propagator) elements under noncompact basis of the UIR's of  $SU(1, 1)$ . Or in the language of quantum control theory, as the free Hamiltonian of the involved quantum control system here is the noncompact operator  $K_2$ , the Euler parametrization (8) and (9) will be more convenient to describe the population transition between different eigenstates of  $K_2$ . Thus algorithms are needed to find the structured decomposition

$$e^{-i\theta K_1} = \prod_{k=1}^3 e^{-it_k(K_2+u_k K_3)}, \tag{19}$$

where  $t_k \geq 0, |u_k| \leq C, k = 1, 2, 3$ .



**Proposition 2.** For any  $\theta \in (-\pi, \pi)$  and  $C > 1$ , the decomposition (18) can be realized with the time durations

$$\begin{cases} t_1 = \frac{2}{r_1} \left[ \operatorname{arccoth} \left( \frac{u_1 - u_2}{r_1} \cot \frac{\theta}{2} + \frac{1}{r_1} \sqrt{\Delta} \right) \right], \\ t_2 = \frac{2}{r_2} \left[ \operatorname{arccot} \left( -\frac{1}{r_2} \sqrt{\Delta} \right) + 2l\pi \right], \\ t_3 = \frac{2}{r_3} \left[ \operatorname{arccoth} \left( \frac{u_3 - u_2}{r_3} \cot \frac{\theta}{2} + \frac{1}{r_3} \sqrt{\Delta} \right) \right], \end{cases} \quad (20)$$

where  $(u_1, u_2, u_3) \in \Xi_+ \cap \Xi_0$ ,

$$\begin{aligned} \Xi_+ &= \left\{ (u_1, u_2, u_3) \mid \Delta \geq 0; \frac{u_k - u_2}{r_k} \cot \frac{\theta}{2} + \frac{1}{r_k} \sqrt{\Delta} \geq 1, k = 1, 3 \right\}, \\ \Xi_0 &= \{(u_1, u_2, u_3) \mid -1 < u_1, u_3 < 1, 1 < |u_2| < C\}, \end{aligned}$$

$r_1 = \sqrt{1 - u_1^2}, r_2 = \sqrt{u_2^2 - 1}, r_3 = \sqrt{1 - u_3^2}, \Delta = (u_2 - u_1)(u_2 - u_3)(\cot^2 \frac{\theta}{2} + 1) + (1 - u_2^2)$ . The integer  $l$  is chosen to keep  $t_2$  positive.

**Proof.** See appendix B. □

The result stated in proposition 2 also provides a rather wide class of control laws for achieving a given target. In such decomposition, only the second term  $e^{-it_2(K_2+u_2K_3)}$  is elliptical, which can be used to adjust  $t_1, t_2$  and  $t_3$  to be positive. Similarly, setting the first and the second pulses  $u_1$  and  $u_3$  to zero will lead to the simplest expression of time durations

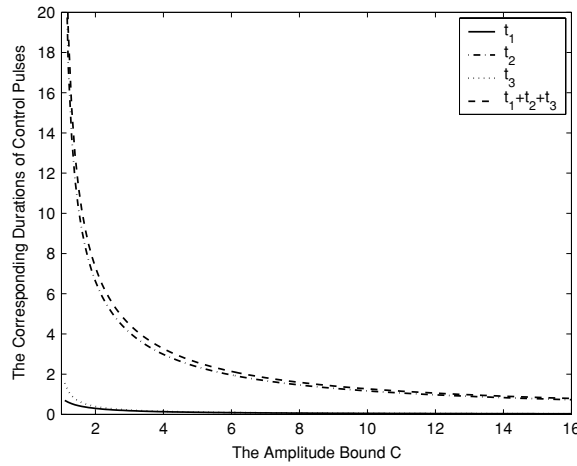
$$\begin{cases} t_1 = 2 \operatorname{arccoth} \left( -u_2 \cot \frac{\theta}{2} + \sqrt{1 + u_2^2 \cot^2 \frac{\theta}{2}} \right), \\ t_2 = \frac{2}{r_2} \left[ \operatorname{arccot} \left( -\frac{1}{r_2} \sqrt{1 + u_2^2 \cot^2 \frac{\theta}{2}} \right) + 2l\pi \right], \\ t_3 = 2 \operatorname{arccoth} \left( -u_2 \cot \frac{\theta}{2} + \sqrt{1 + u_2^2 \cot^2 \frac{\theta}{2}} \right). \end{cases} \quad (21)$$

In comparison with the case when  $H_0 = K_3, H_l = K_2$ , the pulse durations  $t_1, t_2$  and  $t_3$  can be designed to be arbitrary short in the limit of unbounded controls (see figure 3 for an example), because one can verify from equation (20) that

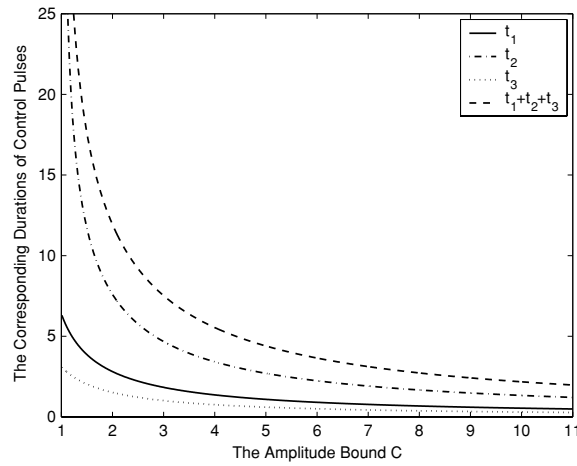
$$\lim_{\substack{|u_2| \rightarrow \infty \\ |u_1|, |u_3| < 1}} t_1 = \lim_{\substack{|u_2| \rightarrow \infty \\ |u_1|, |u_3| < 1}} t_2 = \lim_{\substack{|u_2| \rightarrow \infty \\ |u_1|, |u_3| < 1}} t_3 = 0. \quad (22)$$

It should be noted that all the three factors  $e^{-it_1(K_2+u_1K_3)}, e^{-it_2(K_2+u_2K_3)}$  and  $e^{-it_3(K_2+u_3K_3)}$  on the right-hand side of (18) can be designed to be simultaneously elliptical, i.e.,  $|u_1|, |u_2|, |u_3| \in (1, C]$ , with the corresponding control durations being

$$\begin{cases} t_1 = \frac{2}{r_1} \left[ \operatorname{arccot} \left( \frac{u_1 - u_2}{r_1} \cot \frac{\theta}{2} \pm \frac{1}{r_1} \sqrt{\Delta} \right) + 2m\pi \right], \\ t_2 = \frac{2}{r_2} \left[ \operatorname{arccot} \left( \mp \frac{1}{r_2} \sqrt{\Delta} \right) + 2l\pi \right], \\ t_3 = \frac{2}{r_3} \left[ \operatorname{arccot} \left( \frac{u_3 - u_2}{r_3} \cot \frac{\theta}{2} \pm \frac{1}{r_3} \sqrt{\Delta} \right) + 2n\pi \right], \end{cases} \quad (23)$$



**Figure 3.** The durations of the control pulse for achieving  $e^{i0.9K_3}$  with respect to different  $u_2$  according to formula (20), where  $u_1 = 0.1, u_3 = 0.9, l = 1$ .



**Figure 4.** The durations of the control pulse for achieving  $e^{-i1.5K_3}$  with respect to different  $u_2$  according to formula (23), where  $u_1 = 2u_2, u_3 = 5u_2, m = l = n = 1$ .

where the integers  $m, n$  and  $l$  are introduced so that  $t_1, t_2$  and  $t_3$  are positive. The parities of  $m$  and  $n$  are identical when  $(u_1 - u_2)\theta \geq 0$ , and opposite when  $(u_1 - u_2)\theta < 0$ . From equation (23), we can obtain the following limitations for  $t_1, t_2$  and  $t_3$  as

$$\lim_{\substack{|u_2| \rightarrow \infty \\ |u_1| = O(|u_2|) \\ |u_3| = O(|u_2|)}} t_1 = \lim_{\substack{|u_2| \rightarrow \infty \\ |u_1| = O(|u_2|) \\ |u_3| = O(|u_2|)}} t_2 = \lim_{\substack{|u_2| \rightarrow \infty \\ |u_1| = O(|u_2|) \\ |u_3| = O(|u_2|)}} t_3 = 0. \tag{24}$$

The above equation indicates that the action time  $t_1, t_2$  and  $t_3$ , can be designed arbitrary small as long as the upper bound of the control pulses is large enough (see figure 4 for an example).

**Proposition 3.** For any  $\theta \in \mathbb{R}$  and  $C > 1$ , the decomposition (19) can be realized with time durations

$$\begin{cases} t_1 = \frac{1}{r_1} \left[ \operatorname{arccot} \left( -\frac{\operatorname{sign}(\Delta_{13}/\Delta_{23})}{r_1} \sqrt{\frac{\Delta_{12}\Delta_{13}}{\Delta_{23}}} \right) + 2m\pi \right], \\ t_2 = \frac{1}{r_2} \operatorname{arcoth} \left[ \frac{1}{r_2} \sqrt{\frac{\Delta_{12}\Delta_{23}}{\Delta_{13}}} \right], \\ t_3 = \frac{1}{r_3} \left\{ \operatorname{arctan} \left[ \frac{r_3(\Delta_{13} - \Delta_{23})\operatorname{sign}(\Delta_{23})}{(u_1 - u_2)(u_3 - \coth \theta)} \sqrt{\frac{\Delta_{12}}{\Delta_{13}\Delta_{23}}} \right] + 2n\pi \right\}, \end{cases} \quad (25)$$

where  $r_1 = \sqrt{u_1^2 - 1}$ ,  $r_2 = \sqrt{1 - u_2^2}$ ,  $r_3 = \sqrt{u_3^2 - 1}$ ,  $\Delta_{12} = 1 - u_1u_2 + (u_1 - u_2) \coth \theta$ ,  $\Delta_{13} = 1 - u_1u_3 + (u_1 - u_3) \coth \theta$ ,  $\Delta_{23} = 1 - u_2u_3 + (u_2 - u_3) \coth \theta$ ,  $\Theta_0 = \{(u_1, u_2, u_3) | 1 < |u_1|, |u_3| \leq C, |u_2| < 1\}$ ,  $\Theta_+ = \{(u_1, u_2, u_3) | \frac{\Delta_{12}\Delta_{13}}{\Delta_{23}} \geq 0, \frac{1}{r_2} \sqrt{\frac{\Delta_{12}\Delta_{23}}{\Delta_{13}}} \geq 1\}$ ,  $(u_1, u_2, u_3) \in \Theta_0 \cap \Theta_+$ , and the integers  $m$  and  $n$  are chosen so that  $t_1$  and  $t_3$  are positive.

**Proof.** The cumbersome proof is omitted since similar to that of the last two propositions. □

In the structured decomposition (19), the two terms  $e^{-it_1(K_2+u_1K_3)}$  and  $e^{-it_3(K_2+u_3K_3)}$  are elliptical, while the second hyperbolic term can be taken as a free evolution. Similarly, with the increase of the amplitudes of the control pulses, the corresponding durations will decrease and tend to zero.

The propositions 2 and 3 provide constructive algorithms for decomposing elements in  $SU(1, 1)$  in the forms of  $g(\xi, \mu, \zeta)$ ,  $h(\xi, \mu, \zeta)$  and  $k_l(\xi, \nu, \zeta)$  ( $l = 0, 1, 2, 3$ ) described in (7), (8) and (9), respectively, as follows.

*Algorithm (c).* The algorithm for  $g(\xi, \eta, \zeta)$

*step 1.* Let  $N = \lceil \frac{|\xi|}{\pi} \rceil + 1$  and  $M = \lceil \frac{|\zeta|}{\pi} \rceil + 1$ ;

*step 2.* Let  $|u_{21}| \in (1, C]$  and achieve the decomposition  $e^{-i\frac{\xi}{N}K_3} = e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} \times e^{-it_{31}K_2}$  according to (21);

*step 3.* Let  $|u_{22}| \in (1, C]$ , repeatedly, achieve the decomposition  $e^{-i\frac{\xi}{M}K_3} = e^{-it_{12}K_2} \times e^{-it_{22}(K_2+u_{22}K_3)} e^{-it_{32}K_2}$ ;

*step 4.* The required decomposition is then

$$g(\xi, \eta, \zeta) = [e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} e^{-it_{31}K_2}]^N e^{-i\eta K_2} [e^{-it_{12}K_2} e^{-it_{22}(K_2+u_{22}K_3)} e^{-it_{32}K_2}]^M. \quad (26)$$

*Algorithm (d).* The algorithm for  $h(\xi, \mu, \zeta)$

*step 1.* Let  $p = \frac{1-\operatorname{sign}(\xi)}{2}$  and  $q = \frac{1-\operatorname{sign}(\zeta)}{2}$ ;

*step 2.* Decompose  $e^{-i\frac{\xi}{2}K_3}$  into  $e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} e^{-it_{31}K_2}$  by equation (21), where  $|u_{21}| \in (1, C]$ ;

*step 3.* Repeatedly, obtain the decomposition of  $e^{-i\mu K_3}$  as  $[e^{-it_{12}K_2} e^{-it_{22}(K_2+u_{22}K_3)} e^{-it_{32}K_2}]^N$  in the same way as that introduced in algorithm(c), where  $|u_{23}| \in (1, C]$ ;

*step 4.* Note that  $e^{-i\frac{3}{2}\pi K_3} e^{-i\xi K_2} e^{-i\pi K_3} = e^{-i(-\xi)K_2}$ , thus we finally have

$$\begin{aligned} h(\xi, \mu, \zeta) &= [e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} e^{-it_{31}K_2}]^{6p} e^{-i|\xi|K_2} [e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} e^{-it_{31}K_2}]^{2p} \\ &\quad \times [e^{-it_{12}K_2} e^{-it_{22}(K_2+u_{22}K_3)} e^{-it_{32}K_2}]^N [e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} e^{-it_{31}K_2}]^{6q} \\ &\quad \times e^{-i|\zeta|K_2} [e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} e^{-it_{31}K_2}]^{2q}. \end{aligned}$$

*Algorithm (e).* The algorithm for  $k_l(\xi, \nu, \zeta)$

- step 1.* Calculate the decomposition of  $e^{-i\frac{\xi}{2}K_3}$ ,  $e^{-i\xi K_2}$  and  $e^{-i\zeta K_2}$  according to algorithm (d);
- step 2.* Make use of equation (25) and decompose  $e^{-i\nu K_1}$  into  $e^{-it_1(K_2+u_1K_3)}$   $e^{-it_2K_2}$   $e^{-it_3(K_2+u_3K_3)}$ , where  $|u_1|, |u_3| \in (1, C], u_2 = 0$ ;
- step 3.* Obtain the decomposition of  $k_l(\xi, \nu, \zeta)$  ( $l = 0, 1, 2, 3$ ) as

$$k_l(\xi, \nu, \zeta) = [e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} e^{-it_{31}K_2}]^{6p} e^{-i|\xi|K_2} [e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} e^{-it_{31}K_2}]^{2p} \times e^{-it_1(K_2+u_1K_3)} e^{-it_2K_2} e^{-it_3(K_2+u_3K_3)} [e^{-it_{12}K_2} e^{-it_{22}(K_2+u_{22}K_3)} e^{-it_{32}K_2}]^{2l} \times [e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} e^{-it_{31}K_2}]^{6q} e^{-i|\zeta|K_2} [e^{-it_{11}K_2} e^{-it_{21}(K_2+u_{21}K_3)} e^{-it_{31}K_2}]^{2q}.$$

### 3.3. The general case

In this section,  $H_0$  and  $H_l$  are allowed to be arbitrary linearly independent elements in the  $su(1, 1)$  Lie algebra, i.e.,  $H_0 = a_1K_1 + b_1K_2 + c_1K_3$  and  $H_l = a_2K_1 + b_2K_2 + c_2K_3$ , where the two real vectors  $[a_1, b_1, c_1]^T$  and  $[a_2, b_2, c_2]^T$  are linearly independent.

Similarly, to accomplish the structured decomposition for  $SU(1, 1)$  elements, we only need to decompose  $e^{-i\theta K_3}$  and  $e^{-i\tau K_2}$ . For simplicity, let

$$\Omega = \left\{ u \in \mathbb{R} \mid \frac{(a_1 + ua_2)^2 + (b_1 + ub_2)^2}{(c_1 + uc_2)^2} < 1, |u| \leq C \right\}, \tag{27}$$

$$\Theta(u_1, u_2) = \frac{(a_1 + u_2a_2)(b_1 + u_1b_2) - (a_1 + u_1a_2)(b_1 + u_2b_2)}{(a_1 + u_1a_2)(a_1 + u_2a_2) + (b_1 + u_1b_2)(b_1 + u_2b_2)},$$

and

$$\Upsilon = \{\sigma \mid \sigma = \arctan \Theta(u_1, u_2); u_1, u_2 \in \Omega\}.$$

Obviously, there exists a closed interval  $[\theta_{\min}, \theta_{\max}]$  in  $\Upsilon$ .

First, let us study the procedure for realizing the structured decomposition of  $e^{-i\theta K_3}$ . It is obvious that if  $\theta \in [2\theta_{\min}, 2\theta_{\max}]$  there exist at least two different elements  $u_1$  and  $u_2$ , which satisfy the equation

$$\Theta(u_1, u_2) = \tan \frac{\theta}{2}, \tag{28}$$

in the defined set  $\Omega$  above. Let  $u_{11}$  and  $u_{12}$  satisfy  $\Theta(u_{11}, u_{12}) = \tan \frac{\theta}{2}$ , and then with a few routine calculations we can obtain the following decomposition

$$e^{-i\theta K_3} = \prod_{k=1}^2 e^{-i t_{1k}(H_0 + u_{1k}H_l)}, \tag{29}$$

where

$$\begin{cases} t_{11} = \frac{2}{r_1} \left[ \arctan \frac{r_1 \sin \frac{\theta}{2} (y_2 \sin \frac{\theta}{2} - x_2 \cos \frac{\theta}{2})}{x_1 z_2 + y_2 z_1 \sin \frac{\theta}{2} \cos \frac{\theta}{2} - x_2 z_1 \cos^2 \frac{\theta}{2}} + 2m\pi \right], \\ t_{12} = \frac{2}{r_2} \left[ \arctan \frac{x_1 r_2 \sin \frac{\theta}{2}}{(x_1 z_2 - x_2 z_1) \cos \frac{\theta}{2} + y_2 z_1 \sin \frac{\theta}{2}} + 2n\pi \right], \end{cases} \tag{30}$$

where  $x_k = a_1 + u_{1k}a_2$ ,  $y_k = b_1 + u_{1k}b_2$ ,  $z_k = c_1 + u_{1k}c_2$ ,  $r_k = \sqrt{z_k^2 - x_k^2 - y_k^2}$ ,  $k = 1, 2$ . The integers  $m$  and  $n$  are chosen to keep  $t_{11}$  and  $t_{12}$  positive.

If  $\theta \notin [2\theta_{\min}, 2\theta_{\max}]$  we can find two integers  $N(>0)$  and  $M$ , which satisfy the inequality

$$2\theta_{\min} \leq \tilde{\theta} = \frac{M \times 2\pi + \theta}{N} \leq 2\theta_{\max}. \tag{31}$$

Thus,

$$\begin{aligned} \exp(-i\theta K_3) &= \exp[-i(M \times 2\pi + \theta)K_3] = \left[ \exp\left(-i\frac{M \times 2\pi + \theta}{N}K_3\right) \right]^N \\ &= [\exp(-i\tilde{\theta}K_3)]^N. \end{aligned} \quad (32)$$

Consequently, it can be concluded that for arbitrary  $\theta$  the factor  $e^{-i\theta K_3}$  can be decomposed as

$$e^{-i\theta K_3} = \prod_{k=1}^{Q_1} e^{-it_k^{(1)}(H_0 + u_k^{(1)}H_I)} \quad (33)$$

when the set  $\Omega$  is nonempty, where  $t_k^{(1)} \geq 0$ ,  $|u_k^{(1)}| \leq C$ ,  $k = 1, 2, \dots, Q_1$ .

Next, let us study the structured decomposition for  $e^{-i\tau K_2}$ . Let  $u_{21}, u_{22} (\neq u_{21}), u_{23} (= u_{21}) \in \Omega$ ,  $u'_{2k} = \frac{\sqrt{(a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2}}{|c_1 + u_{2k}c_2|}$  ( $k = 1, 2, 3$ ) and make use of proposition 1, then we can decompose  $e^{-i\tau K_2}$  for any  $\tau \in [0, \infty)$  as

$$\exp(-i\tau K_2) = \left\{ \prod_{k=1}^3 \exp[-it'_{2k}(K_3 + u'_{2k}K_2)] \right\}^{Q'} \quad (34)$$

where  $t'_{2k} \geq 0$ ,  $k = 1, 2, 3$  and  $Q'$  is a positive integer. Therefore

$$\begin{aligned} \exp(-i\tau K_2) &= \left\{ \prod_{k=1}^3 e^{-it'_{2k}(K_3 + u'_{2k}K_2)} \right\}^{Q'} \\ &= \left\{ \prod_{k=1}^3 e^{-i\alpha_k K_3} \exp\left(-it'_{2k} \left[ u'_{2k} \frac{(a_1 + u_{2k}a_2)K_1 + (b_1 + u_{2k}b_2)K_2}{\sqrt{(a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2}} + K_3 \right] \right) e^{-i\gamma_k K_3} \right\}^{Q'} \\ &= \left\{ \prod_{k=1}^3 e^{-i(\alpha_k + \beta_k)K_3} \exp\left(-it'_{2k} \left[ u'_{2k} \frac{(a_1 + u_{2k}a_2)K_1 + (b_1 + u_{2k}b_2)K_2}{\sqrt{(a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2}} \right. \right. \right. \\ &\quad \left. \left. \left. + \text{sign}(c_1 + u_{2k}c_2)K_3 \right] \right) e^{-i(\gamma_k + \beta_k)K_3} \right\}^{Q'} \\ &= \left\{ \prod_{k=1}^3 e^{-i(\alpha_k + \beta_k)K_3} \exp\left(-i\frac{t'_{2k}}{|c_1 + u_{2k}c_2|} [(a_1 K_1 + b_1 K_2 + c_1 K_3) \right. \right. \\ &\quad \left. \left. \left. + u_{2k}(a_2 K_1 + b_2 K_2 + c_2 K_3)] \right) e^{-i(\gamma_k + \beta_k)K_3} \right\}^{Q'} \\ &= \left\{ \prod_{k=1}^3 e^{-i(\alpha_k + \beta_k)K_3} e^{-it'_{2k}(H_0 + u_{2k}H_I)} e^{-i(\gamma_k + \beta_k)K_3} \right\}^{Q'} \quad (35) \end{aligned}$$

where

$$t_{2k} = \frac{t'_{2k}}{|c_1 + u_{2k}c_2|} \geq 0, \quad (36)$$

$$\alpha_k = \arccos \frac{\text{sign}(a_1 + u_{2k}a_2)(b_1 + u_{2k}b_2)}{\sqrt{(a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2}} + \frac{3}{2}[1 - \text{sign}(a_1 + u_{2k}a_2)]\pi, \quad (37)$$

$$\gamma_k = 4\pi - \alpha_k, \quad (38)$$

$$\beta_k = \begin{cases} 0 & (\text{if } c_1 + u_{2k}c_2 \geq 0), \\ \text{sign}(w_k^2 - v_k^2) \arcsin \frac{-2w_k v_k}{w_k^2 + v_k^2} + \frac{1 - \text{sign}(w_k^2 - v_k^2)}{2} \pi & \\ 0 & (\text{if } c_1 + u_{2k}c_2 < 0), \end{cases} \quad (39)$$

$$w_k = \begin{cases} \cosh[t_{2k} \sqrt{(a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2 - (c_1 + u_{2k}c_2)^2}] & (\text{if } (a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2 - (c_1 + u_{2k}c_2)^2 \geq 0), \\ \cos[t_{2k} \sqrt{(c_1 + u_{2k}c_2)^2 - (a_1 + u_{2k}a_2)^2 - (b_1 + u_{2k}b_2)^2}] & (\text{if } (a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2 - (c_1 + u_{2k}c_2)^2 < 0), \end{cases} \quad (40)$$

$$v_k = \begin{cases} \frac{c_1 + u_{2k}c_2}{\sqrt{(a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2 - (c_1 + u_{2k}c_2)^2}} \times \sinh(t_{2k} \sqrt{(a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2 - (c_1 + u_{2k}c_2)^2}) & (\text{if } (a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2 - (c_1 + u_{2k}c_2)^2 \geq 0), \\ \frac{c_1 + u_{2k}c_2}{\sqrt{(c_1 + u_{2k}c_2)^2 - (a_1 + u_{2k}a_2)^2 - (b_1 + u_{2k}b_2)^2}} \times \sin(t_{2k} \sqrt{(c_1 + u_{2k}c_2)^2 - (a_1 + u_{2k}a_2)^2 - (b_1 + u_{2k}b_2)^2}) & (\text{if } (a_1 + u_{2k}a_2)^2 + (b_1 + u_{2k}b_2)^2 - (c_1 + u_{2k}c_2)^2 < 0). \end{cases} \quad (41)$$

From equations (33) and (35), we can draw the conclusion that for arbitrary  $\tau$  the factor  $e^{-i\tau K_2}$  can be decomposed as

$$e^{-i\tau K_2} = \prod_{k=1}^{Q_2} e^{-it_k^{(2)}(H_0 + u_k^{(2)}H_I)} \quad (42)$$

when the set  $\Omega$  is nonempty, where  $t_k^{(2)} \geq 0, |u_k^{(2)}| \leq C, k = 1, 2, \dots, Q_2$ .

Finally, we have the following theorem:

**Theorem 1.** For any given  $g(\xi, \eta, \zeta) \in SU(1, 1)$ , the decomposition  $g(\xi, \eta, \zeta) = \prod_{k=1}^{Q_2} e^{-it_k(H_0 + u_k H_I)}$  with  $t_k \geq 0$  and  $|u_k| \leq C$  always exists if the set  $\Omega$  in (27) is nonempty.

In this theorem, the nonemptiness of set  $\Omega$  assures that  $H_0 + uH_I$  can be adjusted to be the generator of a compact one-parameter subgroup of  $SU(1, 1)$ . It is evident that if the structured decomposition  $g(\xi, \eta, \zeta) = \prod_{k=1}^{Q_2} e^{-it_k(H_0 + u_k H_I)}$  is realizable for arbitrary  $(\xi, \eta, \zeta)$ , every element in  $SU(1, 1)$  will be attainable for the involved quantum system (1). The controls  $u(t)$  that will send the system from the initial  $U(0) = I$  to the terminal  $U(t) = g(\xi, \eta, \zeta)$  are piecewise constant functions of time. Thus the nonemptiness of the set  $\Omega$  is also a sufficient condition of system controllability.

The following is the summarized algorithm for the structured decomposition in the general case.

*Algorithm (f).* Decomposing algorithm for the general case

- step 1. Check  $\Omega$  for the given Hamiltonians  $H_0$  and  $H_I$  and the prescribed control bound  $C$ . If the set is nonempty goto next step, otherwise the required structured decomposition is likely to be inexistent, thus stop the procedure;
- step 2. Decompose  $e^{-i\eta K_2}$  into (34) according to algorithm (a) or (b);
- step 3. Based on the result obtained in step 2, make use of formulae (36)–(41) and obtain the decomposition for  $e^{-i\eta K_2}$  provided in (35);

step 4. Prepare the compact terms  $e^{-i\theta K_3}$  appeared in the above steps and in the parametrization formula  $g(\xi, \eta, \zeta)$  as (33);

step 5. Unify the above steps and complete the structured decomposition for  $g(\xi, \eta, \zeta)$ .

#### 4. Applications

In this section, we will show how the decomposition technique discussed above can be applied to control a realistic physical system evolving on  $SU(1, 1)$ . Generally speaking, the relevant control objectives can be categorized as follows: (i) realize a transition between two different states in  $\mathcal{D}^+(k)$ , such as the basis states  $|m, k\rangle$  or the superposition states  $\sum_{m=0}^{\infty} c_m |m, k\rangle$  (where  $\sum_{m=0}^{\infty} |c_m|^2 = 1$ ); (ii) maximize the expectation value  $\langle \psi | \hat{F} | \psi \rangle$  of a selected observable  $\hat{F}$ , such as the expectation value of the free Hamiltonian  $H_0$ , which corresponds to the energy of the undergoing quantum system. In this section we will concentrate on the first case.

In order to realize a transition between two discrete basis  $|m_1, k\rangle$  and  $|m_2, k\rangle$ , one may find a (nonunique) propagator  $U_f = g(\xi, \eta, \zeta) = e^{-i\xi K_3} e^{-i\eta K_2} e^{-i\zeta K_3}$  that will realize a desired population transfer ratio  $P_{m_1 m_2}^k$ . Since  $K_3$  is diagonalized in the UIR  $\mathcal{D}^+(k)$ , the two compact operators  $e^{-i\xi K_3}$  and  $e^{-i\zeta K_3}$  only affect the phase between different discrete basis states, and will not cause any population transfer. Thus the relevant population transfer ratio  $P_{m_1 m_2}^k$  is completely determined by the term  $e^{-i\eta K_2}$ , and

$$P_{m_1 m_2}^k = |\langle m_1, k | U_f | m_2, k \rangle|^2 = |\langle m_1, k | e^{-i\eta K_2} | m_2, k \rangle|^2 = [V_{m_1 m_2}^k(\eta)]^2, \quad (43)$$

where  $V_{m_1 m_2}^k(\eta) = (-1)^{m_2 - m_1} V_{m_2 m_1}^k(\eta)$  [33, 35], and for  $m_1 \geq m_2$

$$V_{m_1 m_2}^k(\eta) = (-1)^{m_2 - k} \frac{1}{(2k - 1)!} \left[ \frac{(m_1 + k - 1)!(m_2 + k - 1)!}{(m_1 - k)!(m_2 - k)!} \right] \left( \tanh \frac{1}{2} \eta \right)^{m_1 + m_2} \\ \times \left( \cosh \frac{1}{2} \eta \right)^{-2k} F \left( k - m_2; k - m_1; 2k; -\frac{1}{\sinh^2 \frac{1}{2} \eta} \right). \quad (44)$$

Once the terminal population transfer ratio  $P_{m_1 m_2}^k$  is provided, one can immediately compute the corresponding parameter  $\eta$  from (44) and then carry out the procedure to design the proper control field.

As an illustration, consider the following quantum system

$$i \frac{d\varphi(t)}{dt} = [K_3 + u(t)K_2]\varphi(t), \quad (45)$$

where the prescribed bound of the control amplitude is assumed to be  $C = 0.6$ . Assume the initial of system (45) is  $\varphi(0) = |2, 2\rangle$ , and the target population transfer ratio  $P_{24}^2$  to the terminal  $|4, 2\rangle$  is 0.2194. From the equation  $V_{24}^2(\eta) = \sqrt{P_{24}^2}$ , it can be immediately calculated out to be that  $\eta = 1.3333$ . Thus, making use of the result presented in example 1 the required control field is immediately determined.

It should be mentioned that not all the prescribed transfer ratios  $P_{m_1 m_2}^k \in [0, 1]$  can be realized, because the equation  $V_{m_1 m_2}^k(\eta) = \sqrt{P_{m_1 m_2}^k}$  may have no solution. The similar circumstance may occur in the case when the superposition states are involved. A complete transition between two different states  $|\varphi_1\rangle$  and  $|\varphi_2\rangle$  can be realized only if they are in the same orbit of  $SU(1, 1)$  group, i.e., there exists a  $SU(1, 1)$  transformation which sends  $|\varphi_1\rangle$  to  $|\varphi_2\rangle$ .

However, the control laws can be found to realize the complete transition between two arbitrary  $SU(1, 1)$  coherent states (CS's). The  $SU(1, 1)$  CS, a special superposition state in  $\mathcal{D}^+(k)$ , plays an important role in the field of nonlinear optics as it provides an example of ideal squeezed vacuum state [18]. In the laboratory, the  $SU(1, 1)$  CS has been realized in

many systems such as trapped ions [36–38], quantum electrodynamic cavities [39–41] and solids [42]. It will be exhibited that the desired propagators, evolving over the  $SU(1, 1)$  Lie group, can be achieved by piecewise constant external control pulses. These switching control laws can be easily designed based on the decomposition technique.

Following Perelomov [43], in the UIR  $\mathcal{D}^+(k)$  of  $SU(1, 1)$ , the  $SU(1, 1)$  CS's are defined as

$$\begin{aligned} |\xi, k\rangle &= D(\alpha)|0, k\rangle = \exp(\alpha K_+ - \alpha^* K_-)|0, k\rangle \\ &= (1 - |\xi|^2)^k \sum_{m=0}^{\infty} \left[ \frac{\Gamma(m+2k)}{m! \Gamma(2k)} \right]^{\frac{1}{2}} \xi^m |m, k\rangle, \end{aligned} \quad (46)$$

where  $\alpha = -(\theta/2) e^{-i\varphi}$ ,  $\xi = -\tanh(\theta/2) e^{-i\varphi}$ , with the parameters  $\varphi$  and  $\theta$  obeying  $-\infty < \theta < \infty$ ,  $0 \leq \varphi \leq 2\pi$ . Usually, the defined Perelomov  $SU(1, 1)$  CS's are governed by the quantum control system with the Hamiltonian [17]

$$H(t) = A(t)K_3 + f(t)K_+ + f^*(t)K_- + B(t). \quad (47)$$

Without loss of generality, it can be assumed that  $B(t) = 0$ ,  $A(t) = 2\varpi_0$  and  $f(t) \in \mathbb{R}$  [18], by which equation (47) is reduced to

$$H(t) = 2\varpi_0 K_3 + 2f(t)K_1. \quad (48)$$

The Hamiltonian (48) is also a Foldy-like Hamiltonian used to depict a Bose–Einstein condensate system [20, 44], where  $f(t)$  represents the coupling constant of interbosonic interactions.

To realize Perelomov  $SU(1, 1)$  CS's in a realistic quantum system, a special realization of the Lie algebra is required. In the frame work of bosonic operators, the Hamiltonian (47) can be used to describe the parametric down conversion process as well [45]. There are two different kinds of realizations which are familiar in the literatures [18, 23]. The first kind is the single-mode case, which is used to describe a degenerate parametric amplifier [18, 46]. In this case, the  $su(1, 1)$  generators are given by

$$K_+ = \frac{1}{2}(a^\dagger)^2, \quad K_- = \frac{1}{2}(a)^2, \quad K_3 = \frac{1}{4}(a^\dagger a + a a^\dagger). \quad (49)$$

The second kind of realization is the two-mode case, which describes the non-degenerate parametric amplifier [18, 47]. The corresponding  $su(1, 1)$  generators are

$$K_+ = a^\dagger b^\dagger, \quad K_- = ab, \quad K_3 = a^\dagger a + b^\dagger b + 1. \quad (50)$$

No matter which kind of realization is involved, however, will the structured decomposition be affected. To find a feasible control  $u(t)$  that steers the system (48) from the vacuum state  $|0, k\rangle$  to the target  $|\xi, k\rangle$ , we may rewrite the propagator  $D(\alpha)$  defined in (46) as

$$\begin{aligned} D(\alpha) &= \exp(\alpha K_+ - \alpha^* K_-) \\ &= \exp\{-i[-2 \operatorname{Im}(\alpha)K_1 - 2 \operatorname{Re}(\alpha)K_2]\} \\ &= \exp(it_1 K_3) \exp(-i2|\alpha|K_2) \exp(it_3 K_3), \end{aligned} \quad (51)$$

where  $t_1 = \arccos[\operatorname{sign}(\operatorname{Im}(\alpha))\operatorname{Re}(\alpha)/|\alpha|] + \frac{3}{2}[1 + \operatorname{sign}(\operatorname{Im}(\alpha))]\pi$ ,  $t_3 = 4\pi - t_1$ .

Suppose the prescribed bound of the external control pulses  $C > \varpi_0$ . From proposition 1, the factor  $\exp(-i2|\alpha|K_2)$  can be decomposed as

$$\exp(-i2|\alpha|K_2) = \exp(-it_{21} K_3) \exp\{-it_{22}[2\varpi_0 K_3 + u K_2]\} \exp(-it_{23} K_3), \quad (52)$$



where

$$\begin{cases} t_{21} = 2 \operatorname{arccot} \left[ \frac{u}{2\varpi_0} \coth |\alpha| - \sqrt{\left(\frac{u}{2\varpi_0}\right)^2 \coth^2 |\alpha| - 1} \right] + 2n\pi, \\ t_{22} = \frac{1}{\varpi_0 \sqrt{(u/2\varpi_0)^2 - 1}} \operatorname{arccoth} \sqrt{\frac{(u/2\varpi_0)^2 \coth^2 |\alpha| - 1}{(u/2\varpi_0)^2 - 1}}, \\ t_{23} = 2 \operatorname{arccot} \left[ \frac{u}{2\varpi_0} \coth |\alpha| - \sqrt{\left(\frac{u}{2\varpi_0}\right)^2 \coth^2 |\alpha| - 1} \right] + 2m\pi, \end{cases} \quad (53)$$

where  $2\varpi_0 < u < 2C$ , and  $n = 0, 1, 2, \dots, \infty$ ,  $m - n = 0, \pm 2, \pm 4, \dots, \pm \infty$ . The two integers  $m$  and  $n$  are chosen to assure that  $t_{21}, t_{23} > 0$ . On the other hand, it can be observed that  $\exp\{-i[2\varpi_0 K_3 + u K_2]\} = \exp(-i5\pi/2K_3) \exp\{-i[2\varpi_0 K_3 + u K_1]\} \times \exp(-i3\pi/2K_3)$ , thus we have

$$\begin{aligned} D(\alpha) &= \exp(it_1 K_3) \exp(-it_{21} K_3) \exp(-i5\pi/2K_3) \exp[-it_{22}(2\varpi_0 K_3 + u K_1)] \\ &\quad \times \exp(-i3\pi/2K_3) \exp(-it_{23} K_3) \exp(it_3 K_3) \\ &= \exp[-i(-t_1 + t_{21} + 5\pi/2)K_3] \exp[-it_{22}(2\varpi_0 K_3 + u K_1)] \\ &\quad \times \exp[-i(-t_3 + t_{23} + 3\pi/2)K_3]. \end{aligned} \quad (54)$$

For example, if  $u$  is selected to be  $3\varpi_0$ , we can immediately realize the propagator  $D(-2e^{-i\frac{\pi}{6}})$  by (setting  $\hbar = 1$ )

$$\begin{aligned} D(-2e^{-i\frac{\pi}{6}}) &= \exp\left(-i\frac{3.8398}{\varpi_0} \times 2\varpi_0 K_3\right) \exp\left[-i\frac{1.5386}{\varpi_0} (2\varpi_0 K_3 + 3\varpi_0 K_1)\right] \\ &\quad \times \exp\left(-i\frac{1.7454}{\varpi_0} \times 2\varpi_0 K_3\right). \end{aligned} \quad (55)$$

It indicates that the target Perelomov  $SU(1, 1)$  CS  $|-\tanh(2)e^{-i\frac{\pi}{6}}, k\rangle$  can be achieved from the original state  $|0, k\rangle$  by the following control pulses:

$$f(t) = \begin{cases} 0, & 0 \leq t \leq \frac{1.7454}{\varpi_0}; \\ \frac{3}{2}\varpi_0, & \frac{0.8727}{\varpi_0} < t \leq \frac{3.284}{\varpi_0}; \\ 0, & \frac{1.642}{\varpi_0} < t \leq \frac{7.1239}{\varpi_0}. \end{cases} \quad (56)$$

Similarly, the structured decomposition also offers control laws for complete transitions between two arbitrary  $SU(1, 1)$  CS's.

## 5. Conclusions

This paper presented constructive algorithms to achieve the structured decomposition for an arbitrary  $SU(1, 1)$  matrix under the restrictions **O1** and **O2**. It is shown that any element in  $SU(1, 1)$  can be achieved in this way if the total Hamiltonian  $H_0 + uH_I$  can be adjusted to be the generator of some compact subgroup of  $SU(1, 1)$ . Recall that for quantum systems evolving on the  $SU(2)$  Lie group, since the corresponding total Hamiltonians are always compact, the structured decomposition exists for arbitrary  $H_0$  and  $H_I$  as long as they are linearly independent [2]. We believe that the structured decomposition method can be extended to

controlling quantum systems with more complex noncompact symmetry groups such as the control of  $SU(m, n)$  CS's [48, 49].

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### Appendix A. The proof of proposition 1

(1) For the case of  $|C| > 1$ . Let  $-1 < u_1, u_3 < 1$  and  $1 < |u_2| < C$ . Then from the matrix equation  $\prod_{k=1}^3 e^{-it_k(K_3+u_k K_2)} = e^{-i\theta K_2}$  (or equivalently,  $e^{-it_1(K_3+u_1 K_2)} e^{-it_2(K_3+u_2 K_2)} = e^{-i\theta K_2} e^{it_3(K_3+u_3 K_2)}$ ), we can get the following four equations (actually, only three of them are independent) by equating the entries of the matrices on both sides:

$$\begin{aligned} \cos\left(\frac{t_1 r_1}{2}\right) \cosh\left(\frac{t_2 r_2}{2}\right) - \frac{1 - u_1 u_2}{r_1 r_2} \sin\left(\frac{t_1 r_1}{2}\right) \sinh\left(\frac{t_2 r_2}{2}\right) \\ = \cos\left(\frac{t_3 r_3}{2}\right) \cosh\frac{\theta}{2} - \frac{u_3}{r_3} \sin\left(\frac{t_3 r_3}{2}\right) \sinh\frac{\theta}{2}, \end{aligned} \quad (\text{A.1})$$

$$\begin{aligned} \frac{1}{r_1} \sin\left(\frac{t_1 r_1}{2}\right) \cosh\left(\frac{t_2 r_2}{2}\right) + \frac{1}{r_2} \cos\left(\frac{t_1 r_1}{2}\right) \sinh\left(\frac{t_2 r_2}{2}\right) \\ = -\frac{1}{r_3} \sin\left(\frac{t_3 r_3}{2}\right) \cosh\frac{\theta}{2}, \end{aligned} \quad (\text{A.2})$$

$$\begin{aligned} \frac{u_1}{r_1} \sin\left(\frac{t_1 r_1}{2}\right) \cosh\left(\frac{t_2 r_2}{2}\right) + \frac{u_2}{r_2} \cos\left(\frac{t_1 r_1}{2}\right) \sinh\left(\frac{t_2 r_2}{2}\right) \\ = -\frac{u_3}{r_3} \sin\left(\frac{t_3 r_3}{2}\right) \cosh\frac{\theta}{2} + \cos\left(\frac{t_3 r_3}{2}\right) \sinh\frac{\theta}{2}, \end{aligned} \quad (\text{A.3})$$

$$\frac{u_1 - u_2}{r_1 r_2} \sin\left(\frac{t_1 r_1}{2}\right) \sinh\left(\frac{t_2 r_2}{2}\right) = -\frac{1}{r_3} \sin\left(\frac{t_3 r_3}{2}\right) \sinh\frac{\theta}{2}, \quad (\text{A.4})$$

where  $r_1 = \sqrt{1 - u_1^2}$ ,  $r_2 = \sqrt{u_2^2 - 1}$ ,  $r_3 = \sqrt{1 - u_3^2}$ . Equations (A.1)–(A.4) can be further recast as

$$\begin{cases} \cot\left(\frac{t_1 r_1}{2}\right) = \frac{u_1 - u_2}{r_1} \coth\frac{\theta}{2} \pm \frac{1}{r_1} \sqrt{\Delta}, \\ \coth\left(\frac{t_2 r_2}{2}\right) = \mp \frac{1}{r_2} \sqrt{\Delta}, \\ \cot\left(\frac{t_3 r_3}{2}\right) = \frac{u_3 - u_2}{r_3} \coth\frac{\theta}{2} \pm \frac{1}{r_3} \sqrt{\Delta}, \end{cases} \quad (\text{A.5})$$

where  $\Delta = (u_2 - u_1)(u_2 - u_3)(\coth^2\frac{\theta}{2} - 1) + (u_2^2 - 1)$ . As  $-1 < u_1, u_3 < 1$  and  $|u_2| > 1$ , it can be concluded that  $\Delta > 0$  and  $\frac{1}{r_2} \sqrt{\Delta} > 1$ . Therefore, equation (A.5) is solvable for

$(t_1, t_2, t_3)$ , and the corresponding positive solutions can be written as

$$\begin{cases} t_1 = \frac{2}{r_1} \left[ \operatorname{arccot} \left( \frac{u_1 - u_2}{r_1} \coth \frac{\theta}{2} - \frac{1}{r_1} \sqrt{\Delta} \right) + m\pi \right], \\ t_2 = \frac{2}{r_2} \operatorname{arccoth} \left( \frac{1}{r_2} \sqrt{\Delta} \right), \\ t_3 = \frac{2}{r_3} \left[ \operatorname{arccot} \left( \frac{u_3 - u_2}{r_3} \coth \frac{\theta}{2} - \frac{1}{r_3} \sqrt{\Delta} \right) + n\pi \right], \end{cases} \tag{A.6}$$

where the integers  $m$  and  $n$  are introduced to keep  $t_1$  and  $t_3$  positive, and they have an identical parity when  $(u_2 - u_1)\theta \geq 0$ , otherwise they have different parities.

(2) For the case of  $C \leq 1$ . Let  $|u_1|, |u_3| < C$ , and then from  $e^{-it_1(K_3+u_1K_2)} e^{-it_2(K_3+u_2K_2)} = e^{-i\theta K_2} e^{it_3(K_3+u_3K_2)}$  it can be deduced that

$$\begin{aligned} \cos \left( \frac{t_1 r_1}{2} \right) \cosh \left( \frac{t_2 r_2}{2} \right) - \frac{1 - u_1 u_2}{r_1 r_2} \sin \left( \frac{t_1 r_1}{2} \right) \sin \left( \frac{t_2 r_2}{2} \right) \\ = \cos(t_3 r_3) \cosh \frac{\theta}{2} - \frac{u_3}{r_3} \sin \left( \frac{t_3 r_3}{2} \right) \sinh \frac{\theta}{2}, \end{aligned} \tag{A.7}$$

$$\begin{aligned} \frac{1}{r_1} \sin \left( \frac{t_1 r_1}{2} \right) \cos \left( \frac{t_2 r_2}{2} \right) + \frac{1}{r_2} \cos \left( \frac{t_1 r_1}{2} \right) \sin \left( \frac{t_2 r_2}{2} \right) \\ = -\frac{1}{r_3} \sin \left( \frac{t_3 r_3}{2} \right) \cosh \frac{\theta}{2}, \end{aligned} \tag{A.8}$$

$$\begin{aligned} \frac{u_1}{r_1} \sin \left( \frac{t_1 r_1}{2} \right) \cos \left( \frac{t_2 r_2}{2} \right) + \frac{u_2}{r_2} \cos \left( \frac{t_1 r_1}{2} \right) \sin \left( \frac{t_2 r_2}{2} \right) \\ = -\frac{u_3}{r_3} \sin \left( \frac{t_3 r_3}{2} \right) \cosh \frac{\theta}{2} + \cos \left( \frac{t_3 r_3}{2} \right) \sinh \frac{\theta}{2}, \end{aligned} \tag{A.9}$$

$$\frac{u_1 - u_2}{r_1 r_2} \sin \left( \frac{t_1 r_1}{2} \right) \sin \left( \frac{t_2 r_2}{2} \right) = -\frac{1}{r_3} \sin \left( \frac{t_3 r_3}{2} \right) \sinh \frac{\theta}{2}, \tag{A.10}$$

where  $r_k = \sqrt{1 - u_k^2}$ , ( $k = 1, 2, 3$ ). With a few calculations, one can rewrite equations (A.7)–(A.10) as

$$\begin{cases} \cot \left( \frac{t_1 r_1}{2} \right) = \frac{u_1 - u_2}{r_1} \coth \frac{\theta}{2} \pm \frac{1}{r_1} \sqrt{\Delta}, \\ \cot \left( \frac{t_2 r_2}{2} \right) = \mp \frac{1}{r_2} \sqrt{\Delta}, \\ \cot \left( \frac{t_3 r_3}{2} \right) = \frac{u_3 - u_2}{r_3} \coth \frac{\theta}{2} \pm \frac{1}{r_3} \sqrt{\Delta}, \end{cases} \tag{A.11}$$

where  $\Delta = (u_2 - u_1)(u_2 - u_3)(\coth^2 \frac{\theta}{2} - 1) + (u_2^2 - 1)$ . It is easy to verify that  $\Delta \geq 0$  iff

$$\begin{cases} (u_2 - u_1)(u_2 - u_3) > 0 \\ \coth^2 \frac{\theta}{2} \geq \frac{1 - u_1 u_2 + u_1 u_3 - u_2 u_3}{(u_2 - u_1)(u_2 - u_3)}. \end{cases} \tag{A.12}$$

Thus if

$$|\theta| \leq 2 \max \left[ \operatorname{arccoth} \sqrt{\frac{1 + u_1 u_3 - C u_1 - C u_3}{(C - u_1)(C - u_3)}}, \operatorname{arccoth} \sqrt{\frac{1 + u_1 u_3 + C u_1 + C u_3}{(C + u_1)(C + u_3)}} \right], \tag{A.13}$$

and  $u_2$  satisfies

$$\begin{cases} (u_2 - u_1)(u_2 - u_3) > 0, \\ \frac{1}{2\cosh^2\frac{\theta}{2}} \left| \sqrt{u_1^2 + u_3^2 - 2u_1u_3 \cosh\theta + \sinh^2\theta} + u_1 + u_3 \right| \leq |u_2| \leq C, \end{cases} \quad (\text{A.14})$$

from equations (A.11) one can immediately obtain the corresponding positive solutions for  $t_1$ ,  $t_2$  and  $t_3$  as

$$\begin{cases} t_1 = \frac{2}{r_1} \left[ \operatorname{arccot} \left( \frac{u_1 - u_2}{r_1} \coth \frac{\theta}{2} \pm \frac{1}{r_1} \sqrt{\Delta} \right) + m\pi \right] \\ t_2 = \frac{2}{r_2} \operatorname{arccot} \left[ \left( \mp \frac{1}{r_2} \sqrt{\Delta} \right) + l\pi \right] \\ t_3 = \frac{2}{r_3} \left[ \operatorname{arccot} \left( \frac{u_3 - u_2}{r_3} \coth \frac{\theta}{2} \pm \frac{1}{r_3} \sqrt{\Delta} \right) + n\pi \right] \end{cases} \quad (\text{A.15})$$

where the integers  $m$ ,  $n$  and  $l$  are introduced to keep  $t_1$ ,  $t_2$  and  $t_3$  positive, and  $m$  and  $n$  have an identical parity when  $(u_2 - u_1)\theta \geq 0$ , otherwise they have different parities. This completes the proof of proposition 1.

## Appendix B. The proof of proposition 2

Let  $-1 < u_1, u_3 < 1$  and  $1 < |u_2| < C$ , and  $(u_1, u_2, u_3)$  is constrained in the set  $\Xi_+ = \{(u_1, u_2, u_3) | \Delta \geq 0; \frac{u_k - u_2}{r_k} \cot \frac{\theta}{2} + \frac{1}{r_k} \sqrt{\Delta} \geq 1, k = 1, 3\}$ , where  $\Delta = (u_2 - u_1)(u_2 - u_3)(\cot^2 \frac{\theta}{2} + 1) + (1 - u_2^2)$ . It is easy to verify that such  $(u_1, u_2, u_3)$  always exists when  $C > 1$ . From the matrix equation  $e^{-it_1(K_2+u_1K_3)} e^{-it_2(K_2+u_2K_3)} = e^{-i\theta K_3} e^{it_3(K_2+u_3K_3)}$ , we may obtain the following equations (actually, they are equivalent to three independent equations) by equating entries of the matrices on both sides:

$$\begin{aligned} \cosh\left(\frac{t_1 r_1}{2}\right) \cos\left(\frac{t_2 r_2}{2}\right) + \frac{1 - u_1 u_2}{r_1 r_2} \sinh\left(\frac{t_1 r_1}{2}\right) \sin\left(\frac{t_2 r_2}{2}\right) \\ = \cosh\left(\frac{t_3 r_3}{2}\right) \cos\frac{\theta}{2} + \frac{u_3}{r_3} \sinh\left(\frac{t_3 r_3}{2}\right) \sin\frac{\theta}{2}, \end{aligned} \quad (\text{B.1})$$

$$\begin{aligned} \frac{u_1}{r_1} \sinh\left(\frac{t_1 r_1}{2}\right) \cos\left(\frac{t_2 r_2}{2}\right) + \frac{u_2}{r_2} \cosh\left(\frac{t_1 r_1}{2}\right) \sin\left(\frac{t_2 r_2}{2}\right) \\ = \cosh\left(\frac{t_3 r_3}{2}\right) \sin\frac{\theta}{2} - \frac{u_3}{r_3} \sinh\left(\frac{t_3 r_3}{2}\right) \cos\frac{\theta}{2}, \end{aligned} \quad (\text{B.2})$$

$$\begin{aligned} \frac{1}{r_1} \sinh\left(\frac{t_1 r_1}{2}\right) \cos\left(\frac{t_2 r_2}{2}\right) + \frac{1}{r_2} \cosh\left(\frac{t_1 r_1}{2}\right) \sin\left(\frac{t_2 r_2}{2}\right) \\ = -\frac{1}{r_3} \sinh\left(\frac{t_3 r_3}{2}\right) \cos\frac{\theta}{2}, \end{aligned} \quad (\text{B.3})$$

$$\frac{u_1 - u_2}{r_1 r_2} \sinh\left(\frac{t_1 r_1}{2}\right) \sin\left(\frac{t_2 r_2}{2}\right) = -\frac{1}{r_3} \sinh\left(\frac{t_3 r_3}{2}\right) \sin\frac{\theta}{2}, \quad (\text{B.4})$$

where  $r_1 = \sqrt{1 - u_1^2}$ ,  $r_2 = \sqrt{u_2^2 - 1}$ ,  $r_3 = \sqrt{1 - u_3^2}$ . With a few calculations, equations (B.1)–(B.4) can be simplified to

$$\coth\left(\frac{t_1 r_1}{2}\right) = \frac{u_1 - u_2}{r_1} \cot\frac{\theta}{2} \pm \frac{1}{r_1} \sqrt{\Delta}, \quad (\text{B.5})$$

$$\cot\left(\frac{t_2 r_2}{2}\right) = \mp \frac{1}{r_2} \sqrt{\Delta}, \quad (\text{B.6})$$

$$\coth\left(\frac{t_3 r_3}{2}\right) = \frac{u_3 - u_2}{r_3} \cot \frac{\theta}{2} \pm \frac{1}{r_3} \sqrt{\Delta}. \quad (\text{B.7})$$

Therefore, the positive solutions for  $t_1$ ,  $t_2$  and  $t_3$  in equations (B.5)–(B.7) are

$$\begin{cases} t_1 = \frac{2}{r_1} \left[ \operatorname{arccoth} \left( \frac{u_1 - u_2}{r_1} \cot \frac{\theta}{2} + \frac{1}{r_1} \sqrt{\Delta} \right) \right], \\ t_2 = \frac{2}{r_2} \left[ \operatorname{arccot} \left( -\frac{1}{r_2} \sqrt{\Delta} \right) + 2l\pi \right], \\ t_3 = \frac{2}{r_3} \left[ \operatorname{arccoth} \left( \frac{u_3 - u_2}{r_3} \cot \frac{\theta}{2} + \frac{1}{r_3} \sqrt{\Delta} \right) \right]. \end{cases} \quad (\text{B.8})$$

where  $l = 0, 1, 2, \dots, \infty$ , which is introduced to keep  $t_2$  positive. This completes the proof.

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