An Efficient Method for Solving Equations in Generalized Quaternion and Octonion Algebras

Cristina Flaut* and Vitalii Shpakivskyi

Abstract. Quaternions often appear in wide areas of applied science and engineering such as wireless communications systems, mechanics, etc. It is known that there are two types of non-isomorphic generalized quaternion algebras, namely: the algebra of quaternions and the algebra of coquaternions. In this paper, we present the formulae to pass from a basis in the generalized quaternion algebras to a basis in the division quaternions algebra or to a basis in the coquaternions algebra and vice versa. The same result was obtained for the generalized octonion algebra. Moreover, we emphasize the applications of these results to the algebraic equations and De Moivre’s formula in generalized quaternion algebras and in generalized octonion division algebras.

Keywords. Generalized quaternion algebras, de Moivre’s formula.

0. Introduction

Let \( \gamma_1, \gamma_2 \in \mathbb{R} \setminus \{0\} \), let \( \mathbb{H}(\gamma_1, \gamma_2) \) be the generalized quaternion algebra with basis \( \{1, e_1, e_2, e_3\} \) and \( \mathbb{H}(1,1) \) be the quaternion division algebra with basis \( \{1, i, j, k\} \). The multiplication table is given below:

|   | 1  | \(e_1\) | \(e_2\) | \(e_3\) |
|---|----|--------|--------|--------|
| 1 | 1   | \(e_1\) | \(e_2\) | \(e_3\) |
| \(e_1\) | \(e_1\) | \(-\gamma_1\) | \(e_3\) | \(-\gamma_1 e_2\) |
| \(e_2\) | \(e_2\) | \(-e_3\) | \(-\gamma_2\) | \(\gamma_2 e_1\) |
| \(e_3\) | \(e_3\) | \(\gamma_1 e_2\) | \(-\gamma_2 e_1\) | \(-\gamma_1 \gamma_2\) |

The algebra \( \mathbb{H}(1,-1) \) is called the *algebra of coquaternions* [2] or also called the *algebra of para-quaternions* [8], or the *algebra of split-quaternions*.

*Corresponding author.
is called a $H$branized quaternion and octonion algebras. Due to Proposition 1, in the present $A$. It is obvious that $A$ and scalar part $(\{1, \alpha\})$, or of the basis of coquaternion algebra.

$H$, Flaut and V. Shpakivskyi

338                 C. Flaut and V. Shpakivskyi Adv. Appl. Clifford Algebras

The real octonion division algebras are a non-associative and non-commutative extension of the algebra of quaternions. Among all the real division algebras, octonion algebra forms the largest normed division algebra.

Let $O(\alpha, \beta, \gamma)$ be a generalized octonion algebra over $R$, with basis $\{1, f_1, \ldots, f_7\}$ and the multiplication given in the following table:

The algebra $O(\alpha, \beta, \gamma)$ is non-commutative, non-associative but it is alternative (i.e. $x^2y = x(yx)$ and $yx^2 = (yx)x$, $\forall x, y \in O(\alpha, \beta, \gamma)$), flexible (i.e. $x(yx) = (yx)x$, $\forall x, y \in O(\alpha, \beta, \gamma)$), power-associative (i.e. for each $x \in O(\alpha, \beta, \gamma)$ the subalgebra generated by $x$ is an associative algebra).

If $a \in O(\alpha, \beta, \gamma)$, $a = a_0 + a_1f_1 + a_2f_2 + a_3f_3 + a_4f_4 + a_5f_5 + a_6f_6 + a_7f_7$ then $\bar{a} = a_0 - a_1f_1 - a_2f_2 - a_3f_3 - a_4f_4 - a_5f_5 - a_6f_6 - a_7f_7$ is called the conjugate of the element $a$. Let $A = O(\alpha, \beta, \gamma)$ and $a \in A$. We have that $t(a) = a + \bar{a} \in K$ and

$$N(a) = a\bar{a} = a_0^2 + aa^2 + \beta a_2^2 + \alpha\beta a_3^2 + \gamma a_4^2 + \alpha\gamma a_5^2 + \beta\gamma a_6^2 + \alpha\beta\gamma a_7^2 \in K.$$ 

These are called the trace, respectively, the norm of the element $a \in A$. It follows that $(a + \bar{a})a = a^2 + a\bar{a} = a_0^2 + n(a) - 1$ and $a^2 - t(a)a + N(a) = 0, \forall a \in A$, therefore the generalized octonion algebra is quadratic.

The subset $A_0=\{x \in A \mid t(x) = 0\}$ of $A$ is a subspace of the algebra $A$. It is obvious that $A = K \cdot 1 \oplus A_0$, therefore each element $x \in A$ has the form $x = x_0 \cdot 1 + \vec{x}$, with $x_0 \in K$ and $\vec{x} \in A_0$. For $K = R$, we call $x_0$ the scalar part and $\vec{x}$ the vector part for the octonion $x$.

If for $x \in A$, the relation $N(x) = 0$ implies $x = 0$, then the algebra $A$ is called a division algebra. For other details, the reader is referred to [19].

In the papers [6], [7] are considered some algebraic equations in generalized quaternion and octonion algebras. Due to Proposition 1, in the present paper we reduced the study of an algebraic equation in an arbitrary algebra $H(\gamma_1, \gamma_2)$ with $\gamma_1, \gamma_2 \in R \setminus \{0\}$ to study of the corresponding algebraic equation in one of the following two algebras: division quaternion algebra or
coquaternion algebra. Moreover, De Moivre’s formula and Euler’s formula in
generalized quaternion algebras, founded in [11], was proved using this new
method, for \( \gamma_1, \gamma_2 > 0 \). With this technique, the above mentioned results
were also obtained for the octonions.

1. An Isomorphism between the Algebras \( \mathbb{H}(\gamma_1, \gamma_2) \), with
\( \gamma_1, \gamma_2 > 0 \), and \( \mathbb{H}(1,1) \)

Everywhere in this section, we will consider \( \gamma_1, \gamma_2 > 0 \). An isomorphism
between the algebras \( \mathbb{H}(\gamma_1, \gamma_2) \) and \( \mathbb{H}(1,1) \) is given by the operator \( A \) and its
inverse \( A^{-1} \), where

\[
A : \quad e_1 \mapsto i\sqrt{\gamma_1}, \quad e_2 \mapsto j\sqrt{\gamma_2}, \quad e_3 \mapsto k\sqrt{\gamma_1\gamma_2}.
\]

It is easy to prove the following properties for the operator \( A \):

1. \( A(\lambda x) = \lambda A(x) \), \( \forall \lambda \in \mathbb{R}, \forall x \in \mathbb{H}(\gamma_1, \gamma_2) \);
2. \( A(x + y) = A(x) + A(y) \), \( \forall x, y \in \mathbb{H}(\gamma_1, \gamma_2) \);
3. \( A(xy) = A(x)A(y) \), \( \forall x, y \in \mathbb{H}(\gamma_1, \gamma_2) \).

From here, it results that the operators \( A \) and \( A^{-1} \) are additive and
multiplicative.

**Proposition 1.1.** The operators \( A \) and \( A^{-1} \) are continuous and their norms
are equal to 1.

**Proof.** We denote by \( \| \cdot \|_{\mathbb{H}(\gamma_1,\gamma_2)} \) the Euclidian norm in \( \mathbb{H}(\gamma_1, \gamma_2) \). Since the
spaces \( \mathbb{H}(\gamma_1, \gamma_2) \) and \( \mathbb{H}(1,1) \) are normed spaces, then the continuity of \( A \) is
equivalent with the boundedness of \( A \), i.e. there is a real constant \( c \) such that
for all \( x \in \mathbb{H}(\gamma_1, \gamma_2) \), we have

\[
\frac{\| A(x) \|_{\mathbb{H}(1,1)}}{\| x \|_{\mathbb{H}(\gamma_1, \gamma_2)}} \leq c.
\]

It results that

\[
\frac{\| x_0 + x_1i\sqrt{\gamma_1} + x_2j\sqrt{\gamma_2} + x_3k\sqrt{\gamma_1\gamma_2} \|}{\| x_0 + x_1e_1 + x_2e_2 + x_3e_3 \|} = \frac{\sqrt{x_0^2 + x_1^2\gamma_1 + x_2^2\gamma_2 + x_3^2\gamma_3}}{\sqrt{x_0^2 + x_1^2\gamma_1 + x_2^2\gamma_2 + x_3^2\gamma_3}} = 1. \quad \square
\]

2. The Algebra \( \mathbb{H}(\gamma_1, \gamma_2) \), with \( \gamma_1, \gamma_2 < 0 \) or \( \gamma_1\gamma_2 < 0 \)

In this situation, the algebra \( \mathbb{H}(\gamma_1, \gamma_2) \) is isomorphic with \( \mathbb{H}(1,-1) \). We suppose
first that \( \gamma_1, \gamma_2 < 0 \). An isomorphism between the algebra \( \mathbb{H}(\gamma_1, \gamma_2) \),
where \( \gamma_1, \gamma_2 < 0 \), and the algebra \( \mathbb{H}(1,-1) \) is given by the operator \( B \) and
its inverse \( B^{-1} \), where

\[
B : \quad e_1 \mapsto i_3\sqrt{-\gamma_1}, \quad e_2 \mapsto i_2\sqrt{-\gamma_2}, \quad e_3 \mapsto i_1\sqrt{\gamma_1\gamma_2}.
\]
For $\gamma_1 > 0, \gamma_2 < 0$, an isomorphism between the algebra $\mathbb{H}(\gamma_1, \gamma_2)$ and
the algebra $\mathbb{H}(1, -1)$ is given by the operator $C$ and its inverse $C^{-1}$, where
\[
C : \begin{pmatrix}
e_1 \mapsto i_1\sqrt{\gamma_1},
e_2 \mapsto i_2\sqrt{-\gamma_2},
e_3 \mapsto i_3\sqrt{-\gamma_1\gamma_2}.
\end{pmatrix}
\]
For $\gamma_1 < 0, \gamma_2 > 0$, an isomorphism between the algebra $\mathbb{H}(\gamma_1, \gamma_2)$ and
the algebra $\mathbb{H}(1, -1)$ is given by the operator $D$ and its inverse $D^{-1}$, where
\[
D : \begin{pmatrix}
e_1 \mapsto i_3\sqrt{-\gamma_1},
e_2 \mapsto i_1\sqrt{\gamma_2},
e_3 \mapsto i_2\sqrt{-\gamma_1\gamma_2}.
\end{pmatrix}
\]
The properties of the operators $B, B^{-1}, C, C^{-1}, D, D^{-1}$ are similarly
with the properties of the operator $A$.
Since each algebra $\mathbb{H}(\gamma_1, \gamma_2)$ is isomorphic with algebra of quaternions
or coquaternions, it results that the above operators provide us a simple way
to generalize known results in these two algebras to generalized quaternion
algebra.

3. Application to the Algebraic Equations

Let $x = x_0 + x_1e_1 + x_2e_2 + x_3e_3 \in \mathbb{H}(\gamma_1, \gamma_2)$ and let $f : \mathbb{H}(\gamma_1, \gamma_2) \rightarrow \mathbb{H}(\gamma_1, \gamma_2)$ be a continuous function of the form $f(x) = f_0(x_0, x_1, x_2, x_3) + f_1(x_0, x_1, x_2, x_3)e_1 + f_2(x_0, x_1, x_2, x_3)e_2 + f_3(x_0, x_1, x_2, x_3)e_3$. Let $F$ be the
one of the operators $A, B, C$ or $D$, depending on the signs of $\gamma_1$ and $\gamma_2$. We
define the operator $\mathfrak{f}$ which for any continuous function $f$, taking values in
$\mathbb{H}(\gamma_1, \gamma_2)$, maps it in the continuous function $\mathfrak{f}f$, taking values in $\mathbb{H}(1, 1)$ or
$\mathbb{H}(1, -1)$ by the rule:
\[
\mathfrak{f}f := f_0 + f_1F(e_1) + f_2F(e_2) + f_3F(e_3).
\]

Theorem 3.1. Let $x^0 \in \mathbb{H}(\gamma_1, \gamma_2)$ be a root of the equation $f(x) = 0$ in
$\mathbb{H}(\gamma_1, \gamma_2)$. Then $F(x^0)$ is a root of the equation $\mathfrak{f}f(F(x)) = 0$ in $\mathbb{H}(1, 1)$ or
$\mathbb{H}(1, -1)$, depending on the signs of $\gamma_1$ and $\gamma_2$. The converse is also true.

Proof. Let $\gamma_1, \gamma_2 > 0$. Applying operator $A$ to the equality $f(x^0) = 0$ and
using the continuity of $A$, we obtain
\[
A(f(x^0)) = Af(A(x^0)) = A(0) = 0.
\]
To prove the converse statement we apply the operator $A^{-1}$ to the
equality $f(x^0) = 0$. The remaining cases can be proved similarly. $\square$

Therefore, all results from quaternionic equations and from coquaternionic
equations can be generalized in $\mathbb{H}(\gamma_1, \gamma_2)$.

It is known that any polynomial of degree $n$ with coefficients in a field
$K$ has at most $n$ roots in $K$. If the coefficients are in $\mathbb{H}(1, 1)$, the situation is
different. For the real division quaternion algebra over the real field, there is a
kind of a fundamental theorem of algebra: If a polynomial has only one term
of the greatest degree, then it has at least one root in $\mathbb{H}(1, 1)$. ([21], Theorem
65; [4], Theorem 1).

We consider the polynomial of degree $n$ of the form
\[
f(x) = a_0x_0 + a_1x_1 + \ldots + a_{n-1}x_{n-1} + a_n + \varphi(x), \quad (3.1.)
\]
where $x, a_0, a_1, \ldots, a_{n-1}, a_n \in \mathbb{H}(1, 1)$, with $a_\ell \neq 0$ for $\ell \in \{0, 1, \ldots, n\}$ and $\varphi(x)$ is a sum of a finite number of monomials of the form $b_0 x b_1 x \ldots b_{t-1} x b_t$ where $t < n$. From the above, it results that the equation $f(x) = 0$ has at least one root. Applying operator $A^{-1}$ to this last equality, the equation $(A^{-1} f)(A^{-1}(x)) = 0$, with $x = x_0 + x_1 e_1 + x_2 e_2 + x_3 e_3$, has at least one root in $\mathbb{H}(\gamma_1, \gamma_2)$. Therefore, we proved the following result:

**Theorem 3.2.** In the generalized quaternion algebra $\mathbb{H}(\gamma_1, \gamma_2)$ with $\gamma_1, \gamma_2 > 0$, any polynomial of the form (3.1) has at least one root. \qed

In the following, we consider the equation $x^2 + ax + b = 0$, where $\mathbb{H}(\gamma_1, \gamma_2)$ with $\gamma_1, \gamma_2 > 0$. We say that a root $x_0 = a_0 + a_1 i_1 + a_2 i_2 + a_3 i_3 \in \mathbb{H}(\gamma_1, \gamma_2)$, $\gamma_1, \gamma_2 > 0$ is an ellipsoidal root of every element $x_1 \in \mathbb{H}(\gamma_1, \gamma_2)$ of the form $x_1 = a_0 + b_1 i_1 + b_2 i_2 + b_3 i_3$ such that $\gamma_1 a_1^2 + \gamma_2 a_2^2 + \gamma_1 \gamma_2 a_3^2 = \gamma_1 b_1^2 + \gamma_2 b_2^2 + \gamma_1 \gamma_2 b_3^2$ is also a root of this equation.

Using Theorem 3 from [12] and Theorem 3.1, we just proved the following theorem:

**Theorem 3.3.** In the generalized quaternion algebra $\mathbb{H}(\gamma_1, \gamma_2)$ with $\gamma_1, \gamma_2 > 0$, the equation $x^2 + ax + b = 0$ has ellipsoidal root if and only if $a$ and $b$ are real numbers and $a^2 - 4b < 0$. \qed

More results on the structure of roots of the quadratic quaternionic equations can be found in see [22], [13], [14], [15].

In the following, we apply the above results to the coquaternion algebra. We will consider one of the three cases: $\gamma_1, \gamma_2 < 0; \gamma_1 < 0, \gamma_2 > 0; \gamma_1 > 0, \gamma_2 < 0$. We say that a root $x_0 = a_0 + a_1 i_1 + a_2 i_2 + a_3 i_3 \in \mathbb{H}(\gamma_1, \gamma_2)$ is a hyperboloidal root of every element $x_1 \in \mathbb{H}(\gamma_1, \gamma_2)$ of the form $x_1 = a_0 + b_1 i_1 + b_2 i_2 + b_3 i_3$ such that $\gamma_1 a_1^2 + \gamma_2 a_2^2 + \gamma_1 \gamma_2 a_3^2 = \gamma_1 b_1^2 + \gamma_2 b_2^2 + \gamma_1 \gamma_2 b_3^2$ is also a root of this equation. Using Theorem 2.5 of [17] and the above Theorem 3.1, we proved:

**Theorem 3.4.** If we suppose that coefficients $r_k$, $k = 0, 1, \ldots, n$ of the polynomial equation $r_n x^n + r_{n-1} x^{n-1} + \ldots + r_0 = 0$, $x \in \mathbb{H}(\gamma_1, \gamma_2)$, are real numbers, therefore all its non-real roots are hyperboloidal. \qed

Solutions of linear equations in coquaternionic algebra can be found in [9], [5] and solutions of linear equations in quaternion algebra can be found, for example, in [23], [20].

Let $x = x_0 + x_1 i + x_2 j + x_3 k \in \mathbb{H}(1, 1)$, $x_0, x_1, x_2, x_3 \in \mathbb{R}$. We denote

$$\vec{x} = A^{-1}(x) = x_0 + x_1 \frac{e_1}{\sqrt{\gamma_1}} + x_2 e_2 \frac{e_2}{\sqrt{\gamma_2}} + x_3 e_3 \frac{e_1}{\sqrt{\gamma_1 \gamma_2}}.$$ 

**Example 3.5.** Consider the general polynomial equation in $\mathbb{H}(1, 1)$:

$$\sum_{p=1}^{n} \left( \sum_{l=1}^{m_p} a_{p,l,1} x a_{p,l,2} x \ldots a_{p,l,p} x a_{p,l,p+1} \right) + c = 0.$$
This equation is “equivalent” to the following equation in $\mathbb{H}(\gamma_1, \gamma_2)$, with $\gamma_1, \gamma_2 > 0$:

$$\sum_{p=1}^{n} \left( \sum_{l=1}^{m_p} \tilde{a}_{p,l,1} \tilde{x} \tilde{a}_{p,l,2} \tilde{x} \ldots \tilde{a}_{p,l,p} \tilde{x} \tilde{a}_{p,l,p+1} \right) + \tilde{c} = 0.$$ 

Therefore, the algebraic equations $f(x) = 0$, with $f$ continuous, in usual quaternions $\mathbb{H}(1, 1)$ can be reduced to the similar equations in all algebras $\mathbb{H}(\gamma_1, \gamma_2)$ for $\gamma_1, \gamma_2 > 0$ and vice versa. A similar result can be found for different signs of $\gamma_1$ and $\gamma_2$.

### 4. De Moivre’s Formula

In the following, we will use some ideas and notations from [3]. Let $q = q_0 + q_1 e_1 + q_2 e_2 + q_3 e_3 \in \mathbb{H}(\gamma_1, \gamma_2)$, with $\gamma_1, \gamma_2 > 0$, $q_0, q_1, q_2, q_3 \in \mathbb{R}$ and

$$|q| = \sqrt{q_0^2 + \gamma_1 q_1^2 + \gamma_2 q_2^2 + \gamma_1 \gamma_2 q_3^2}.$$

Consider the sets

$$S^3_G = \{ q \in \mathbb{H}(\gamma_1, \gamma_2) , \gamma_1, \gamma_2 > 0 : |q| = 1 \},$$

$$S^2_G = \{ q \in \mathbb{H}(\gamma_1, \gamma_2) , \gamma_1, \gamma_2 > 0 : q_0 = 0, |q| = 1 \}.$$

Any $q \in S^3_G$ can be expressed as $q = \cos \theta + \varepsilon \sin \theta$, where

$$\cos \theta = q_0, \quad \varepsilon = \frac{q_1 e_1 + q_2 e_2 + q_3 e_3}{\sqrt{\gamma_1 q_1^2 + \gamma_2 q_2^2 + \gamma_1 \gamma_2 q_3^2}}.$$

Using Proposition 2 from [3] and applying the operator $A^{-1}$ we will find De Moivre’s formula for $\mathbb{H}(\gamma_1, \gamma_2)$, $\gamma_1, \gamma_2 > 0$.

**Theorem 4.1.** Let $q = \cos \theta + \varepsilon \sin \theta \in S^3_G$, $\theta \in \mathbb{R}$. Then $q^n = \cos n\theta + \varepsilon \sin n\theta$, for every integer $n$.

Theorem 4.1 is the same with Theorem 7 from the paper [11], obtained with another proof. □

Using Corollary 3 from [3] and Theorem 3.1, we obtain the next statement.

**Proposition 4.2.** i) In $\mathbb{H}(\gamma_1, \gamma_2)$, with $\gamma_1, \gamma_2 > 0$, the equation $x^n = 1$, with $n$ integer and $n \geq 3$, has infinity of roots, namely

$$q = \cos \frac{2\pi}{n} \frac{2\pi}{n} + \varepsilon \sin \frac{2\pi}{n} + \varepsilon \in S^3_G.$$

ii) In $\mathbb{H}(\gamma_1, \gamma_2)$, $\gamma_1, \gamma_2 > 0$, the equation $x^n = a$, $a \in \mathbb{N}$, has infinity of roots, namely $\sqrt[n]{a} q$, where $q = \cos \frac{2\pi}{n} \frac{2\pi}{n} + \varepsilon \sin \frac{2\pi}{n} \in S^3_G$, with $\varepsilon \in S^3_G$. If $n$ is even, it is necessary that $a > 0$. 
5. De Moivre’s Formula and Euler’s Formula for Octonions

In the following, we will generalize in a natural way De Moivre formula and Euler’s formula for the division octonion algebra $\mathbb{O} (1, 1, 1)$. For this, we will use some ideas and notations from [3]. We consider the sets

$$ S^3 = \{ a \in \mathbb{O} (1, 1, 1) : N(a) = 1 \}, $$
$$ S^3_o = \{ a \in \mathbb{O} (\alpha, \beta, \gamma) : N(a) = 1 \}, $$
$$ S^2 = \{ a \in \mathbb{O} (1, 1, 1) : t(a) = 0, N(a) = 1 \}, $$
$$ S^2_o = \{ a \in \mathbb{O} (1, 1, 1) : t(a) = 0, N(a) = 1 \}. $$

We remark that for all elements $a \in S^2$, we have $a^2 = -1$. Let $a \in S^3, a = a_0 + a_1 f_1 + a_2 f_2 + a_3 f_3 + a_4 f_4 + a_5 f_5 + a_6 f_6 + a_7 f_7$. This element can be written in the form

$$ a = \cos \lambda + w \sin \lambda, $$

where $\cos \lambda = a_0$ and

$$ w = \frac{a_1 f_1 + a_2 f_2 + a_3 f_3 + a_4 f_4 + a_5 f_5 + a_6 f_6 + a_7 f_7}{\sqrt{a_1^2 + a_2^2 + a_3^2 + a_4^2 + a_5^2 + a_6^2 + a_7^2}} = \frac{a_1 f_1 + a_2 f_2 + a_3 f_3 + a_4 f_4 + a_5 f_5 + a_6 f_6 + a_7 f_7}{\sqrt{1 - a_0^2}}. $$

Since $w^2 = -1$, we obtain the following Euler formula:

$$ e^{\lambda w} = \sum_{i=1}^{\infty} \frac{(\lambda w)^n}{n!} = \sum_{i=1}^{\infty} \frac{(-1)^n \lambda^{2n}}{(2n)!} + w \sum_{i=1}^{\infty} \frac{(-1)^{n-1} \lambda^{2n-1}}{(2n-1)!} $$

$$ = \cos \lambda + w \sin \lambda. $$

**Proposition 5.1.** The cosinus function is constant, for all elements in $S^2$.

**Proof.** Indeed, $\cos w = \sum_{i=1}^{\infty} \frac{(-1)^n \lambda^{2n}}{(2n)!} = \cos i$. $\square$

**Proposition 5.2.** For $w \in S^2$, we have $\cos (\lambda_1 + w \sin \lambda_1)(\cos \lambda_2 + w \sin \lambda_2) = \cos(\lambda_1 + \lambda_2) + w \sin(\lambda_1 + \lambda_2)$.

**Proof.** By straightforward calculations. $\square$

**Proposition 5.3 (De Moivre formula for octonions).** With the above notations, we have that

$$ a^n = e^{n \lambda w} = (\cos \lambda + w \sin \lambda)^n = \cos n \lambda + w \sin n \lambda, $$

where $a \in S^3, n \in \mathbb{Z}$ and $\lambda \in \mathbb{R}$.

**Proof.** For $n > 0$, by induction. We obtain

$$ a^{n+1} = (\cos \lambda + w \sin \lambda)^{n+1} $$

$$ = (\cos \lambda + w \sin \lambda)^n (\cos \lambda + w \sin \lambda) $$

$$ = (\cos n \lambda + w \sin n \lambda) (\cos \lambda + w \sin \lambda) $$

$$ = \cos(n + 1) \lambda + w \sin(n + 1) \lambda. $$
Since $a^{-1} = \cos \lambda - w \sin \lambda = \cos(-\lambda) + w \sin(-\lambda)$, it results the asked formula for all $n \in \mathbb{Z}$. □

**Remark 5.4.** It is known that any polynomial of degree $n$ with coefficients in a field $K$ has at most $n$ roots in $K$. If the coefficients are in $\mathbb{O}(1,1,1)$ there is a kind of a fundamental theorem of algebra: If a polynomial has only one term of the greatest degree, then it has at least one root in $\mathbb{O}(1,1,1)$ (see [21], Theorem 65).

**Theorem 5.5.** Equation $x^n = a$, where $a \in \mathbb{O}(1,1,1) \setminus \mathbb{R}$, has $n$ roots.

**Proof.** The octonion $a$ can be written under the form $a = \sqrt{N(a)} \frac{a}{\sqrt{N(a)}}$. The octonion $b = \frac{a}{\sqrt{N(a)}}$ is in $S^2$, then we can find the elements $w \in S^2$ and $\lambda \in \mathbb{R}$ such that $b = \cos \lambda + w \sin \lambda$. From Proposition 5.3, we have that the solutions of the above equation are $x_r = \sqrt{Q} \left( \cos \frac{\lambda + 2r\pi}{n} + w \sin \frac{\lambda + 2r\pi}{n} \right)$, where $Q = \sqrt{N(a)}$ and $r \in \{0,1,\ldots,n-1\}$. □

**Corollary 5.6.** If $a \in \mathbb{R}$, therefore the equation $x^n = a$ has an infinity of roots.

**Proof.** Indeed, if $a \in \mathbb{R}$, we can write $a = a \cdot 1 = (\cos 2\pi + w \sin 2\pi)$, where $w \in S^2$ is an arbitrary element. □

**Remark 5.7.** The rotation of the octonion $x \in \mathbb{O}(1,1,1)$ on the angle $\lambda$ around the unit vector $w \in S^2$ is defined by the formula

$$x^r = \overline{u}xu,$$

where $u \in S^3$, $u = \cos \frac{\lambda}{2} + w \sin \frac{\lambda}{2}$ and $\overline{u} = \cos \frac{\lambda}{2} - w \sin \frac{\lambda}{2}$.

Using the form $x = x_0 \cdot 1 + \overrightarrow{x}$, $y = y_0 \cdot 1 + \overrightarrow{y}$ for the octonions $x,y \in \mathbb{O}(1,1,1)$, we obtain the following expression for the product of two octonions:

$$xy = (x_0 \cdot 1 + \overrightarrow{x})(y_0 \cdot 1 + \overrightarrow{y}) = x_0y_0 \cdot 1 + x_0 \overrightarrow{y} + y_0 \overrightarrow{x} + <\overrightarrow{x},\overrightarrow{y}> + \overrightarrow{x} \times \overrightarrow{y},$$

where $<\overrightarrow{x},\overrightarrow{y}>$ is the inner product of two octonionic-vector and $\overrightarrow{x} \times \overrightarrow{y}$ is the cross product. From here, we obtain that

$$x^r = \overline{u}xu$$

$$= \left( \cos \frac{\lambda}{2} - w \sin \frac{\lambda}{2} \right) \left( x_0 \cdot 1 + \overrightarrow{x} \right) \left( \cos \frac{\lambda}{2} + w \sin \frac{\lambda}{2} \right)$$

$$= x_0 + \overrightarrow{x} \cos \lambda - w <\overrightarrow{x},\overrightarrow{y}> (1 - \cos \lambda) - (w \times \overrightarrow{x}) \sin \lambda.$$

It results that that rotation does not transform the octonion-scalar part, but the octonion-vector part $\overrightarrow{x}$ is rotated on the angle $\lambda$ around $w$. 

6. An Isomorphism between the Algebras $\mathbb{O}(\alpha, \beta, \gamma)$ and Some of its Applications

In the following, we will consider the generalized real octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$ and the algebras $\mathbb{O}(1, 1, 1)$ and $\mathbb{O}(1, 1, -1)$. Let $\{1, f_1, \ldots, f_7\}$ be a basis in $\mathbb{O}(\alpha, \beta, \gamma)$, and $\{1, \tilde{f}_1, \ldots, \tilde{f}_7\}$ be the canonical basis in $\mathbb{O}(1, 1, 1)$, and $\{1, \hat{f}_1, \ldots, \hat{f}_7\}$ be the canonical basis in $\mathbb{O}(1, 1, -1)$.

We prove that the algebra $\mathbb{O}(\alpha, \beta, \gamma)$ with $\alpha, \beta, \gamma \in \mathbb{R} \setminus \{0\}$ is isomorphic with algebra $\mathbb{O}(1, 1, 1)$ or $\mathbb{O}(1, 1, -1)$ and indicate the formulae to pass from one basis to another basis. Thus, if $\alpha, \beta, \gamma > 0$ then the real octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$ is isomorphic with algebra $\mathbb{O}(1, 1, 1)$ and this isomorphism is given by the relations:

$A_1: \quad f_1 \mapsto \tilde{f}_1 \sqrt{\alpha}, \ f_2 \mapsto \tilde{f}_2 \sqrt{\beta}, \ f_3 \mapsto \tilde{f}_3 \sqrt{\alpha\beta},$

$\quad f_4 \mapsto \tilde{f}_4 \sqrt{\gamma}, \ f_5 \mapsto \tilde{f}_5 \sqrt{\alpha\gamma}, \ f_6 \mapsto \tilde{f}_6 \sqrt{\beta\gamma}, \ f_7 \mapsto \tilde{f}_7 \sqrt{\alpha\beta\gamma}.
$

If $\alpha, \beta > 0, \gamma < 0$, then the real octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$ is isomorphic with algebra $\mathbb{O}(1, 1, -1)$ and this isomorphism is given by the relations:

$A_2: \quad f_1 \mapsto \tilde{f}_1 \sqrt{\alpha}, \ f_2 \mapsto \tilde{f}_2 \sqrt{\beta}, \ f_3 \mapsto \tilde{f}_3 \sqrt{\alpha\beta},$

$\quad f_4 \mapsto \tilde{f}_4 \sqrt{-\gamma}, \ f_5 \mapsto \tilde{f}_5 \sqrt{-\alpha\gamma}, \ f_6 \mapsto \tilde{f}_6 \sqrt{-\beta\gamma}, \ f_7 \mapsto \tilde{f}_7 \sqrt{-\alpha\beta\gamma}.
$

If $\alpha, \gamma > 0, \beta < 0$, then the real octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$ is isomorphic with algebra $\mathbb{O}(1, 1, -1)$ and this isomorphism is given by the relations:

$A_3: \quad f_1 \mapsto \tilde{f}_1 \sqrt{\alpha}, \ f_2 \mapsto \tilde{f}_4 \sqrt{-\beta}, \ f_3 \mapsto \tilde{f}_5 \sqrt{-\alpha\beta},$

$\quad f_4 \mapsto \tilde{f}_2 \sqrt{\gamma}, \ f_5 \mapsto \tilde{f}_3 \sqrt{\alpha\gamma}, \ f_6 \mapsto \tilde{f}_6 \sqrt{-\beta\gamma}, \ f_7 \mapsto \tilde{f}_7 \sqrt{-\alpha\beta\gamma}.
$

If $\alpha > 0, \beta, \gamma < 0$, then the real octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$ is isomorphic with algebra $\mathbb{O}(1, 1, -1)$ and this isomorphism is given by the relations:

$A_4: \quad f_1 \mapsto \hat{f}_1 \sqrt{\alpha}, \ f_2 \mapsto \hat{f}_4 \sqrt{-\beta}, \ f_3 \mapsto \hat{f}_5 \sqrt{-\alpha\beta},$

$\quad f_4 \mapsto \hat{f}_6 \sqrt{-\gamma}, \ f_5 \mapsto \hat{f}_7 \sqrt{-\alpha\gamma}, \ f_6 \mapsto \hat{f}_2 \sqrt{\beta\gamma}, \ f_7 \mapsto \hat{f}_3 \sqrt{\alpha\beta\gamma}.
$

If $\alpha < 0, \beta, \gamma > 0$, then the real octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$ is isomorphic with algebra $\mathbb{O}(1, 1, -1)$ and this isomorphism is given by the relations:

$A_5: \quad f_1 \mapsto \hat{f}_4 \sqrt{\alpha}, \ f_2 \mapsto \hat{f}_1 \sqrt{-\beta}, \ f_3 \mapsto \hat{f}_5 \sqrt{-\alpha\beta},$

$\quad f_4 \mapsto \hat{f}_2 \sqrt{\gamma}, \ f_5 \mapsto \hat{f}_6 \sqrt{-\alpha\gamma}, \ f_6 \mapsto \hat{f}_3 \sqrt{\beta\gamma}, \ f_7 \mapsto \hat{f}_7 \sqrt{-\alpha\beta\gamma}.
$

If $\alpha, \gamma < 0, \beta > 0$, then real octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$ is isomorphic with algebra $\mathbb{O}(1, 1, -1)$ and this isomorphism is given by the relations:

$A_6: \quad f_1 \mapsto \hat{f}_4 \sqrt{-\alpha}, \ f_2 \mapsto \hat{f}_1 \sqrt{-\beta}, \ f_3 \mapsto \hat{f}_5 \sqrt{-\alpha\beta},$

$\quad f_4 \mapsto \hat{f}_6 \sqrt{-\gamma}, \ f_5 \mapsto \hat{f}_2 \sqrt{-\alpha\gamma}, \ f_6 \mapsto \hat{f}_7 \sqrt{-\beta\gamma}, \ f_7 \mapsto \hat{f}_3 \sqrt{\alpha\beta\gamma}.
$

If $\alpha, \beta < 0, \gamma > 0$, then the real octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$ is isomorphic with algebra $\mathbb{O}(1, 1, -1)$ and this isomorphism is given by the relations:

$A_7: \quad f_1 \mapsto \hat{f}_4 \sqrt{-\alpha}, \ f_2 \mapsto \hat{f}_5 \sqrt{-\beta}, \ f_3 \mapsto \hat{f}_1 \sqrt{\alpha\beta},$

$\quad f_4 \mapsto \hat{f}_2 \sqrt{\gamma}, \ f_5 \mapsto \hat{f}_6 \sqrt{-\alpha\gamma}, \ f_6 \mapsto \hat{f}_7 \sqrt{-\beta\gamma}, \ f_7 \mapsto \hat{f}_3 \sqrt{\alpha\beta\gamma}.$
If $\alpha, \beta, \gamma < 0$, then the real octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$ is isomorphic with algebra $\mathbb{O}(1, 1, -1)$ and this isomorphism is given by the relations:

$$A_8 : \begin{align*}
f_1 &\mapsto \hat{f}_4\sqrt{-\alpha}, & f_2 &\mapsto \hat{f}_5\sqrt{-\beta}, & f_3 &\mapsto \hat{f}_1\sqrt{\alpha\beta}, \\
f_4 &\mapsto \hat{f}_6\sqrt{-\gamma}, & f_5 &\mapsto \hat{f}_2\sqrt{\alpha\gamma}, & f_6 &\mapsto \hat{f}_3\sqrt{\beta\gamma}, & f_7 &\mapsto \hat{f}_7\sqrt{-\alpha\beta\gamma}.
\end{align*}$$

It is easy to prove that the operators $A_k$, $k = \bar{1}, \bar{8}$ is additive and multiplicative. The following statement can be proved completely analogous as Proposition 1.1.

**Proposition 6.1.** The operators $A_k$, $k = \bar{1}, \bar{8}$, are continuous and have norm 1. \(\square\)

Let $x = x_0 + \sum_{k=1}^7 x_k f_k \in \mathbb{O}(\alpha, \beta, \gamma)$ and let $g : \mathbb{O}(\alpha, \beta, \gamma) \to \mathbb{O}(\alpha, \beta, \gamma)$ be a continuous function of the form $g(x) = g_0(x_0, \ldots, x_7) + \sum_{k=1}^7 g_k(x_0, \ldots, x_7) f_k$.

Let $L$ be one of the operators $A_k$, $k = \bar{1}, \bar{8}$, depending on the signs of $\alpha, \beta$ and $\gamma$. We define the operator $\mathcal{L}$ by the rule:

$$\mathcal{L}g := f_0 + \sum_{k=1}^7 g_k L(f_k).$$

The operator $\mathcal{L}$ for any continuous function $g$, taking values in $\mathbb{O}(\alpha, \beta, \gamma)$, maps it in the continuous function $\mathcal{L}g$, taking values in $\mathbb{O}(1, 1, 1)$ or $\mathbb{O}(1, 1, -1)$.

The following statement can be analogously proved as Theorem 3.1.

**Theorem 6.2.** Let $x^0 \in \mathbb{O}(\alpha, \beta, \gamma)$ be a root of the equation $g(x) = 0$ in $\mathbb{O}(\alpha, \beta, \gamma)$. Then $L(x^0)$ is a root of the equation $\mathcal{L}g(L(x)) = 0$ in $\mathbb{O}(1, 1, 1)$ or $\mathbb{O}(1, 1, -1)$, depending on the signs of $\alpha, \beta$, and $\gamma$. The converse is also true. \(\square\)

Thus, the study of algebraic equations in an arbitrary algebra $\mathbb{O}(\alpha, \beta, \gamma)$ with $\alpha, \beta, \gamma \in \mathbb{R} \setminus \{0\}$ was reduced to study of the corresponding algebraic equation in one of the following two algebras: division octonion algebra $\mathbb{O}(1, 1, 1)$ or algebra $\mathbb{O}(1, 1, -1)$.

Using the above notations, we can prove the following theorem.

**Theorem 6.3.** Equation $x^n = a$, where $a \in \mathbb{O}(\alpha, \beta, \gamma) \setminus \mathbb{R}, \alpha, \beta, \gamma > 0$, has $n$ roots.

**Proof.** The octonion $b = \frac{a}{\sqrt{N(a)}}$ is in $S^3_G$, then there are $w \in S^n_G$, $w = A^{-1}_1(\bar{w})$, $\bar{w} \in S^2$ and $\lambda \in \mathbb{R}$ such that $b = \cos \lambda + \bar{w}\sin \lambda$. From Proposition 5.3, we have that the solutions of the above equation are $x_r = A^{-1}_1(\bar{x}_r) = \sqrt{\bar{N}(a)}(\cos \frac{\lambda + 2\pi r}{n} + \bar{w}\sin \frac{\lambda + 2\pi r}{n})$, where $r \in \{0, 1, \ldots, n-1\}$ and $\bar{x}_r$ is a solution of the equation $\bar{x}^n = \bar{a}$ in $\mathbb{O}(1, 1, 1)$. \(\square\)
Remark 6.4. Using the operator $A_1^{-1}$, the rotation of the octonion $x \in \mathbb{O}(\alpha, \beta, \gamma)$ on the angle $\lambda$ around the unit vector $w \in \mathbb{S}_G^2$ is defined by the formula

$$x^\tau = \overline{u} xu,$$

where $u \in \mathbb{S}_G^2, w \in \mathbb{S}_G^2,$ $u = \cos \frac{\lambda}{2} + w \sin \frac{\lambda}{2}$ and $\overline{u} = \cos \frac{\lambda}{2} - w \sin \frac{\lambda}{2}$.

By straightforward calculations, it results that rotation does not transform the octonion-scalar part, but the octonion-vector part $\overline{a}^\tau$ is rotated on the angle $\lambda$ around $w.$

Example 6.5. 1) Let $a \in S^3,$

$$a = \frac{\sqrt{2}}{2} + \frac{1}{\sqrt{14}} \tilde{f}_1 + \frac{1}{\sqrt{14}} \tilde{f}_2 + \frac{1}{\sqrt{14}} \tilde{f}_3 + \frac{1}{\sqrt{14}} \tilde{f}_4 + \frac{1}{\sqrt{14}} \tilde{f}_5 + \frac{1}{\sqrt{14}} \tilde{f}_6 + \frac{1}{\sqrt{14}} \tilde{f}_7,$$

we have $\cos \lambda = \frac{\sqrt{2}}{2}, \sin \lambda = \frac{\sqrt{2}}{2}.$ It results that $a = \cos \frac{\pi}{4} + v \sin \frac{\pi}{4},$ where $v = \frac{1}{\sqrt{3}}(\tilde{f}_1 + \tilde{f}_2 + \tilde{f}_3 + \tilde{f}_4 + \tilde{f}_5 + \tilde{f}_6 + \tilde{f}_7).$ The vector $a$ corresponds to the rotation of the space $\mathbb{R}^8$ on the angle $\frac{\pi}{2}$ around the vector $v = \left(\frac{1}{\sqrt{3}}, \frac{1}{\sqrt{4}}, \ldots, \frac{1}{\sqrt{14}}\right) \in \mathbb{R}^7$ written in the canonical basis.

2) In the algebra $\mathbb{O}(2, 4, 7),$ for the above element $a \in S^3,$ we have $b = A^{-1}(a) = \frac{\sqrt{2}}{2} + \frac{1}{\sqrt{14}} \tilde{f}_1 + \frac{1}{\sqrt{14}} \tilde{f}_2 + \frac{1}{\sqrt{14}} \tilde{f}_3 + \frac{1}{\sqrt{14}} \tilde{f}_4 + \frac{1}{\sqrt{14}} \tilde{f}_5 + \frac{1}{\sqrt{14}} \tilde{f}_6 + \frac{1}{\sqrt{14}} \tilde{f}_7 \in \mathbb{S}_G^3,$ and corresponds to the rotation of the space $\mathbb{R}^8$ on the angle $\frac{\pi}{2}$ around the vector $v = \left(\frac{1}{\sqrt{3}}, \frac{1}{\sqrt{4}}, \frac{1}{\sqrt{7}}, \frac{1}{\sqrt{14}}, \frac{1}{\sqrt{14}}, \frac{1}{\sqrt{14}}\right) \in \mathbb{R}^7$ written in the basis $\{f_1, \ldots, f_7\}.$

Case when $\alpha = \beta = 1, \gamma = -1$

In this case, the octonion algebra $\mathbb{O}(1, 1, -1)$ is not a division algebra (is a split algebra). The norm of an octonion $a \in \mathbb{O}(1, 1, -1),$ $a = a_0 + a_1 f_1 + a_2 f_2 + a_3 f_3 + a_4 f_4 + a_5 f_5 + a_6 f_6 + a_7 f_7,$ in this situation, can be positive, zero or negative. In the following, we used definitions and propositions obtained for the split quaternions as in [16] to generalized them to similar results for the split octonions. A split octonion is called spacelike, timelike or lightlike if $N(a) < 0, N(a) > 0$ or $N(a) = 0.$ If $N(a) = 1,$ then $a$ is called the unit split octonion.

Spacelike octonions

Let $a \in \mathbb{O}(1, 1, -1)$ such that $N(a) = -1,$ be a spacelike octonion. For the octonion $w = a_1 f_1 + a_2 f_2 + a_3 f_3 + a_4 f_4 + a_5 f_5 + a_6 f_6 + a_7 f_7,$ we have $N(w) = -1$ and $t(w) = 0,$ therefore $w^2 = 1.$ Denoting $\sinh \lambda = a_0$ and $\cosh \lambda = \sqrt{1 + a_0^2}, \lambda \in \mathbb{R},$ it results:

$$a = e^{\lambda w} = \sinh \lambda + w \cosh \lambda.$$

If $a \in \mathbb{O}(1, 1, -1)$ with $N(a) < 0,$ we have $a = \sqrt{|N(a)|}(\sinh \lambda + w \cosh \lambda).$

Proposition 6.6. We have that $a^n = (\sqrt{|N(a)|})^n(\sinh \lambda + w \cosh \lambda),$ for $n$ odd and $a^n = (\sqrt{|N(a)|})^n(\cosh \lambda + w \sinh \lambda),$ for $n$ even. □
Timelike octonions
Let $a \in \mathbb{O}(1,1,-1)$ be a timelike octonion such that $N(a) = 1$. If $1 - a_0^2 > 0$, for the octonion $w = \frac{a_1 f_1 + a_2 f_2 + a_3 f_3 + a_4 f_4 + a_5 f_5 + a_6 f_6 + a_7 f_7}{\sqrt{1 - a_0^2}}$, we have $N(w) = 1$ and $t(w) = 0$, therefore $w^2 = -1$ Denoting $\cos \lambda = a_0$ and $\sin \lambda = \sqrt{1 - a_0^2}$, $\lambda \in \mathbb{R}$, it results:

**Proposition 6.7.** With the above notations, we have the Euler’s formula:

$$a = e^{\lambda w} = \cos \lambda + w \sin \lambda.$$

**Proof.** Indeed, $e^{\lambda w} = \sum_{n=0}^{\infty} \frac{(\lambda w)^n}{n!} = \sum_{n=1}^{\infty} (-1)^n \frac{\lambda^{2n}}{(2n)!} + w \sum_{n=1}^{\infty} (-1)^n \frac{\lambda^{2n-1}}{(2n-1)!} = \cos \lambda + w \sin \lambda$. □

If $a \in \mathbb{O}(1,1,-1)$ with $N(a) > 0$, it results $a = \sqrt{N(a)} (\cos \lambda + w \sin \lambda)$.

**Proposition 6.8.** We have that $a^n = \left(\sqrt{N(a)}\right)^n (\cos n \lambda + w \sin n \lambda)$. □

**Proposition 6.9.** 1) If $a \in \mathbb{O}(1,1,-1)$, it results $a^n = \left(\sqrt{N(a)}\right)^n (\cos n \lambda + w \sin n \lambda)$.

2) The equation $x^n = a$ has $n$ roots: $\sqrt[n]{\left|N(a)\right|} (\cos \frac{\lambda}{n} + w \sin \frac{\lambda}{n})$. □

If $1 - a_0^2 < 0$, we have $w = \frac{a_1 f_1 + a_2 f_2 + a_3 f_3 + a_4 f_4 + a_5 f_5 + a_6 f_6 + a_7 f_7}{\sqrt{a_0^2 - 1}}$, with $N(w) = -1$ and $t(w) = 0$, therefore $w^2 = 1$. Denoting $\cosh \lambda = a_0$ and $\sinh \lambda = \sqrt{a_0^2 - 1}$, $\lambda \in \mathbb{R}$, it results:

**Proposition 6.10.** With the above notations, we have Euler’s formula:

$$a = e^{\lambda w} = \cosh \lambda + w \sinh \lambda.$$

**Proof.** Indeed, $e^{\lambda w} = \sum_{n=0}^{\infty} \frac{(\lambda w)^n}{n!} = \sum_{n=0}^{\infty} \frac{\lambda^{2n}}{(2n)!} + w \sum_{n=0}^{\infty} \frac{\lambda^{2n+1}}{(2n+1)!} = \cosh \lambda + w \sinh \lambda$. □

If $a \in \mathbb{O}(1,1,-1)$ with $N(a) < 0$, it results $a = \sqrt{|N(a)|}(\cosh \lambda + w \sinh \lambda)$.

**Proposition 6.11.** 1) If $a \in \mathbb{O}(1,1,-1)$, then $a^n = \left(\sqrt{|N(a)|}\right)^n (\cosh n \lambda + w \sinh n \lambda)$.

2) The equation $x^n = a$ has only one root: $\sqrt[n]{\left|N(a)\right|} (\cosh \frac{\lambda}{n} + w \sinh \frac{\lambda}{n})$. □

**Remark 6.12.** Using the above technique, De Moivre’s formula and Euler’s formula can be easy proved for the octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$, with $\alpha, \beta, \gamma \in \mathbb{R} \setminus \{0\}$ such that $\mathbb{O}(\alpha, \beta, \gamma)$ is split. Thus, the study of algebraic equations in an arbitrary algebra $\mathbb{O}(\alpha, \beta, \gamma)$ with $\alpha, \beta, \gamma \in \mathbb{R} \setminus \{0\}$ was reduced to study of the corresponding algebraic equation in one of the following two algebras: division octonion algebra $\mathbb{O}(1,1,1)$ or algebra $\mathbb{O}(1,1,-1)$.
Conclusion

In this paper, we used isomorphism between the real quaternion algebras $\mathbb{H}(\gamma_1, \gamma_2)$ and $\mathbb{H}(1, 1)$ or $\mathbb{H}(1, -1)$ to reduced the study of some algebraic equations in an arbitrary algebra $\mathbb{H}(\gamma_1, \gamma_2)$ with $\gamma_1, \gamma_2 \in \mathbb{R} \setminus \{0\}$ to study of the corresponding algebraic equation in one of the following two algebras: division quaternion algebra or coquaternion algebra. The same result was obtained for the generalized octonion algebra $\mathbb{O}(\alpha, \beta, \gamma)$. De Moivre’s formula in generalized quaternion algebras and generalized octonion division algebras was proved using this new method.

Acknowledgement

The authors thank the referee for his/her suggestions which helped us to improve this paper.

For the first author, this paper is partially supported by the CNCS/UEFISCDI grant PN-II-PT-PCCA 2013-4-0377.

References

[1] K. Carmody, *Circular and Hyperbolic Quaternions, Octonions, and Sedenions—Further Results*. Appl. Math. Comput., 84 (1997), 27-47.
[2] J. Cockle, *On Systems of Algebra involving more than one Imaginary*. Philosophical Magazine, 35 (3) (1849), 434-435.
[3] E. Cho, *De-Moivre’s formula for quaternions*. Appl. Math. Lett., 11 (6) (1998), 33-35.
[4] S. Eilenberg, I. Niven, *The fundamental theorem of algebra for quaternions*. Bull. Amer. Math. Soc., 50 (1944), 246-248.
[5] M. Erdoğdu, M. Özdemir, *Two-sided linear split quaternionic equations with unknowns*. Linear and Multilinear Algebra, DOI:10.1080/03081087.2013.851196
[6] C. Flaut, *Some equations in algebras obtained by the Cayley-Dickson process*. An. Șt. Univ. Ovidius Constanța, 9(2) (2001), 45-68.
[7] C. Flaut, M. Ștefănescu, *Some equations over generalized quaternion and octonion division algebras*. Bull. Math. Soc. Sci. Math. Roumanie, 52 (100) no. 4 (2009), 427-439.
[8] S. Ivanov, S. Zamkovoy, *Parahermitian and paraquaternionic manifolds*. Diff. Geometry Appl. 23, pp. 205-234.
[9] D. Janovská, G. Opfer, *Linear equations and the Kronecker product in coquaternions*. Mitt. Math. Ges. Hamburg 33 (2013), 181-196.
[10] T.Y. Lam, *Quadratic forms over fields*. AMS, Providence, Rhode Island, 2004.
[11] A. B. Mamagani, M. Jafari, *On Properties of Generalized Quaternion Algebra*. J. Novel Appl. Sci., 2 (12) (2013), 683-689.
[12] D. A. Mierzejewski, V. S. Szpakowski, *On solutions of some types of quaternion quadratic equations*. Bull. Soc. Sci. Lett. Łódź 58, Ser. Rech. Déform., 55 (2008), 49-58.
[13] D. A. Mierzejewski *Linear manifolds in sets of solutions of quaternionic polynomial equations of several types.* Adv. Appl. Clifford Alg., 21 (2011), 417-428.

[14] D. Mierzejewski *Spheres in sets of solutions of quadratic quaternionic equations of some types.* Bull. Soc. Sci. Lett. Łódź, Ser. Rech. Déform., 60 (1) (2010), 49-58.

[15] I. Niven, *Equations in Quaternions.* Amer. Math. Monthly 48 (1941), 654-661.

[16] M. Özdemir, *The roots of a split quaternion.* Appl. Math. Lett., 22 (2009) 258-263.

[17] A. Pogoruy, R. M. Rodrigues-Dagnino, *Some algebraic and analytical properties of coquaternion algebra.* Adv. Appl. Clifford Alg., 20 (2010), 79-84.

[18] B. A. Rosenfeld, *A History of Non-Euclidean Geometry.* Springer-Verlag, 1988.

[19] Schafer, R. D., *An Introduction to Nonassociative Algebras,* Academic Press, New-York, 1966.

[20] V. S. Shpakivskyi, *Linear quaternionic equations and their systems.* Adv. Appl. Clifford Alg., 21(2011), 637-645.

[21] W. D. Smith, *Quaternions, octonions, and now, 16-ons, and 2n-ons; New kinds of numbers.* www.math.temple.edu/2dcwds/homepage/nce2.ps, 2004.

[22] V. Szpakowski, *Solution of general quadratic quaternionic equations.* Bull. Soc. Sci. Lett. Łódź Ser. Rech. Déform., 58 (2009), 45-58.

[23] Y. Tian, *Similarity and cosimilarity of elements in the real Cayley-Dickson algebras.* Adv. Appl. Clifford Alg. 9 (1) (1999), 61-76.

Cristina Flaut  
Faculty of Mathematics and Computer Science  
Ovidius University  
Bd. Mamaia 124  
900527 Constanta  
Romania  
http://cristinaflaut.wikispaces.com/; http://www.univ-ovidius.ro/math/  
e-mail: cflaut@univ-ovidius.ro  
cristina_flaut@yahoo.com

Vitalii Shpakivskyi  
Department of Complex Analysis and Potential Theory  
Institute of Mathematics of the National Academy of Sciences of Ukraine  
3, Tereshchenkivs’ka st.  
01601 Kiev-4  
Ukraine  
http://www.imath.kiev.ua/~complex/  
e-mail: shpakivskyi@mail.ru

Received: June 1, 2014.  
Accepted: July 2, 2014.