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web if one has a linear transformation in functional form it is easy to determine the transformation matrix a by transforming each of the vectors of the standard basis by t then inserting the result into the columns of a matrix in other words for example the function is a linear transformation

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web in linear algebra a rotation matrix is a transformation matrix that is used to perform a rotation in euclidean space for

example using the convention below the matrix rotates points in the xy plane counterclockwise through an angle θ about the origin of a two dimensional cartesian coordinate system

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web orthogonality of the transformation matrix q as in the two dimensional case the transformation matrix is orthogonal $q^T q = I$ this follows from $\begin{pmatrix} 1 & 0 \\ 0 & 1 \end{pmatrix} = \begin{pmatrix} 1 & 0 \\ 0 & 1 \end{pmatrix}^T \begin{pmatrix} 1 & 0 \\ 0 & 1 \end{pmatrix}$ example consider a cartesian coordinate system with base vectors e_1 a coordinate transformation is carried out with the new basis given by $\begin{pmatrix} 3 & 2 \\ 3 & 1 \end{pmatrix}$ $\begin{pmatrix} 2 & 3 \\ 3 & 1 \end{pmatrix}$

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web coordinates of v the standard coordinates are $v = \begin{pmatrix} v_1 \\ v_2 \end{pmatrix}$ are the b_1 b_2 are assumed if no other basis is specified this means $v = v_1 e_1 + v_2 e_2$ if $b = \{v_1, v_2\}$ is a basis of \mathbb{R}^n then the matrix S which contains the vectors v_k as column vectors is called the coordinate change matrix

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web the vector \mathbf{b} is parallel to \mathbf{a} and points in the same direction if $\alpha > 0$ for $\alpha < 0$ the vector \mathbf{b} is parallel to but points in the opposite direction antiparallel if we multiply an arbitrary vector \mathbf{a} by the inverse of its magnitude $1/|\mathbf{a}|$ we obtain a

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web sep 17 2022 consider the matrix transformation $T: \mathbb{R}^2 \rightarrow \mathbb{R}^2$ that assigns to a vector \mathbf{x} the closest vector on horizontal axis as illustrated in figure 2.6.20 this transformation is called the projection onto the horizontal axis

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web and now that we know what \mathbf{d} is we can now solve for \mathbf{a} we can now solve for the transformation matrix with respect to the standard basis so to do that we have to figure out \mathbf{c} and \mathbf{c}^{-1} so \mathbf{c} remember \mathbf{c} is just the change of basis matrix and all that is is the basis vectors it's just a matrix with the basis vectors in the column

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web a translation by a nonzero vector is not a linear map because linear maps must send the zero vector to the zero vector however translations are very useful in performing coordinate transformations i'll introduce the following terminology for the composite of a linear transformation and a translation definition let \mathbf{a} be a real matrix

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web any vector \mathbf{v} represented in \mathbf{b} can be transformed to a representation in \mathbf{c} as follows under the transformation of basis notice that the superscript on the transformation matrix \mathbf{m} and the subscript on the coordinate vector \mathbf{v} are the same and seemingly cancel leaving the remaining subscript

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