

QFT

spin: 0
scalar

$\frac{1}{2}$
fermion

1
boson

characterise "excitations" of the fields by the way they transform under group action (transition)

irreducible representations of the Lorentz group*

$$R = \begin{pmatrix} 1 & & & \\ & D_2 & & \\ & & & \\ & & & D_3 \end{pmatrix}$$

if the laws are invariant, then these numbers are constants

mass: $m^2 = E^2 - p^2 = P_\mu P^\mu$, invariant under boosts.

electric charge:

particles
anti-particles

$$U(1) \cong SO(2)$$

$$\begin{pmatrix} 0 & -1 \\ 1 & 0 \end{pmatrix} \rightarrow \begin{pmatrix} i & 0 \\ 0 & -i \end{pmatrix}$$

$$\lambda^2 + 1 = 0 \Rightarrow \lambda = \pm i$$

$$\begin{pmatrix} \phi_1 \\ \phi_2 \end{pmatrix} \rightarrow \begin{pmatrix} \phi'_1 \\ \phi'_2 \end{pmatrix} = \begin{pmatrix} \cos \alpha & -\sin \alpha \\ \sin \alpha & \cos \alpha \end{pmatrix} \begin{pmatrix} \phi_1 \\ \phi_2 \end{pmatrix} = g_\alpha(\vec{\phi})$$

$$\phi = \phi_1 + i \phi_2$$

$$\phi' = \cos \alpha \phi_1 - \sin \alpha \phi_2 + i(\sin \alpha \phi_1 + \cos \alpha \phi_2)$$

$$= (\cos \alpha + i \sin \alpha) \phi_1 + i(\cos \alpha + i \sin \alpha) \phi_2$$

$$= e^{i\alpha} \phi = g_\alpha(\phi)$$

Had I chosen $\bar{\phi} = \phi_1 + i(-\phi_2) = \phi_1 - i\phi_2$

$$\bar{\Phi}' = e^{-i\alpha} \bar{\Phi} = q_{\alpha}(\bar{\Phi})$$

$$\left. \frac{\partial q_{\alpha}}{\partial \alpha} \right|_{\alpha=0} \phi = \underbrace{i}_{\downarrow} \phi + \text{this is the particle's "charge"}$$

$$\left. \frac{\partial q_{\alpha}}{\partial \alpha} \right|_{\alpha=0} \bar{\Phi} = \underbrace{-i}_{\downarrow} \bar{\Phi} - \text{this is the anti-particle's "charge"}$$

(more info when Noether theorem)

1) Variational formulation of QFT / QM

↳ path integral

2) Transformations from group action

→ continuous \Leftrightarrow Lie group \Leftrightarrow Lie algebra

↳ spacetime transformations (diffeomorphisms)

↳ internal transformations (flavour)

3) Symmetry \Leftrightarrow conserved "charges"

(Noether theorem)

↳ classify states/solutions by their charge

↳ "Recipe" for building models based on symmetry

Classical mechanics (particles)

Lagrangian

$$S[q] = \int_{t_i}^{t_f} L(q, \dot{q}) dt$$

$$\delta S = 0 \Leftrightarrow E = L$$



Hamiltonian

(q, p)

$$H(q, p)$$

$$\{f, g\} = \frac{\partial f}{\partial q} \frac{\partial g}{\partial p} - \frac{\partial f}{\partial p} \frac{\partial g}{\partial q}$$

$$\{q, p\} = 1$$

$$\frac{df}{dt} = \{f, H\}$$

Classical fields

Quantum mechanics

Path integral

↳ semiclassical limit

↳ QFT



\hat{q}, \hat{p} operators

$$\hat{H}(q, p)$$

$$[\hat{A}, \hat{B}] = \hat{A}\hat{B} - \hat{B}\hat{A}$$

$$[\hat{q}, \hat{p}] = i\hbar$$

Heisenberg

$$\hat{A}(t) = e^{\frac{i\hat{H}t}{\hbar}} \hat{A}(0) e^{-\frac{i\hat{H}t}{\hbar}} \quad | \psi(t) \rangle = e^{-\frac{i\hat{H}t}{\hbar}} | \psi(0) \rangle$$

$$\dot{\hat{A}} = \frac{i}{\hbar} [\hat{A}, \hat{H}]$$



Schrodinger

QFT

Q2

Path integral formulation of QM

$\Psi(x,t)$ satisfies the Schrödinger equation / Hamiltonian perspective
 $(i\hbar \partial_t - H_x) \Psi = 0$

for a free particle $H_x = -\frac{\hbar^2}{2m} \partial_x^2$
with initial condition $\Psi(x,0) = g(x)$

Fundamental solution (owing to heat equation)

$$(i\hbar \partial_t - H_x) G = 0 \quad , \quad \left[\partial_t - \frac{i\hbar}{2m} \partial_x^2 \right] G = 0$$
$$G(x,0) = \delta(x)$$

$$\Rightarrow G(x,t) = \Theta(t) K(x,t)$$

$$\text{free particle} \quad K(x,t) = \frac{1}{\sqrt{4\pi \left(\frac{i\hbar}{2m}\right) t}} e^{-\frac{x^2}{4 \frac{i\hbar}{2m} t}}$$

$$= \sqrt{\frac{m}{2\pi i\hbar t}} e^{\frac{i m x^2}{2\hbar t}}$$

$$\Psi(x,t) = \int \underbrace{K(x-y, t)}_{\text{propagator}} \Psi(y,0) dy$$

the propagator conveys the probability amplitude

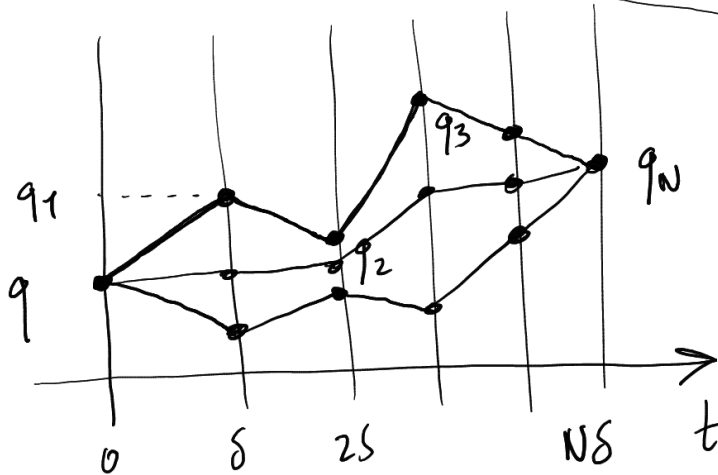
$$K(x_f, t_f, x_i, t_i) = \langle x_f, t_f | x_i, t_i \rangle$$

$$1) P_{x_i \rightarrow x_f} = \sum_{x_d} P_{x_i \rightarrow x_d} P_{x_d \rightarrow x_f}$$

$$K(x_f, t_f, x_i, t_i) = \int dy K(x_f, t_f, y, T) K(y, T, x_i, t_i)$$

Splitting in N portions of $\frac{t_f - t_i}{N} = \delta$

$$\phi = K(q_N, N\delta, q_0, 0) = \int dq_1 \dots dq_{N-1} K_{q_N q_{N-1}} K_{q_{N-1} q_{N-2}} \dots K_{q_1 q_0}$$



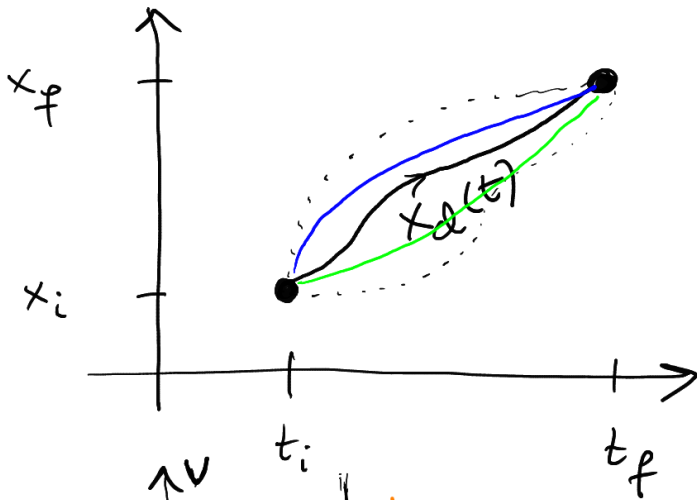
$$= \sum_{\gamma \text{ path}} \phi[\gamma]$$

where

$$\sum_{\text{path}} = \int dq_1 \dots dq_{N-1}$$

$$\phi[\gamma] = K_{q_N q_{N-1}} \dots K_{q_1 q_0} = \phi[\gamma_{N-1}] \dots \phi[\gamma_1], \text{ multiplicative}$$

Principle of Least action



The classical path is the one that minimizes the action

$$S[\gamma]_{x_f, x_i} = \int_{t_i}^{t_f} L(\gamma, \dot{\gamma}) dt$$

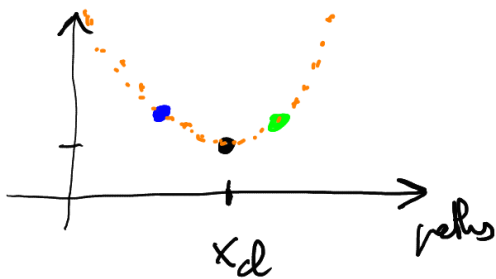
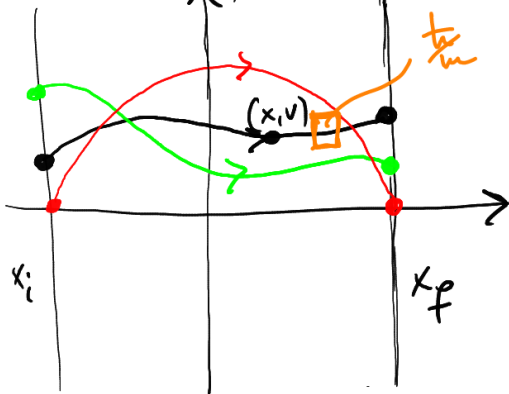
$$\delta S[\gamma_d] = 0$$

In QM, the uncertainty principle states

$$\Delta x \Delta v \leq \frac{\hbar}{m}$$

leads to a stochastic (random walk) description of a quantum trajectory

\Rightarrow probabilities/propagator



2) For a given path (choice of $\{q_k\}$)

$$S[\gamma] = \int_0^{N\delta} L(q, \dot{q}) dt = \sum_{k=1}^N \int_{(k-1)\delta}^{k\delta} L dt$$

$$= \sum_{k=1}^N S[\gamma_{k-1, k}], \quad \text{additive}$$

$$\Rightarrow K_{q_{k-1} q_k} \propto e^{\frac{i S[\gamma_{k-1, k}]}{\hbar}}$$

$$K(x_f, t_f, x_i, t_i) = \int \mathcal{D}q(t) e^{\frac{iS[q(t)]}{\hbar}}$$

where $S[q] = \int_{t_i}^{t_f} \mathcal{L}(q, \dot{q}) dt$ and $q(t_i) = x_i$
 $q(t_f) = x_f$

then, we can evolve the solution by

$$\Psi(x, t) = \int \mathcal{D}[x] \Psi(x(0), 0) e^{\frac{iS[x]}{\hbar}}$$

Free particle

$$S[x] = \int_0^T \frac{1}{2} m \dot{y}^2 dt$$

Let's split $T = N\delta$,

$$S_k = \int_{k\delta}^{(k+1)\delta} \frac{1}{2} m \dot{y}^2 dt = \frac{\delta m}{2} \dot{y}^2(c) \approx \frac{\delta m}{2} \frac{(x_{k+1} - x_k)^2}{\delta^2}$$

(assumption of continuity of \dot{y})
use value here

$$K(x_f, T, x_i, 0) = A(T) \int dx_1 \dots dx_{N-1} e^{-\sum_{k=0}^{N-1} \frac{i m}{2\hbar \delta} \frac{(x_{k+1} - x_k)^2}{2}}$$

List:

$$\frac{1}{2} \left[(x_0^2 - 2x_0x_1 + x_1^2) + (x_1^2 - 2x_1x_2 + x_2^2) + \dots \right]$$

$$= x_1^2 - 2x_1 \left(\frac{x_0 + x_2}{2} \right) + \frac{x_0^2 + x_2^2}{2} + \sum_{k=2}^{N-1} \frac{(x_{k+1} - x_k)^2}{2}$$

$$= \left(x_1 - \frac{x_0 + x_2}{2} \right)^2 - \frac{(x_0 + x_2)^2}{4} + \frac{x_0^2 + x_2^2}{2} + \dots$$

$$= \frac{1}{4} \left[2x_0^2 + 2x_2^2 - \cancel{x_0^2} - \cancel{x_2^2} - 2x_0x_2 \right]$$

$$= \frac{1}{4} (x_2 - x_0)^2$$

$$\frac{1}{4} (x_2 - x_0)^2 + \frac{(x_3 - x_2)^2}{2} + \sum_{k=3}^{N-1} (x_{k+1} - x_k)^2$$

$$= \frac{1}{4} \left[x_2^2 - 2x_0x_2 + x_0^2 + 2x_3^2 + 2x_2^2 - 4x_2x_3 \right] + \dots$$

$$= \frac{1}{4} \left[3x_2^2 - 3 \cdot 2x_2 \left(\frac{x_0 + 2x_3}{3} \right) + x_0^2 + 2x_3^2 \right] + \dots$$

$$= \frac{1}{4} \left[3 \left(x_2 - \frac{x_0 + 2x_3}{3} \right)^2 - \frac{(x_0 + 2x_3)^2}{3} + \frac{3x_0^2 + 6x_3^2}{3} \right] + \dots$$

$$= \frac{3x_0^2 + 6x_3^2 - x_0^2 - 4x_3^2 - 4x_0x_3}{12} = \frac{1}{6} (x_0^2 + x_3^2 - 2x_0x_3)$$

$$= \frac{1}{3} \frac{(x_3 - x_0)^2}{2} + \sum_{k=3}^{N-1} \frac{(x_{k+1} - x_k)^2}{2}$$

$$= \frac{1}{3} \frac{(x_3 - x_0)^2}{2} + \frac{(x_4 - x_3)^2}{2} = \frac{1}{2} \left(\frac{1}{3} + 1 \right) x_3^2 + \dots$$

$$= \frac{1.4}{2.3} x_3^2$$

$$\int dx_1 e^{\frac{i\omega}{\hbar\delta t} (x_1 - \dots)^2} \int dx_2 e^{\frac{i\omega}{\hbar\delta t} \frac{1}{2} (x_2 - \dots)^2} \int dx_3 e^{\frac{i\omega}{\hbar\delta t} \frac{1}{3} (x_3 - \dots)^2} \dots \int dx_{N-1}$$

$$\times \underline{e^{\frac{i\omega}{\hbar\delta t N} (x_N - x_0)^2}} = e^{\frac{i\omega}{\hbar T} \frac{(x_N - x_0)^2}{2}}$$

$$\left(\sqrt{\frac{2\pi\hbar\delta}{-im}} \right)^{N-1} \frac{(N-1)!}{N!} = \left(\sqrt{\frac{2\pi\hbar\delta}{m}} \right)^{N-1} \sqrt{\frac{1}{N}}$$

$$K = A \sqrt{\frac{2\pi\hbar\delta}{m}}^{N-1} \sqrt{\frac{1}{N}} e^{\frac{im}{\hbar T} \frac{(x_N - x_0)^2}{2}}$$

$$\Rightarrow A = \sqrt{\frac{m}{2\pi\hbar\delta}}^N$$

compare with known expression

Evolution operator

$$\hat{U}(t_f, t_i) = e^{-\frac{i}{\hbar}(t_f - t_i)\hat{H}} = e^{-\frac{i}{\hbar}t_f\hat{H}} e^{\frac{i}{\hbar}t_i\hat{H}}$$

$$\hat{U}(t_f, 0) \hat{U}(0, t_i)$$

$$\hat{U}(t_i, t_f) = \hat{U}(t_f, t_i)^\dagger \quad \text{and} \quad \hat{U}(t_f, t_i) \hat{U}(t_i, t_f) = 1$$

$$\hat{U} \hat{U}^\dagger = 1 \quad \text{unitary}$$

$$i\hbar \frac{\partial}{\partial t} \hat{U} = \hat{H}_{(t)} \hat{U}, \quad |\psi(t)\rangle = \hat{U} |\psi(0)\rangle$$

$$|x_i, t_i\rangle := \hat{U}^\dagger(t_i, 0) |x_i\rangle \quad \hat{X}_H(t) := \hat{U}^\dagger \hat{x} \hat{U}$$

$$\hat{X}_H(t) |x, t\rangle = \hat{U}^\dagger \hat{x} \hat{U} \hat{U}^\dagger |x\rangle = x \hat{U}^\dagger |x\rangle = x |x, t\rangle$$

$$\langle x_f, t_f | x_i, t_i \rangle = \langle x_f | \hat{U}(t_f, 0) \hat{U}^\dagger(t_i, 0) | x_i \rangle$$

$$= \langle x_f | \hat{U}(t_f, t_i) | x_i \rangle$$