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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

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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 1 5 11 1 5 13 example consider a cartesian coordinate system with base vectors e_i a coordinate transformation is carried out with the new basis given by $\begin{pmatrix} 3 & 3 & 2 \\ 3 & 3 & 1 \\ 1 & 2 & 3 \\ 3 & 1 & 3 \\ 2 & & \end{pmatrix}$

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web coordinates of v the standard coordinates are v_3 are the b_1 b are assumed if no other basis is specified this means $v = 3e_1 + 4e_2 + 4e_5 + 2e_6$ if $b = \{v_1, v_2, v_3\}$ 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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second order tensor projected in the first order tensor the stress and strain tensors are now defined by and then once
constructs the bound matrix in the orthonormal base with the rotation matrix in base

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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
composition 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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