# Modeling and Simulation

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Academic year: 2023/2024

# Overview of Linear Algebra in Modeling and Simulation

- Linear algebra is a fundamental mathematical discipline that plays a pivotal role in computer science, particularly in the field of modeling and simulation. It provides a powerful set of tools for representing and solving complex problems that arise in various computational domains.
- Linear algebra is a branch of mathematics that focuses on vector spaces and linear mappings between these spaces.
- In this chapter, we will explore the foundational concepts of linear algebra and their applications in computer science.

# Definitions (1): Vectors and Vector Spaces

- Vectors: Vectors are mathematical entities that represent quantities with both magnitude and direction. In computer science, vectors can represent data such as position, velocity, or color.
- Vector Operations: Addition: Component-wise addition of vectors.
  Scalar Multiplication: Multiplying a vector by a scalar.
- Vector spaces are sets of vectors with defined operations that satisfy certain properties.
- Subspaces are subsets of vector spaces that are also vector spaces.

## Definitions (2): Vectors and Vector Spaces

- Consider the set of all 2D vectors, denoted as $\mathbb{R}^2$, where each vector is in the form $\begin{bmatrix} x \\ y \end{bmatrix}$ and $x, y$ are real numbers.
- This set of all 2D vectors, $\mathbb{R}^2$, is a vector space. To be a vector space, it must satisfy the following properties:

  1. Closure under Addition: If $\mathbf{u} = \begin{bmatrix} u_1 \\ u_2 \end{bmatrix}$ and $\mathbf{v} = \begin{bmatrix} v_1 \\ v_2 \end{bmatrix}$ are vectors in $\mathbb{R}^2$, then their sum $\mathbf{u} + \mathbf{v}$ is also in $\mathbb{R}^2$.
  Example: If $\mathbf{u} = \begin{bmatrix} 1 \\ 2 \end{bmatrix}$ and $\mathbf{v} = \begin{bmatrix} -1 \\ 3 \end{bmatrix}$, then $\mathbf{u} + \mathbf{v} = \begin{bmatrix} 0 \\ 5 \end{bmatrix}$.
  2. Closure under Scalar Multiplication: If $\mathbf{u}$ is a vector in $\mathbb{R}^2$ and $c$ is a scalar, then the product $c\mathbf{u}$ is also in $\mathbb{R}^2$.
  Example: If $\mathbf{u} = \begin{bmatrix} 2 \\ -1 \end{bmatrix}$ and $c = 3$, then $c\mathbf{u} = \begin{bmatrix} 6 \\ -3 \end{bmatrix}$.

# Definitions (3): Vectors and Vector Spaces

- 3. Associativity of Addition and Scalar Multiplication: The operations of addition and scalar multiplication are associative.
- 4. Identity Elements: There exists an additive identity (zero vector) and a multiplicative identity (1) such that $\mathbf{u} + \mathbf{0} = \mathbf{u}$ and $1 \cdot \mathbf{u} = \mathbf{u}$.
- 5. Inverse Elements: For every vector $\mathbf{u}$, there exists an additive inverse $-\mathbf{u}$ such that $\mathbf{u} + (-\mathbf{u}) = \mathbf{0}$.

## Definitions (4): Vectors and Vector Spaces

- Now, consider the subset $W$ of $\mathbb{R}^2$ consisting of all vectors where the second component is zero. Mathematically, $W = \{\begin{bmatrix} x \\ 0 \end{bmatrix} \mid x \in \mathbb{R}\}$. $W$ is a subspace of $\mathbb{R}^2$. To be a subspace, it must satisfy the following:
  1. Closure under Addition: If $\mathbf{v}_1$ and $\mathbf{v}_2$ are vectors in $W$, then $\mathbf{v}_1 + \mathbf{v}_2$ is also in $W$.
  Example: If $\mathbf{v}_1 = \begin{bmatrix} 2 \\ 0 \end{bmatrix}$ and $\mathbf{v}_2 = \begin{bmatrix} -1 \\ 0 \end{bmatrix}$, then $\mathbf{v}_1 + \mathbf{v}_2 = \begin{bmatrix} 1 \\ 0 \end{bmatrix}$, which is in $W$.
  2. Closure under Scalar Multiplication: If $c$ is a scalar and $\mathbf{v}$ is in $W$, then $c\mathbf{v}$ is also in $W$.
  Example: If $\mathbf{v} = \begin{bmatrix} 3 \\ 0 \end{bmatrix}$ and $c = -2$, then $c\mathbf{v} = \begin{bmatrix} -6 \\ 0 \end{bmatrix}$, which is in $W$.

# Definitions (5): Vectors and Vector Spaces

3. Contains the Zero Vector: The zero vector is in $W$.
4. Closed under Negation: For every vector $\mathbf{v}$ in $W$, its additive inverse $-\mathbf{v}$ is also in $W$.

Therefore, $W$ is a subspace of $\mathbb{R}^2$.

# Definition of Matrices

- Matrices are rectangular arrays of numbers.
- Example: $A = \begin{bmatrix} 1 & 2 \\ 3 & 4 \end{bmatrix}$
- Addition: Component-wise addition of matrices.
- Multiplication: Not element-wise; it's a specific operation involving rows and columns.

  Example: If $B = \begin{bmatrix} 5 & 6 \\ 7 & 8 \end{bmatrix}$, then $A + B = \begin{bmatrix} 6 & 8 \\ 10 & 12 \end{bmatrix}$.

## Systems of Linear Equations

- Linear systems can be represented as matrices and vectors.
- Example: $A\mathbf{x} = \mathbf{b}$, where $A = \begin{bmatrix} 2 & 3 \\ 1 & -1 \end{bmatrix}$, $\mathbf{x} = \begin{bmatrix} x \\ y \end{bmatrix}$, and $\mathbf{b} = \begin{bmatrix} 8 \\ 1 \end{bmatrix}$.
- Matrix inversion, Gaussian elimination, and other methods.

  Example: Solving the system $A\mathbf{x} = \mathbf{b}$ yields $\mathbf{x} = \begin{bmatrix} 3 \\ 1 \end{bmatrix}$.

## Linear transformations in Simulations

- Linear transformations are mathematical operations that preserve the properties of vector spaces.
- In simulations, they are crucial for modeling various physical phenomena accurately.
- This presentation explores the concept of linear transformations and their applications in simulations.
- Linear transformations are functions that map vectors from one vector space to another while preserving linear relationships.
- They are characterized by two properties: preservation of vector addition and scalar multiplication.

# Linear transformations in Simulations

- 1. Preservation of Addition: $T(\mathbf{u}+\mathbf{v}) = T(\mathbf{u}) + T(\mathbf{v})$
- 2. Preservation of Scalar Multiplication: $T(c\mathbf{u}) = cT(\mathbf{u})$
- 3. Preservation of the Zero Vector: $T(\mathbf{0}) = \mathbf{0}$

## Linear transformations in Simulations

- Linear transformations can be represented by matrices.
- Each column of the matrix represents the image of a basis vector under the transformation. Example:
  Consider a 2D rotation transformation by an angle $\theta$.

$$T(\mathbf{v}) = \begin{bmatrix} \cos(\theta) & -\sin(\theta) \\ \sin(\theta) & \cos(\theta) \end{bmatrix} \mathbf{v}$$

# Examples of Linear Transformations (1)

- Translation: Translation shifts all points in a space by a fixed vector. - Mathematical Representation: - Let $\mathbf{v} = \begin{bmatrix} x \\ y \end{bmatrix}$ be a point in 2D space. - The translation of $\mathbf{v}$ by a vector $\mathbf{t} = \begin{bmatrix} t_x \\ t_y \end{bmatrix}$ is given by:

$$T(\mathbf{v}) = \mathbf{v} + \mathbf{t}$$

Example: - If $\mathbf{v} = \begin{bmatrix} 2 \\ 3 \end{bmatrix}$ and $\mathbf{t} = \begin{bmatrix} 1 \\ -2 \end{bmatrix}$, the translated point $T(\mathbf{v})$ would be $\begin{bmatrix} 2 \\ 3 \end{bmatrix} + \begin{bmatrix} 1 \\ -2 \end{bmatrix} = \begin{bmatrix} 3 \\ 1 \end{bmatrix}$.

## Examples of Linear Transformations (2)

- Scaling: Scaling enlarges or shrinks objects by a fixed factor along each axis. - Mathematical Representation: - Let $\mathbf{v} = \begin{bmatrix} x \\ y \end{bmatrix}$ be a point in 2D space. - The scaling of $\mathbf{v}$ by factors $s_x$ and $s_y$ along the x and y axes, respectively, is given by:

$$T(\mathbf{v}) = \begin{bmatrix} s_x & 0 \\ 0 & s_y \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

- Example: - If $\mathbf{v} = \begin{bmatrix} 2 \\ 3 \end{bmatrix}$ and $s_x = 2, s_y = 0.5$, the scaled point $T(\mathbf{v})$ would be $\begin{bmatrix} 2 & 0 \\ 0 & 0.5 \end{bmatrix} \begin{bmatrix} 2 \\ 3 \end{bmatrix} = \begin{bmatrix} 4 \\ 1.5 \end{bmatrix}$.

## Examples of Linear Transformations (3)

- Rotation: Description: Rotation rotates objects about the origin by a certain angle. - Mathematical Representation: - Let $\mathbf{v} = \begin{bmatrix} x \\ y \end{bmatrix}$ be a point in 2D space. - The rotation of $\mathbf{v}$ by an angle $\theta$ is given by:

$$T(\mathbf{v}) = \begin{bmatrix} \cos(\theta) & -\sin(\theta) \\ \sin(\theta) & \cos(\theta) \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

- Example: - If $\mathbf{v} = \begin{bmatrix} 1 \\ 0 \end{bmatrix}$ and $\theta = \frac{\pi}{2}$, the rotated point $T(\mathbf{v})$ would be $\begin{bmatrix} \cos(\frac{\pi}{2}) & -\sin(\frac{\pi}{2}) \\ \sin(\frac{\pi}{2}) & \cos(\frac{\pi}{2}) \end{bmatrix} \begin{bmatrix} 1 \\ 0 \end{bmatrix} = \begin{bmatrix} 0 \\ 1 \end{bmatrix}$.

## Examples of Linear Transformations (4)

- Reflection: Description: Reflection reflects objects across a line or plane. - Mathematical Representation: - Let $\mathbf{v} = \begin{bmatrix} x \\ y \end{bmatrix}$ be a point in 2D space. - The reflection of $\mathbf{v}$ across the x-axis is given by:

$$T(\mathbf{v}) = \begin{bmatrix} 1 & 0 \\ 0 & -1 \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

- Example: - If $\mathbf{v} = \begin{bmatrix} 2 \\ 3 \end{bmatrix}$, the reflected point $T(\mathbf{v})$ across the x-axis would be $\begin{bmatrix} 1 & 0 \\ 0 & -1 \end{bmatrix} \begin{bmatrix} 2 \\ 3 \end{bmatrix} = \begin{bmatrix} 2 \\ -3 \end{bmatrix}$.

This expanded slide provides detailed examples of various linear transformations, including translation, scaling, rotation, reflection, and shearing, along with their mathematical representations and specific examples.

## Application in Simulations

- Linear transformations are fundamental in simulations for modeling transformations of objects, materials, and environments. They enable us to simulate various physical phenomena accurately and efficiently.
- In computer graphics, linear transformations are used to transform objects in 2D and 3D space.
- They are applied to vertices of objects to achieve effects like scaling, rotation, translation, and projection.
  Example: Applying a transformation matrix to a vertex to rotate and scale a 3D model.