02-math

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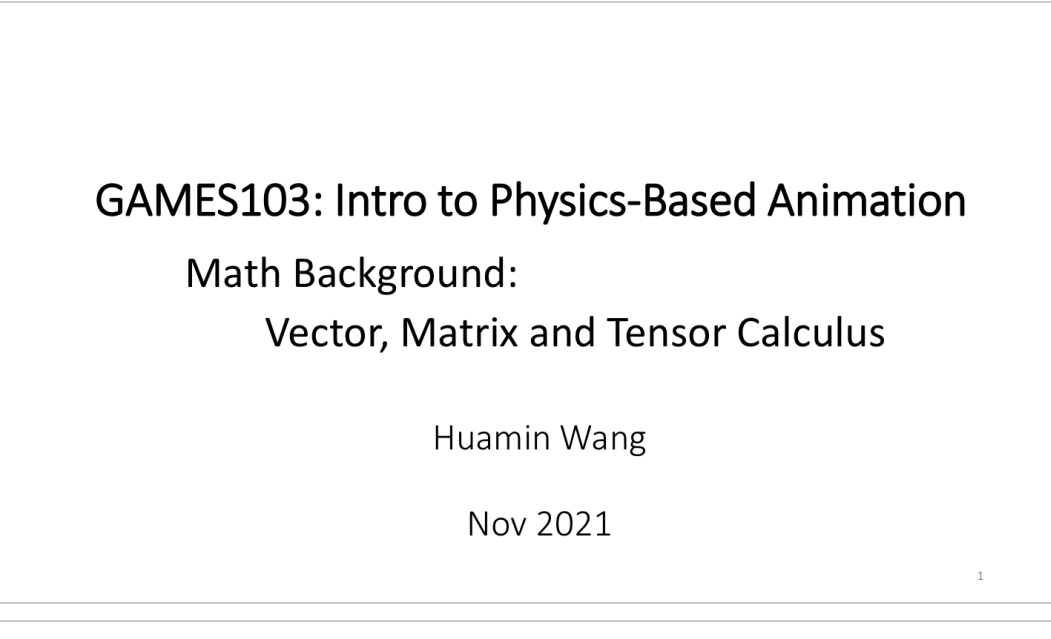
GAMES103-02-math



GAMES103: Intro to Physics-Based Animation

Math Background:
Vector, Matrix and Tensor Calculus

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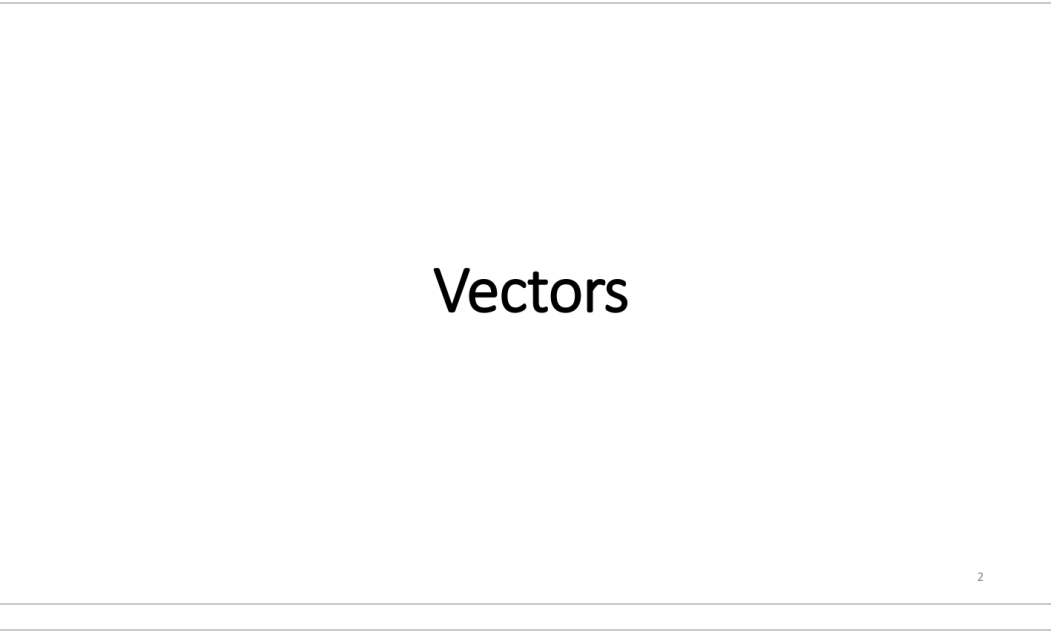
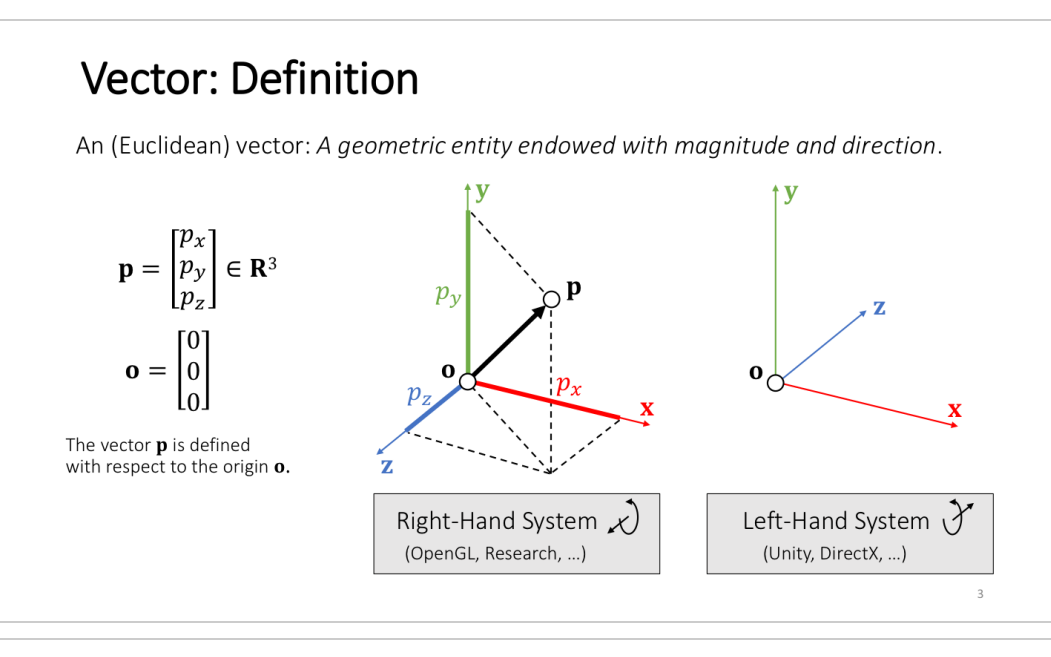
Nov 2021



Vectors



Vector: Definition

An (Euclidean) vector: *A geometric entity endowed with magnitude and direction.*

$\mathbf{p}=\begin{bmatrix}p_x\\p_y\\p_z\end{bmatrix}\in\mathbf{R}^3$

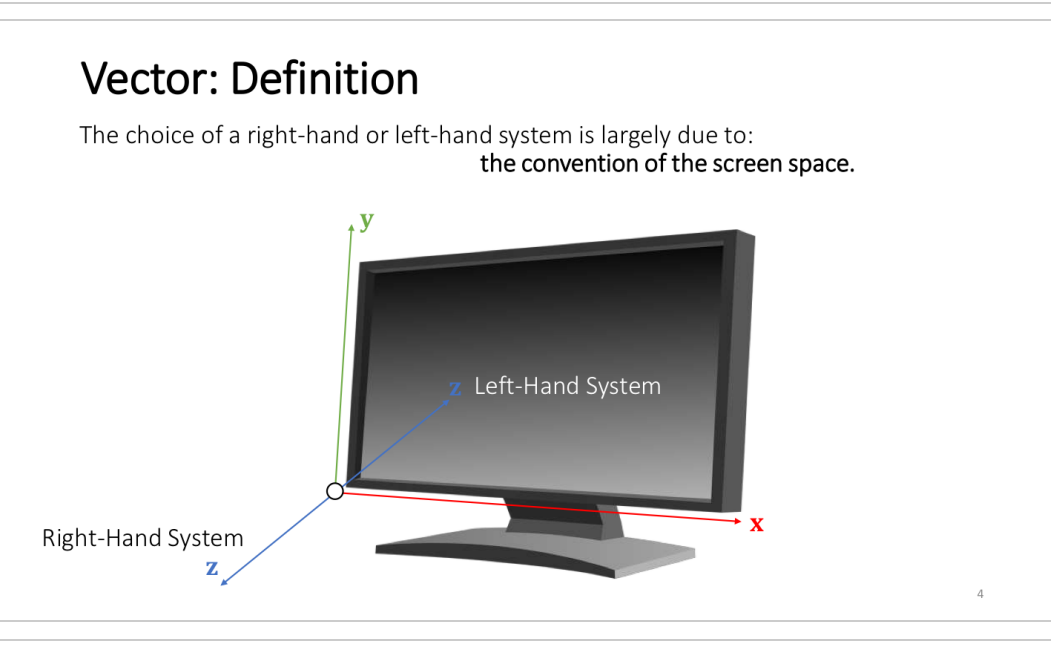
$\mathbf{o}=\begin{bmatrix}0\\0\\0\end{bmatrix}$

The vector $\mathbf{p}$ is defined with respect to the origin $\mathbf{o}$.

Right-Hand System (OpenGL, Research, …)

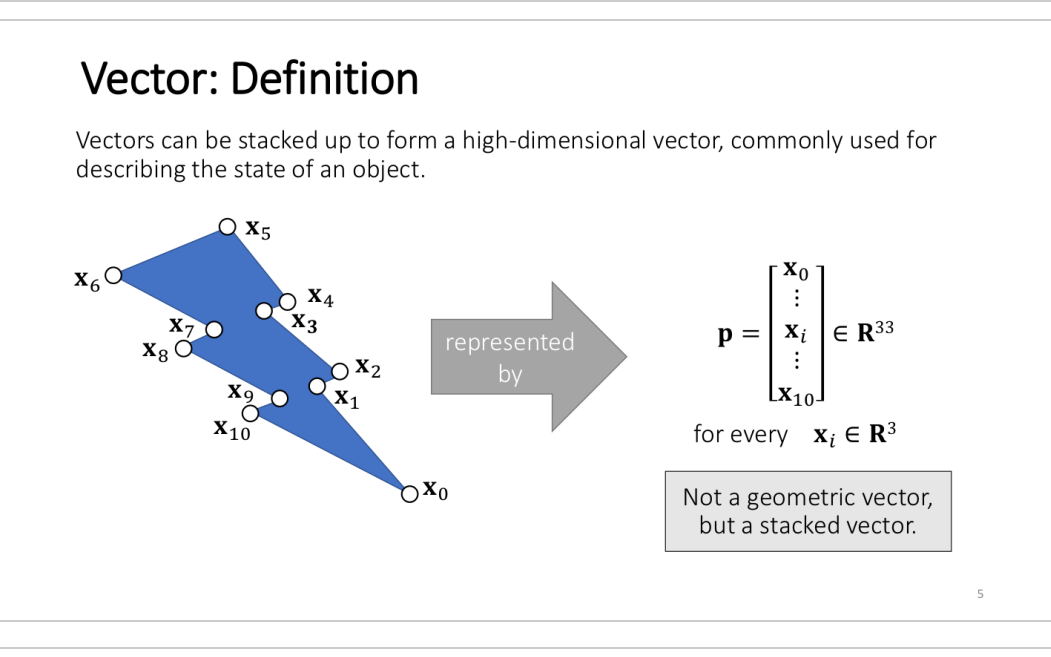
Left-Hand System (Unity, DirectX, …)

x轴：手掌
y轴：大拇指
z轴：手指
左右手都是



Vector: Definition

The choice of a right-hand or left-hand system is largely due to: the convention of the screen space.

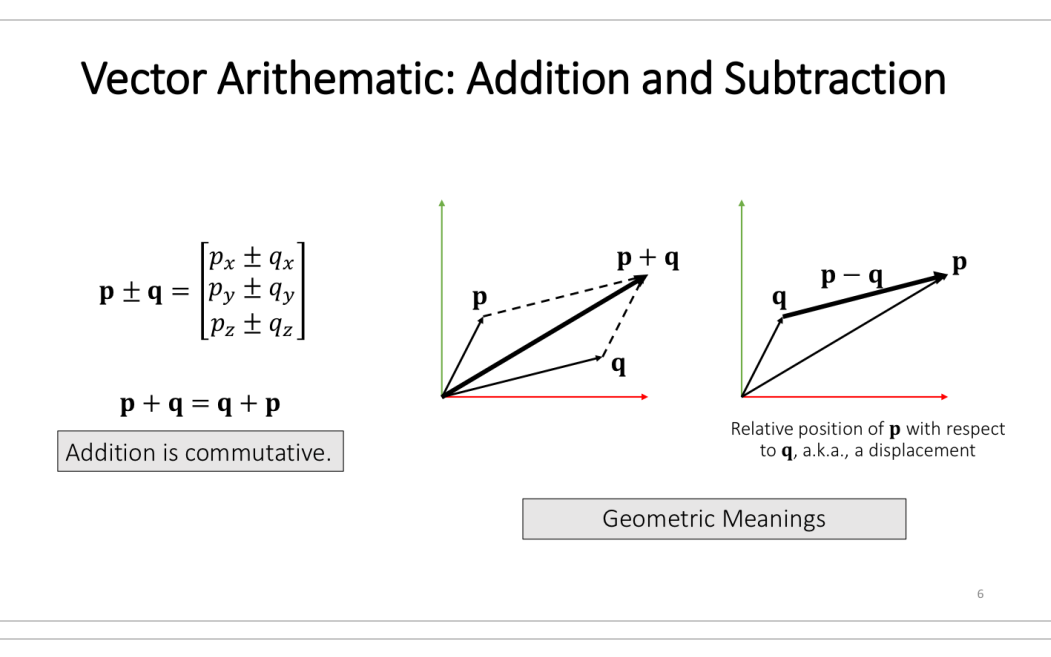


Vector: Definition

Vectors can be stacked up to form a high-dimensional vector, commonly used for describing the state of an object.

$\mathbf{p}=\begin{bmatrix}\mathbf{x}_0\\\vdots\\\mathbf{x}_i\\\vdots\\\mathbf{x}_{10}\end{bmatrix}\in\mathbf{R}^{33}$ for every $\mathbf{x}_i\in\mathbf{R}^3$

Not a geometric vector, but a stacked vector.



Vector Arithematic: Addition and Subtraction

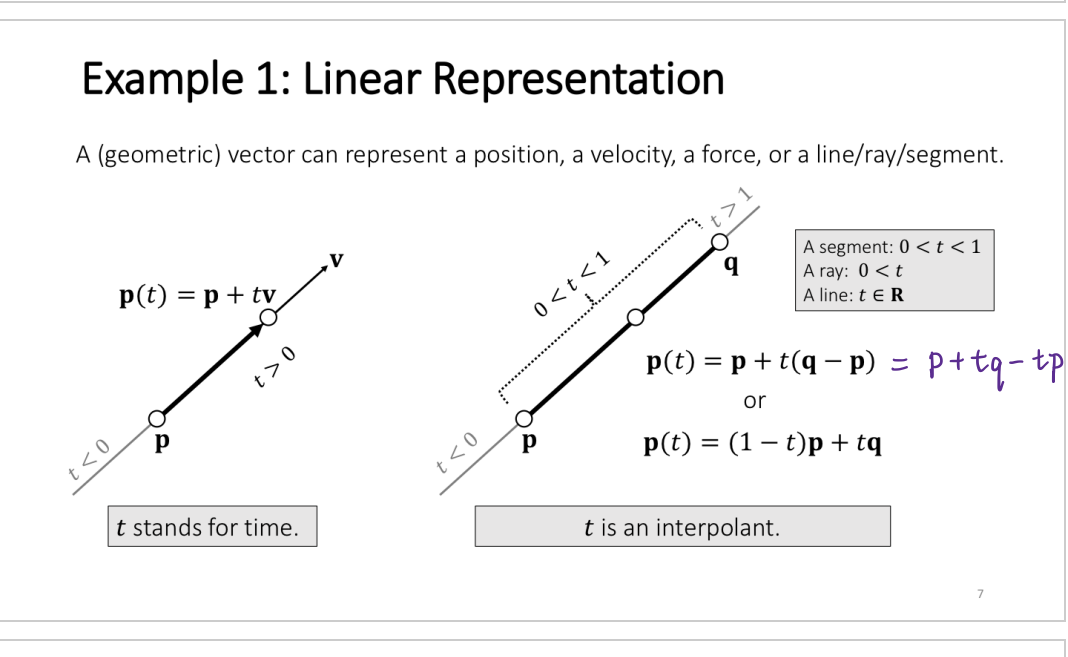
$\mathbf{p}\pm\mathbf{q}=\begin{bmatrix}p_x\pm q_x\\p_y\pm q_y\\p_z\pm q_z\end{bmatrix}$

$\mathbf{p}+\mathbf{q}=\mathbf{q}+\mathbf{p}$

Addition is commutative.

Relative position of **p** with respect to **q**, a.k.a., a displacement

Geometric Meanings



Example 1: Linear Representation

A (geometric) vector can represent a position, a velocity, a force, or a line/ray/segment.

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

A segment: $0<t<1$
A ray: $0<t$
A line: $t\in\mathbf{R}$

$\mathbf{p}(t)=\mathbf{p}+t(\mathbf{q}-\mathbf{p})$ = p+tq−tp

or

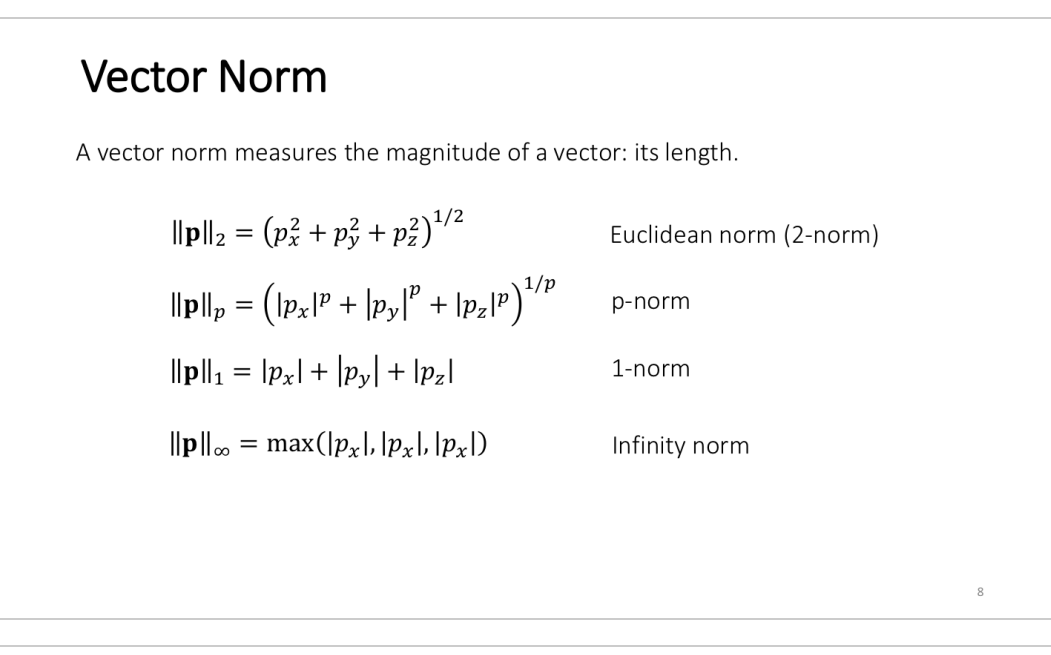
$\mathbf{p}(t)=(1-t)\mathbf{p}+t\mathbf{q}$

t stands for time.

t is an interpolant.

t的取值不同，线的类型不同

因为 1−t > 0，所以 t<1



Vector Norm

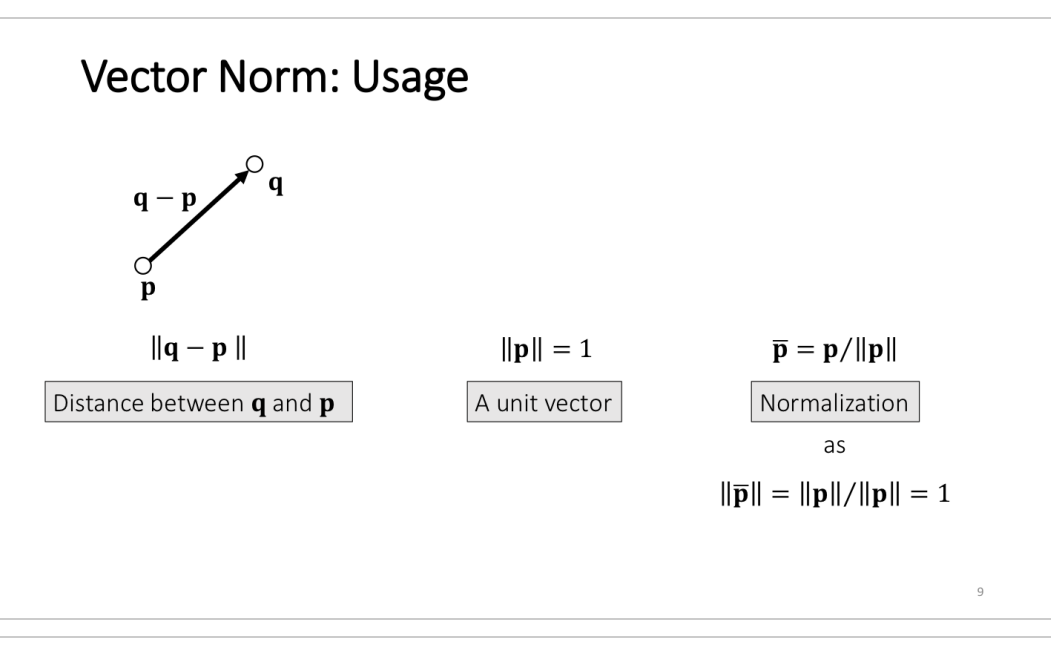
A vector norm measures the magnitude of a vector: its length.

$\|\mathbf{p}\|_2=(p_x^2+p_y^2+p_z^2)^{1/2}$ Euclidean norm (2-norm)

$\|\mathbf{p}\|_p=(|p_x|^p+|p_y|^p+|p_z|^p)^{1/p}$ p-norm

$\|\mathbf{p}\|_1=|p_x|+|p_y|+|p_z|$ 1-norm

$\|\mathbf{p}\|_\infty=\max(|p_x|,|p_x|,|p_x|)$ Infinity norm



Vector Norm: Usage

$\|\mathbf{q}-\mathbf{p}\|$ — Distance between **q** and **p**

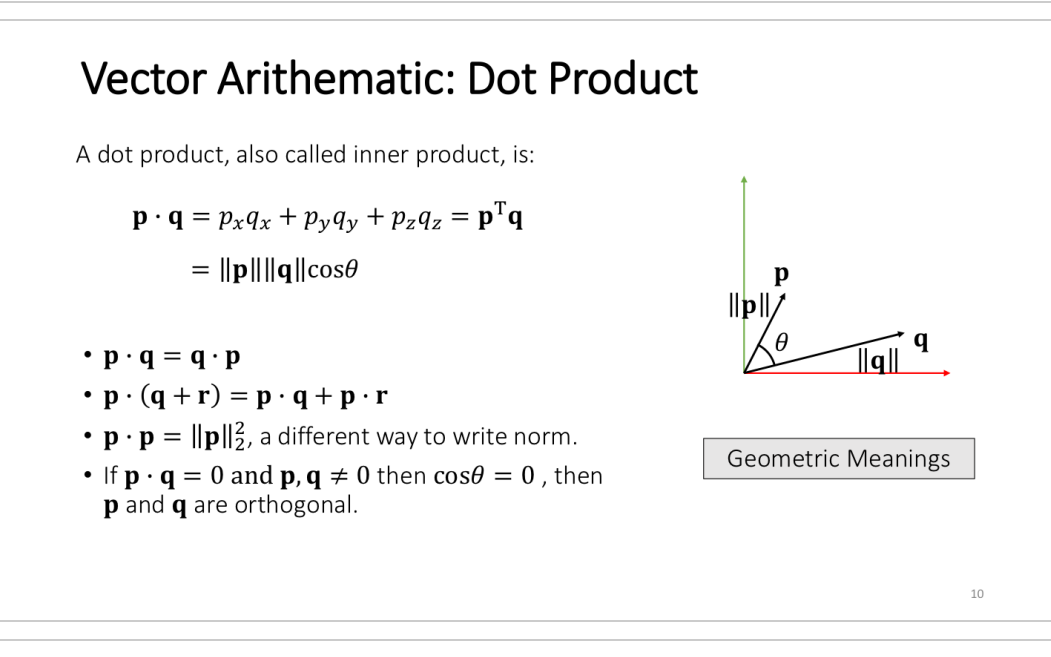
$\|\mathbf{p}\|=1$ — A unit vector

$\bar{\mathbf{p}}=\mathbf{p}/\|\mathbf{p}\|$ — Normalization

as

$\|\bar{\mathbf{p}}\|=\|\mathbf{p}\|/\|\mathbf{p}\|=1$

标准化？归一化？



Vector Arithematic: Dot Product

A dot product, also called inner product, is:

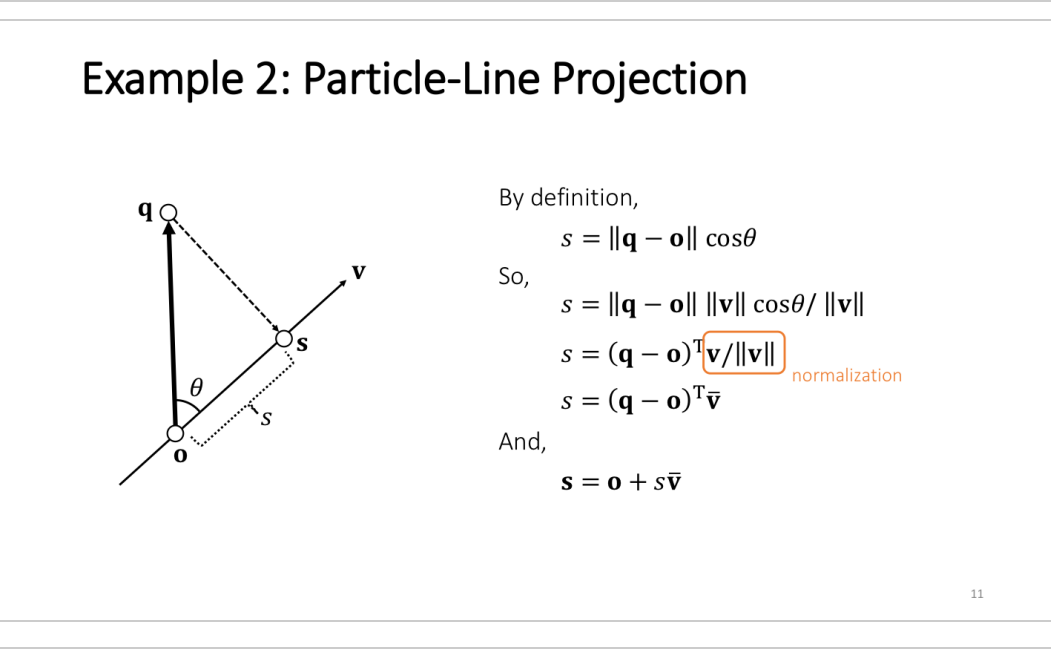
$\mathbf{p}\cdot\mathbf{q}=p_xq_x+p_yq_y+p_zq_z=\mathbf{p}^\mathrm{T}\mathbf{q}$
$=\|\mathbf{p}\|\|\mathbf{q}\|\cos\theta$

- $\mathbf{p}\cdot\mathbf{q}=\mathbf{q}\cdot\mathbf{p}$
- $\mathbf{p}\cdot(\mathbf{q}+\mathbf{r})=\mathbf{p}\cdot\mathbf{q}+\mathbf{p}\cdot\mathbf{r}$
- $\mathbf{p}\cdot\mathbf{p}=\|\mathbf{p}\|_2^2$, a different way to write norm.
- If $\mathbf{p}\cdot\mathbf{q}=0$ and $\mathbf{p},\mathbf{q}\neq0$ then $\cos\theta=0$, then **p** and **q** are orthogonal.

Geometric Meanings

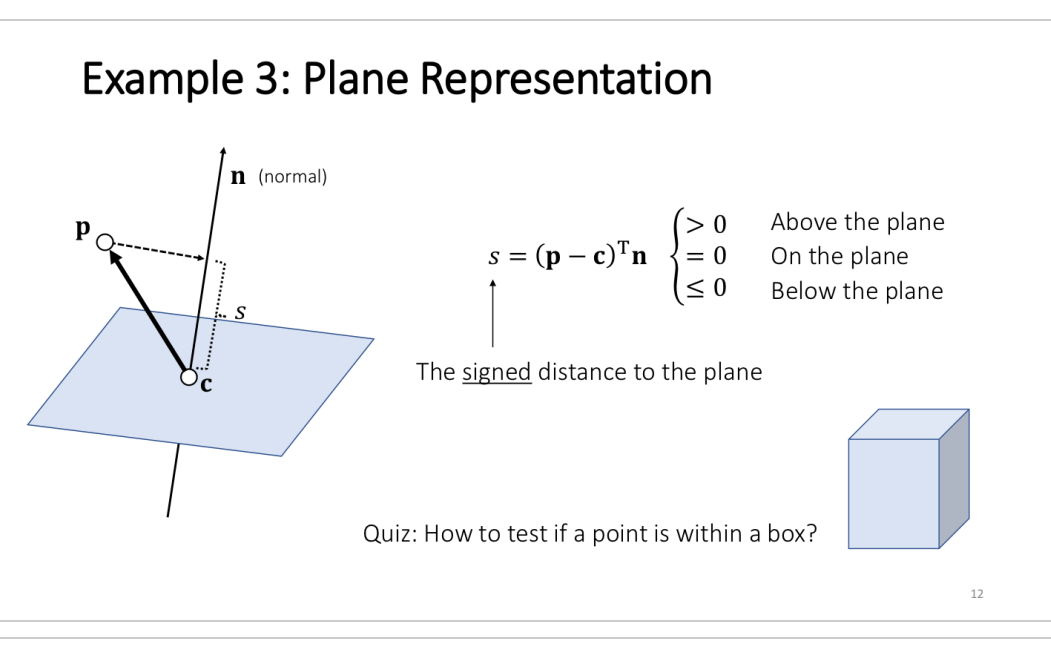
$\vec p=\begin{bmatrix}p_x\\p_y\\p_z\end{bmatrix}$ $\vec q=\begin{bmatrix}q_x\\q_y\\q_z\end{bmatrix}$

$\vec p^T=[p_x\ p_y\ p_z]$



Example 2: Particle-Line Projection

By definition,
$s=\|\mathbf{q}-\mathbf{o}\|\cos\theta$
So,
$s=\|\mathbf{q}-\mathbf{o}\|\,\|\mathbf{v}\|\cos\theta/\|\mathbf{v}\|$
$s=(\mathbf{q}-\mathbf{o})^\mathrm{T}\boxed{\mathbf{v}/\|\mathbf{v}\|}$ normalization
$s=(\mathbf{q}-\mathbf{o})^\mathrm{T}\bar{\mathbf{v}}$
And,
$\mathbf{s}=\mathbf{o}+s\bar{\mathbf{v}}$



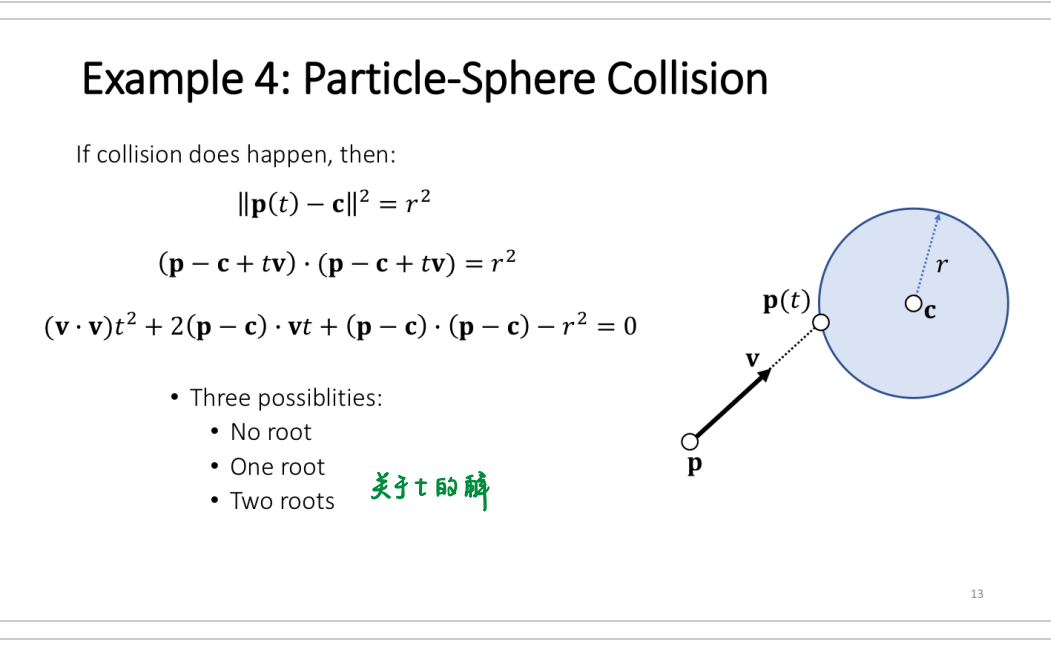
Example 3: Plane Representation

$s=(\mathbf{p}-\mathbf{c})^\mathrm{T}\mathbf{n}\begin{cases}>0 & \text{Above the plane}\\=0 & \text{On the plane}\\\le0 & \text{Below the plane}\end{cases}$

The signed distance to the plane

Quiz: How to test if a point is within a box?

可以利用这个距离来做检测，
比如：碰撞检测



Example 4: Particle-Sphere Collision

If collision does happen, then:

$\|\mathbf{p}(t)-\mathbf{c}\|^2=r^2$

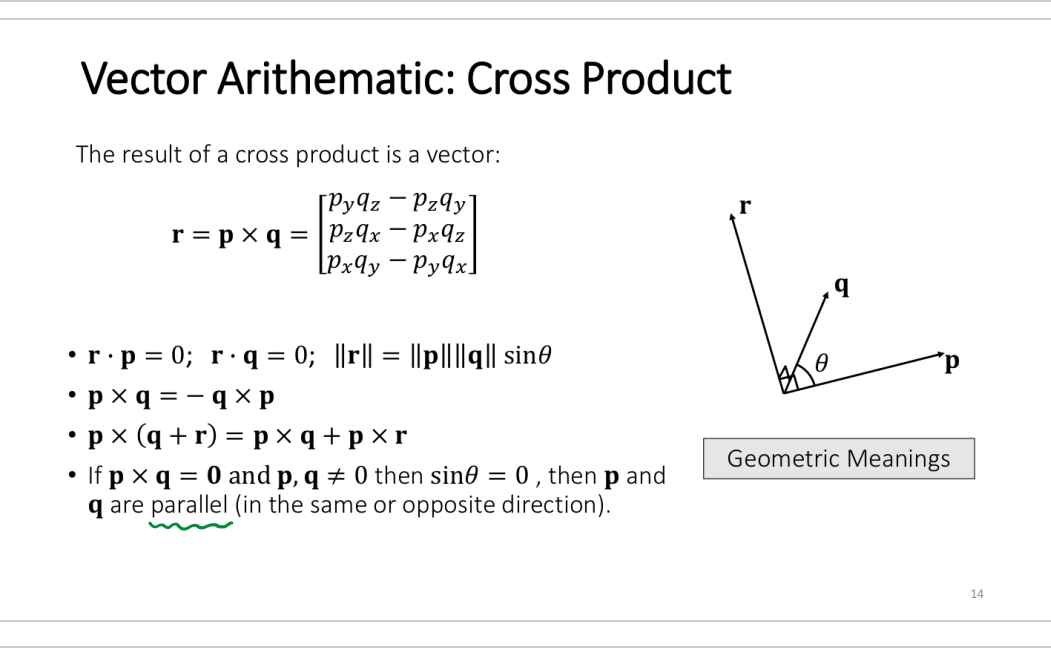
$(\mathbf{p}-\mathbf{c}+t\mathbf{v})\cdot(\mathbf{p}-\mathbf{c}+t\mathbf{v})=r^2$

$(\mathbf{v}\cdot\mathbf{v})t^2+2(\mathbf{p}-\mathbf{c})\cdot\mathbf{v}t+(\mathbf{p}-\mathbf{c})\cdot(\mathbf{p}-\mathbf{c})-r^2=0$

- Three possiblities:
  - No root
  - One root
  - Two roots 关于t的解

$p(t)=\vec p+t\vec v$

$(\vec p-\vec c+t\vec v)^2=\vec p\cdot\vec p+\vec c\cdot\vec c+t^2\vec v\cdot\vec v$
$-\vec p\cdot\vec c+\vec p\cdot t\vec v$
$-\vec c\cdot\vec p-\vec c\cdot t\vec v$
$+t\vec v\cdot\vec p-t\vec v\cdot\vec c$
$=\vec p^2+\vec c^2+\vec v^2\cdot t^2-2\vec p\cdot\vec c$
$+2t\vec v(\vec p-\vec c)$
$=(\vec v\cdot\vec v)t^2+2(\vec p-\vec c)\cdot\vec v t+(\vec p-\vec c)\cdot(\vec p-\vec c)$



Vector Arithematic: Cross Product

The result of a cross product is a vector:

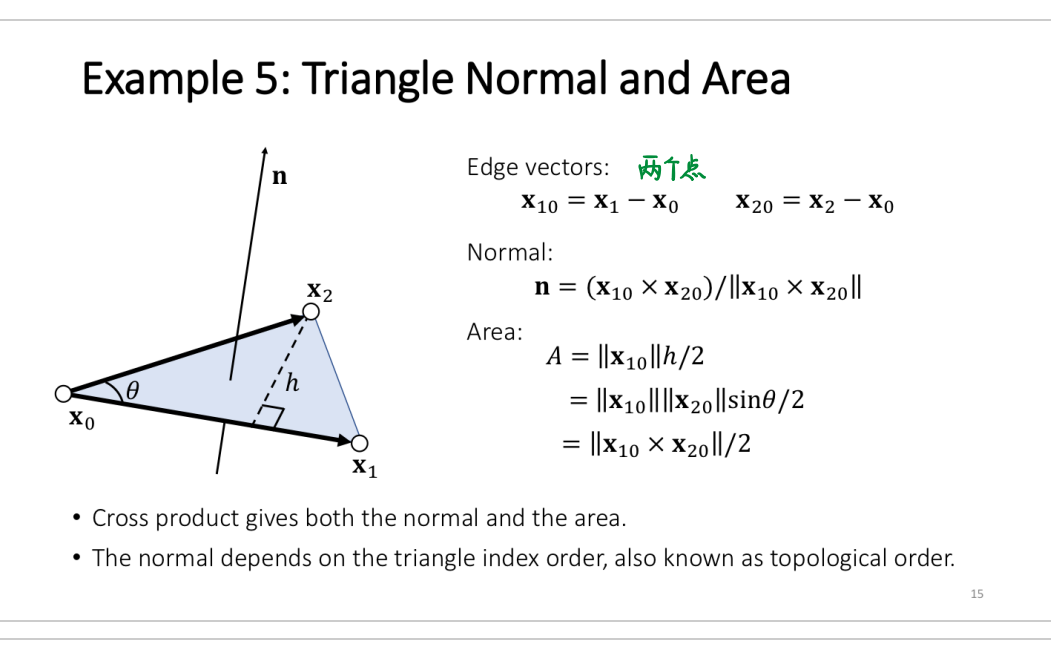
$\mathbf{r}=\mathbf{p}\times\mathbf{q}=\begin{bmatrix}p_yq_z-p_zq_y\\p_zq_x-p_xq_z\\p_xq_y-p_yq_x\end{bmatrix}$

- $\mathbf{r}\cdot\mathbf{p}=0$; $\mathbf{r}\cdot\mathbf{q}=0$; $\|\mathbf{r}\|=\|\mathbf{p}\|\|\mathbf{q}\|\sin\theta$
- $\mathbf{p}\times\mathbf{q}=-\mathbf{q}\times\mathbf{p}$
- $\mathbf{p}\times(\mathbf{q}+\mathbf{r})=\mathbf{p}\times\mathbf{q}+\mathbf{p}\times\mathbf{r}$
- If $\mathbf{p}\times\mathbf{q}=\mathbf{0}$ and $\mathbf{p},\mathbf{q}\neq0$ then $\sin\theta=0$, then **p** and **q** are parallel (in the same or opposite direction).

Geometric Meanings

$\vec p\times\vec q=\begin{vmatrix}\vec i&\vec j&\vec k\\p_x&p_y&p_z\\q_x&q_y&q_z\end{vmatrix}$ 右手定则？(from Adv Math II)

$=(p_yq_z-p_zq_y)\vec i+\underbrace{(p_zq_x-p_xq_z)\vec j}_{=-(p_xq_z-p_zq_x)\vec j}+(p_xq_y-p_yq_x)\vec k$



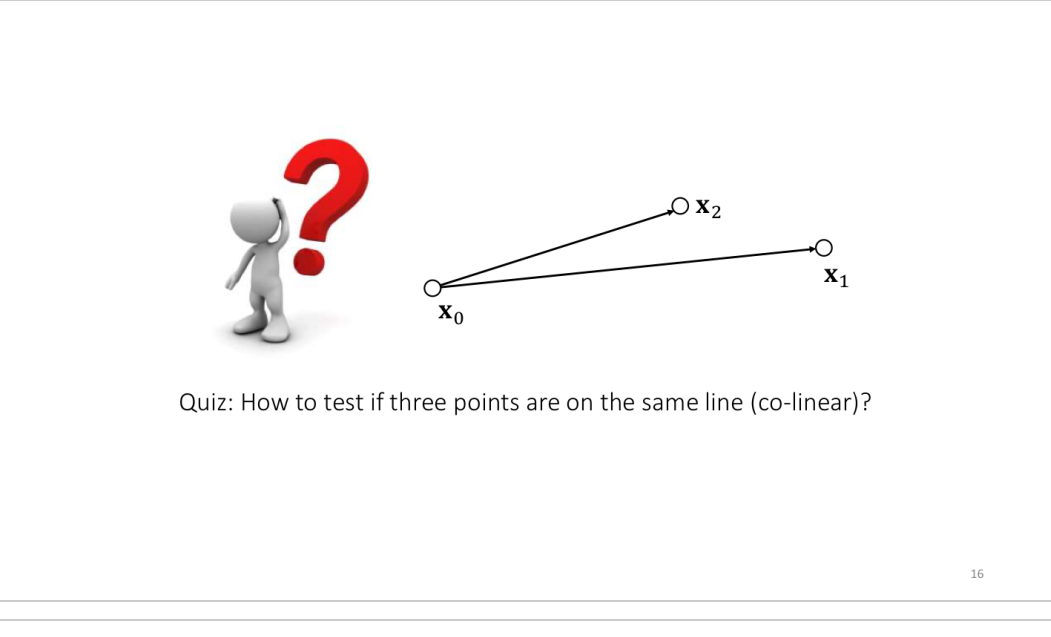
Example 5: Triangle Normal and Area

Edge vectors: 两个点
$\mathbf{x}_{10}=\mathbf{x}_1-\mathbf{x}_0$ $\mathbf{x}_{20}=\mathbf{x}_2-\mathbf{x}_0$

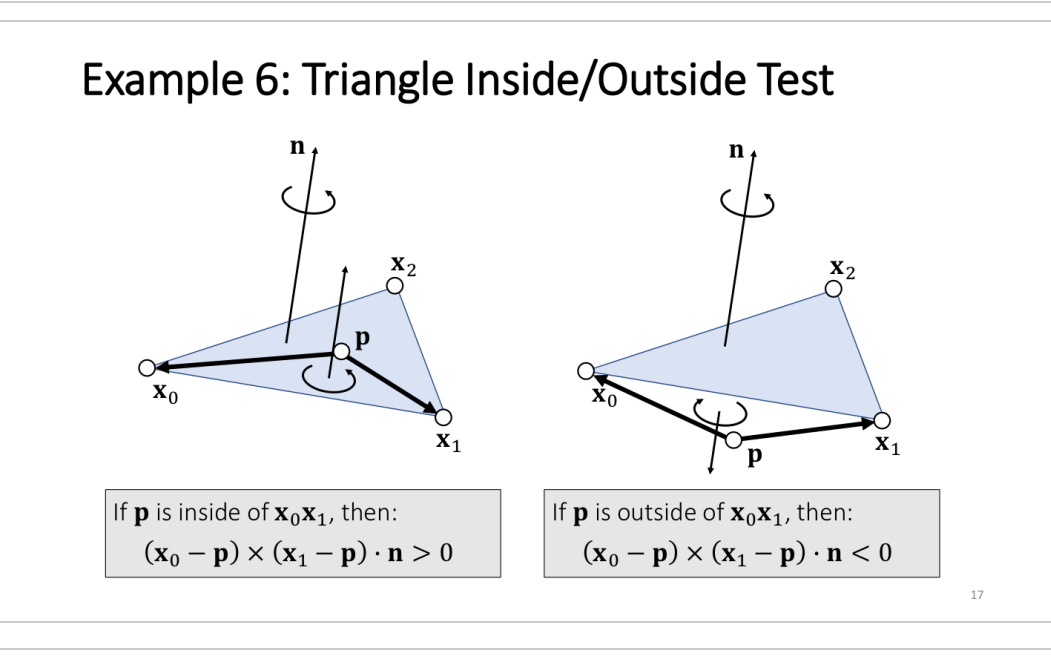
Normal:
$\mathbf{n}=(\mathbf{x}_{10}\times\mathbf{x}_{20})/\|\mathbf{x}_{10}\times\mathbf{x}_{20}\|$

Area:
$A=\|\mathbf{x}_{10}\|h/2$
$=\|\mathbf{x}_{10}\|\|\mathbf{x}_{20}\|\sin\theta/2$
$=\|\mathbf{x}_{10}\times\mathbf{x}_{20}\|/2$

- Cross product gives both the normal and the area.
- The normal depends on the triangle index order, also known as topological order.



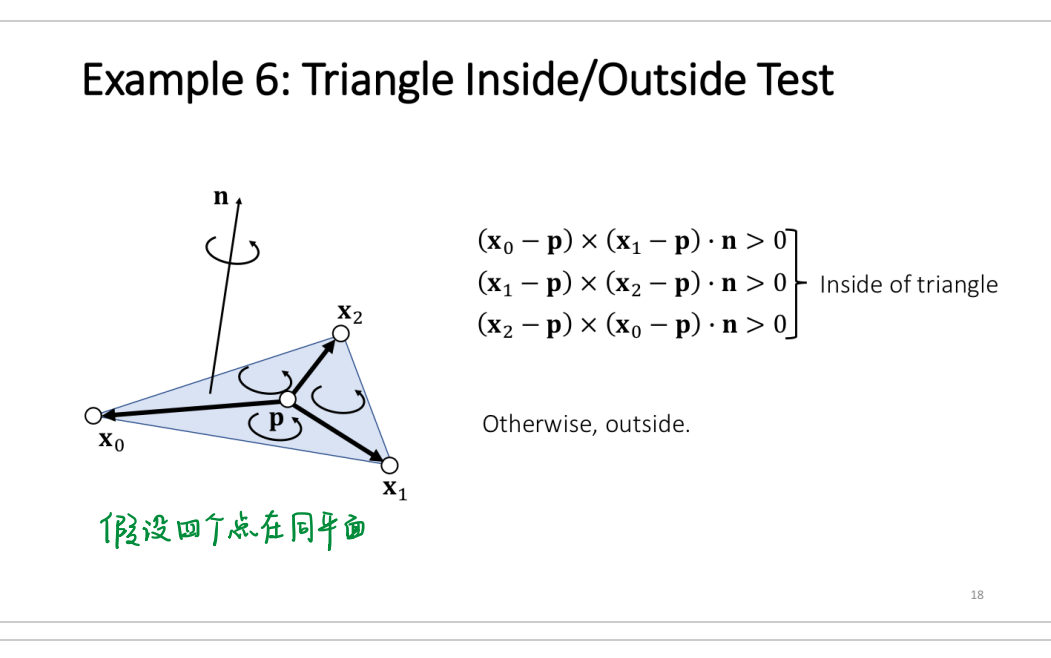
Quiz: How to test if three points are on the same line (co-linear)?



Example 6: Triangle Inside/Outside Test

If **p** is inside of $\mathbf{x}_0\mathbf{x}_1$, then:
$(\mathbf{x}_0-\mathbf{p})\times(\mathbf{x}_1-\mathbf{p})\cdot\mathbf{n}>0$

If **p** is outside of $\mathbf{x}_0\mathbf{x}_1$, then:
$(\mathbf{x}_0-\mathbf{p})\times(\mathbf{x}_1-\mathbf{p})\cdot\mathbf{n}<0$

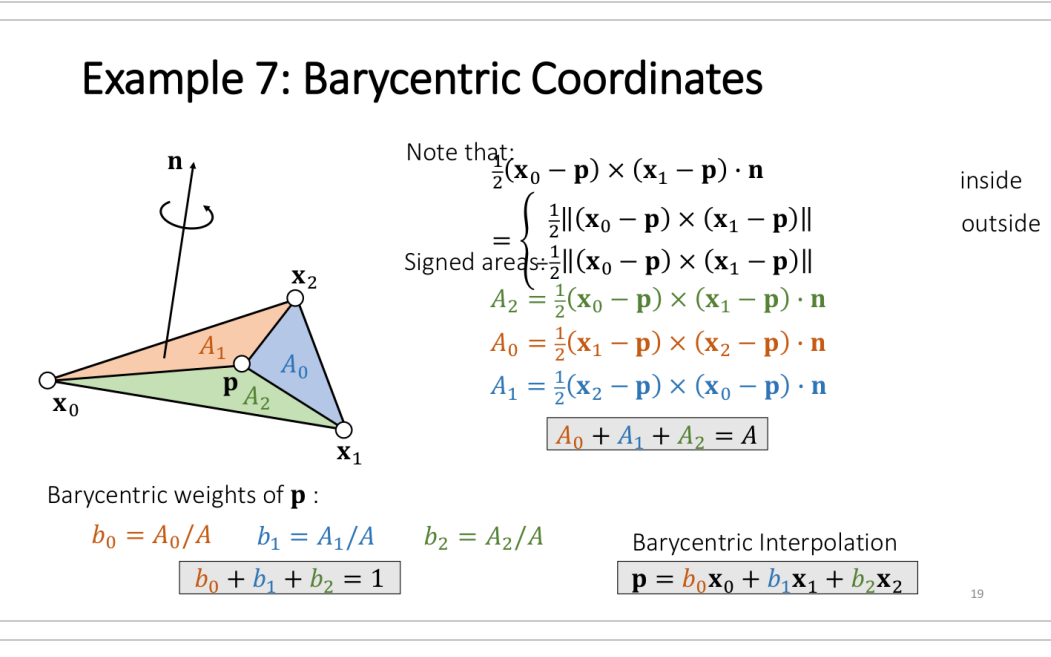


Example 6: Triangle Inside/Outside Test

$\left.\begin{aligned}(\mathbf{x}_0-\mathbf{p})\times(\mathbf{x}_1-\mathbf{p})\cdot\mathbf{n}>0\\(\mathbf{x}_1-\mathbf{p})\times(\mathbf{x}_2-\mathbf{p})\cdot\mathbf{n}>0\\(\mathbf{x}_2-\mathbf{p})\times(\mathbf{x}_0-\mathbf{p})\cdot\mathbf{n}>0\end{aligned}\right\}$ Inside of triangle

Otherwise, outside.

假设四个点在同平面



Example 7: Barycentric Coordinates

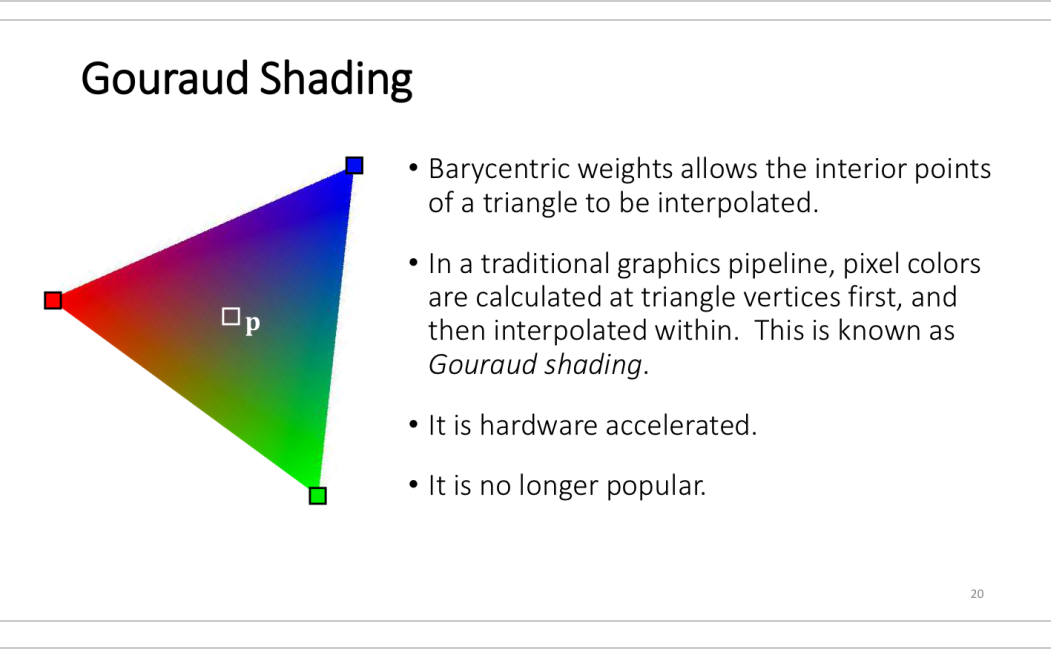
Note that: $\frac12(\mathbf{x}_0-\mathbf{p})\times(\mathbf{x}_1-\mathbf{p})\cdot\mathbf{n}=\begin{cases}\frac12\|(\mathbf{x}_0-\mathbf{p})\times(\mathbf{x}_1-\mathbf{p})\| & \text{inside}\\-\frac12\|(\mathbf{x}_0-\mathbf{p})\times(\mathbf{x}_1-\mathbf{p})\| & \text{outside}\end{cases}$

Signed areas:
$A_2=\frac12(\mathbf{x}_0-\mathbf{p})\times(\mathbf{x}_1-\mathbf{p})\cdot\mathbf{n}$
$A_0=\frac12(\mathbf{x}_1-\mathbf{p})\times(\mathbf{x}_2-\mathbf{p})\cdot\mathbf{n}$
$A_1=\frac12(\mathbf{x}_2-\mathbf{p})\times(\mathbf{x}_0-\mathbf{p})\cdot\mathbf{n}$
$A_0+A_1+A_2=A$

Barycentric weights of **p**:
$b_0=A_0/A$ $b_1=A_1/A$ $b_2=A_2/A$
$b_0+b_1+b_2=1$

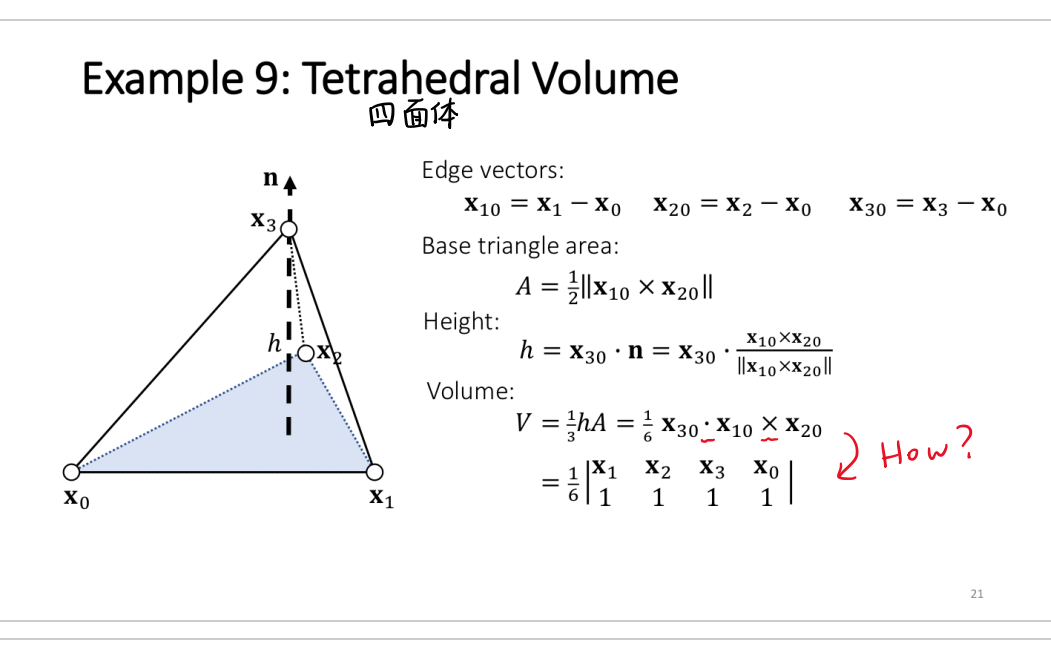
Barycentric Interpolation
$\mathbf{p}=b_0\mathbf{x}_0+b_1\mathbf{x}_1+b_2\mathbf{x}_2$

?错了
好像没有



Gouraud Shading

- Barycentric weights allows the interior points of a triangle to be interpolated.
- In a traditional graphics pipeline, pixel colors are calculated at triangle vertices first, and then interpolated within. This is known as *Gouraud shading*.
- It is hardware accelerated.
- It is no longer popular.



Example 9: Tetrahedral Volume

四面体

Edge vectors:
$\mathbf{x}_{10}=\mathbf{x}_1-\mathbf{x}_0$ $\mathbf{x}_{20}=\mathbf{x}_2-\mathbf{x}_0$ $\mathbf{x}_{30}=\mathbf{x}_3-\mathbf{x}_0$

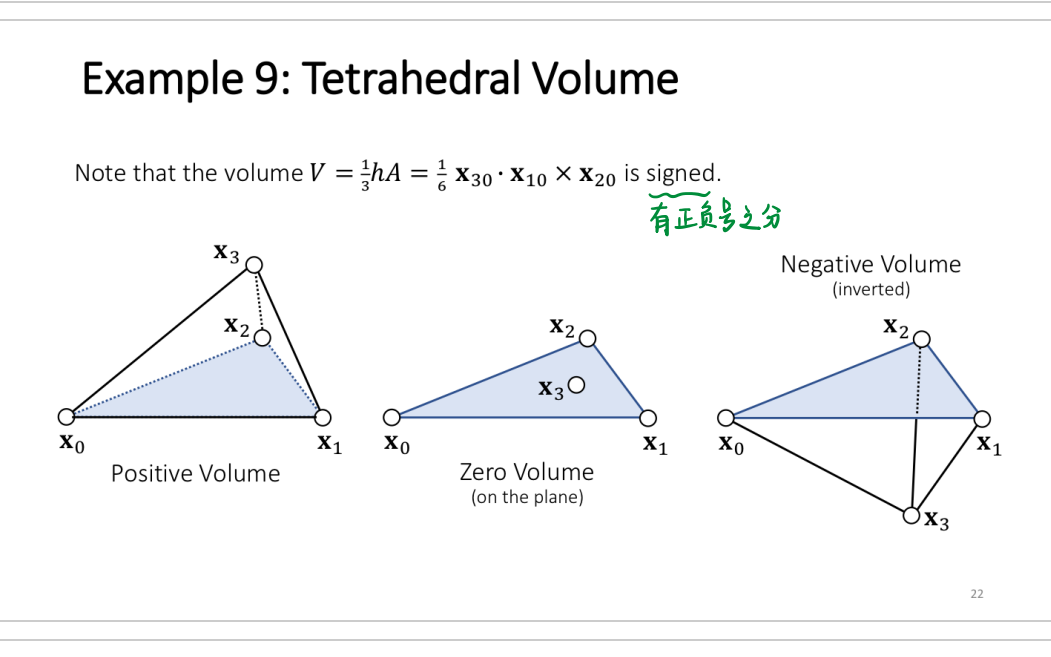
Base triangle area:
$A=\frac12\|\mathbf{x}_{10}\times\mathbf{x}_{20}\|$

Height:
$h=\mathbf{x}_{30}\cdot\mathbf{n}=\mathbf{x}_{30}\cdot\frac{\mathbf{x}_{10}\times\mathbf{x}_{20}}{\|\mathbf{x}_{10}\times\mathbf{x}_{20}\|}$

Volume:
$V=\frac13hA=\frac16\mathbf{x}_{30}\cdot\mathbf{x}_{10}\times\mathbf{x}_{20}$ How?
$=\frac16\begin{vmatrix}\mathbf{x}_1&\mathbf{x}_2&\mathbf{x}_3&\mathbf{x}_0\\1&1&1&1\end{vmatrix}$

$\vec x_{30}\cdot\vec n=h$

$\vec n$：单位法向量



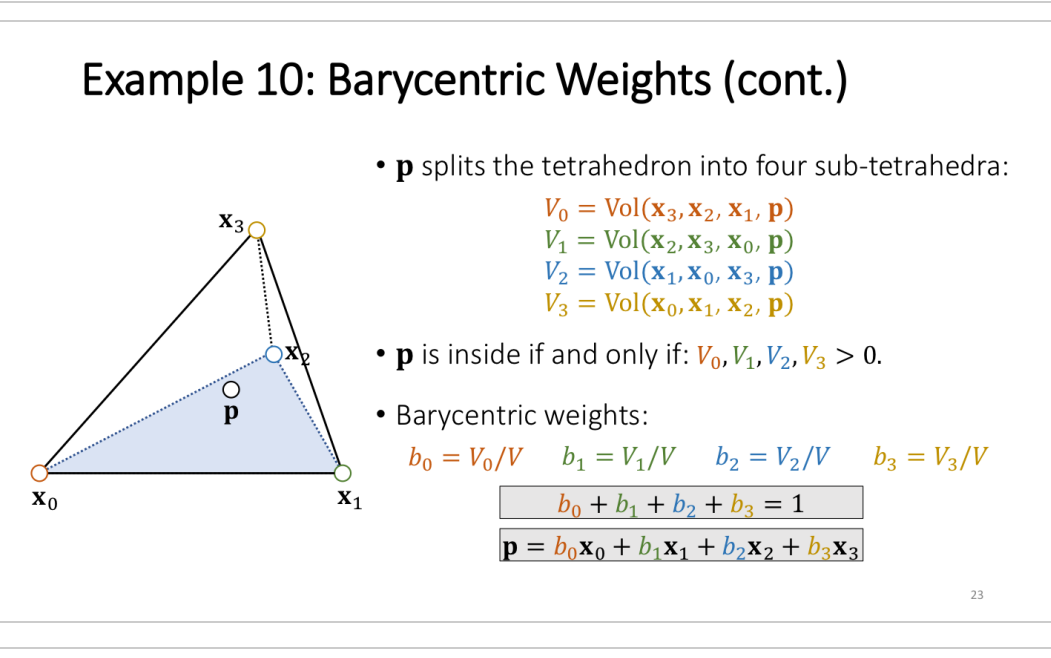
Example 9: Tetrahedral Volume

Note that the volume $V=\frac13hA=\frac16\mathbf{x}_{30}\cdot\mathbf{x}_{10}\times\mathbf{x}_{20}$ is signed. 有正负号之分

Positive Volume

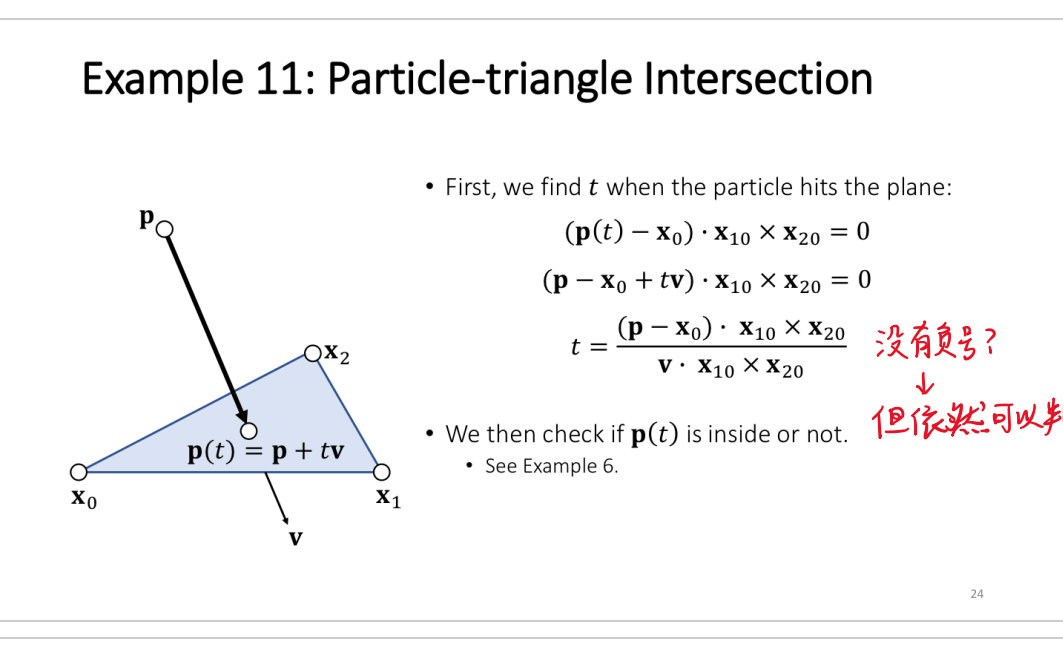
Zero Volume (on the plane)

Negative Volume (inverted)



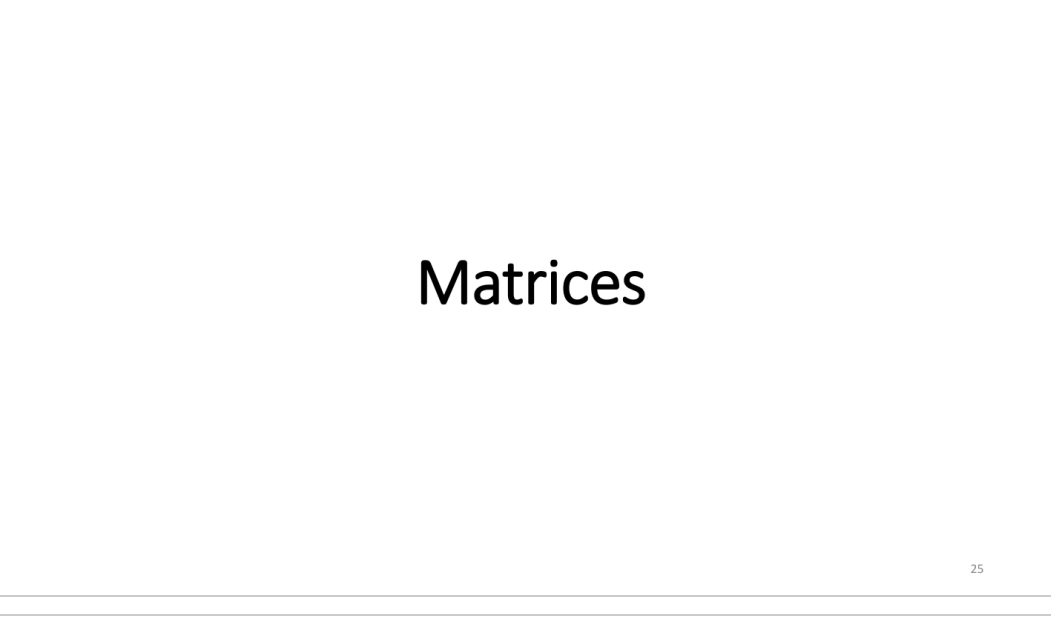
Example 10: Barycentric Weights (cont.)

- **p** splits the tetrahedron into four sub-tetrahedra:
  $V_0=\mathrm{Vol}(\mathbf{x}_3,\mathbf{x}_2,\mathbf{x}_1,\mathbf{p})$
  $V_1=\mathrm{Vol}(\mathbf{x}_2,\mathbf{x}_3,\mathbf{x}_0,\mathbf{p})$
  $V_2=\mathrm{Vol}(\mathbf{x}_1,\mathbf{x}_0,\mathbf{x}_3,\mathbf{p})$
  $V_3=\mathrm{Vol}(\mathbf{x}_0,\mathbf{x}_1,\mathbf{x}_2,\mathbf{p})$
- **p** is inside if and only if: $V_0,V_1,V_2,V_3>0$.
- Barycentric weights:
  $b_0=V_0/V$ $b_1=V_1/V$ $b_2=V_2/V$ $b_3=V_3/V$
  $b_0+b_1+b_2+b_3=1$
  $\mathbf{p}=b_0\mathbf{x}_0+b_1\mathbf{x}_1+b_2\mathbf{x}_2+b_3\mathbf{x}_3$

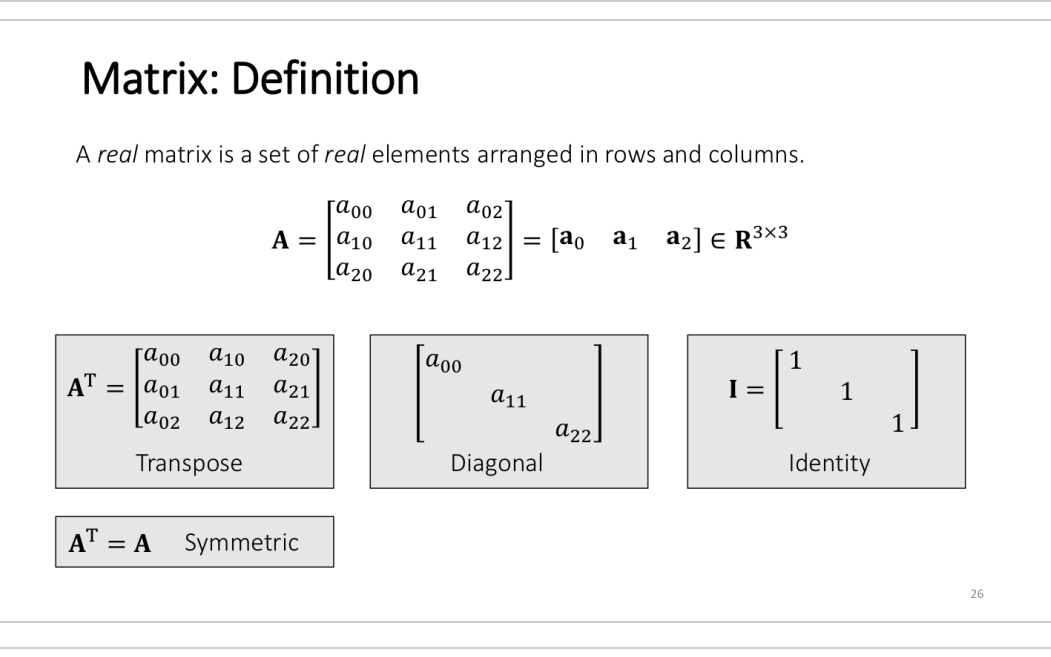


Example 11: Particle-triangle Intersection

- First, we find *t* when the particle hits the plane:
  $(\mathbf{p}(t)-\mathbf{x}_0)\cdot\mathbf{x}_{10}\times\mathbf{x}_{20}=0$
  $(\mathbf{p}-\mathbf{x}_0+t\mathbf{v})\cdot\mathbf{x}_{10}\times\mathbf{x}_{20}=0$
  $t=\frac{(\mathbf{p}-\mathbf{x}_0)\cdot\mathbf{x}_{10}\times\mathbf{x}_{20}}{\mathbf{v}\cdot\mathbf{x}_{10}\times\mathbf{x}_{20}}$ 没有负号？ ↓ 但依然可以判断
- We then check if $\mathbf{p}(t)$ is inside or not.
  - See Example 6.



Matrices



Matrix: Definition

A *real* matrix is a set of *real* elements arranged in rows and columns.

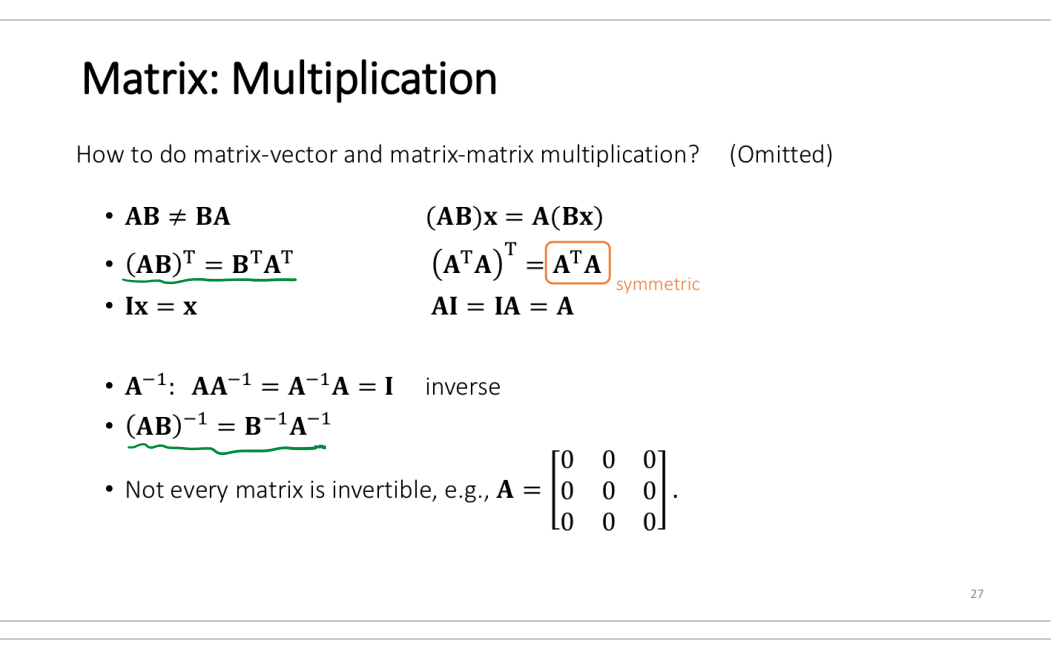
$\mathbf{A}=\begin{bmatrix}a_{00}&a_{01}&a_{02}\\a_{10}&a_{11}&a_{12}\\a_{20}&a_{21}&a_{22}\end{bmatrix}=[\mathbf{a}_0\ \ \mathbf{a}_1\ \ \mathbf{a}_2]\in\mathbf{R}^{3\times3}$

$\mathbf{A}^\mathrm{T}=\begin{bmatrix}a_{00}&a_{10}&a_{20}\\a_{01}&a_{11}&a_{21}\\a_{02}&a_{12}&a_{22}\end{bmatrix}$ Transpose

$\begin{bmatrix}a_{00}&&\\&a_{11}&\\&&a_{22}\end{bmatrix}$ Diagonal

$\mathbf{I}=\begin{bmatrix}1&&\\&1&\\&&1\end{bmatrix}$ Identity

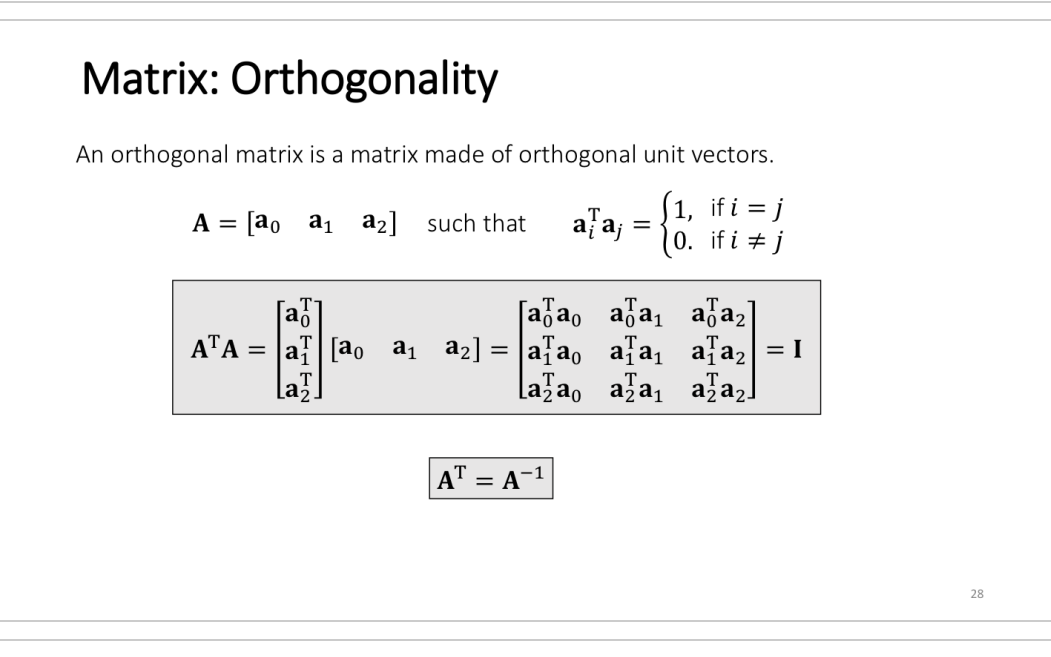
$\mathbf{A}^\mathrm{T}=\mathbf{A}$ Symmetric



Matrix: Multiplication

How to do matrix-vector and matrix-matrix multiplication? (Omitted)

- $\mathbf{AB}\neq\mathbf{BA}$ $(\mathbf{AB})\mathbf{x}=\mathbf{A}(\mathbf{Bx})$
- $(\mathbf{AB})^\mathrm{T}=\mathbf{B}^\mathrm{T}\mathbf{A}^\mathrm{T}$ $(\mathbf{A}^\mathrm{T}\mathbf{A})^\mathrm{T}=\boxed{\mathbf{A}^\mathrm{T}\mathbf{A}}$ symmetric
- $\mathbf{Ix}=\mathbf{x}$ $\mathbf{AI}=\mathbf{IA}=\mathbf{A}$
- $\mathbf{A}^{-1}$: $\mathbf{AA}^{-1}=\mathbf{A}^{-1}\mathbf{A}=\mathbf{I}$ inverse
- $(\mathbf{AB})^{-1}=\mathbf{B}^{-1}\mathbf{A}^{-1}$
- Not every matrix is invertible, e.g., $\mathbf{A}=\begin{bmatrix}0&0&0\\0&0&0\\0&0&0\end{bmatrix}$.



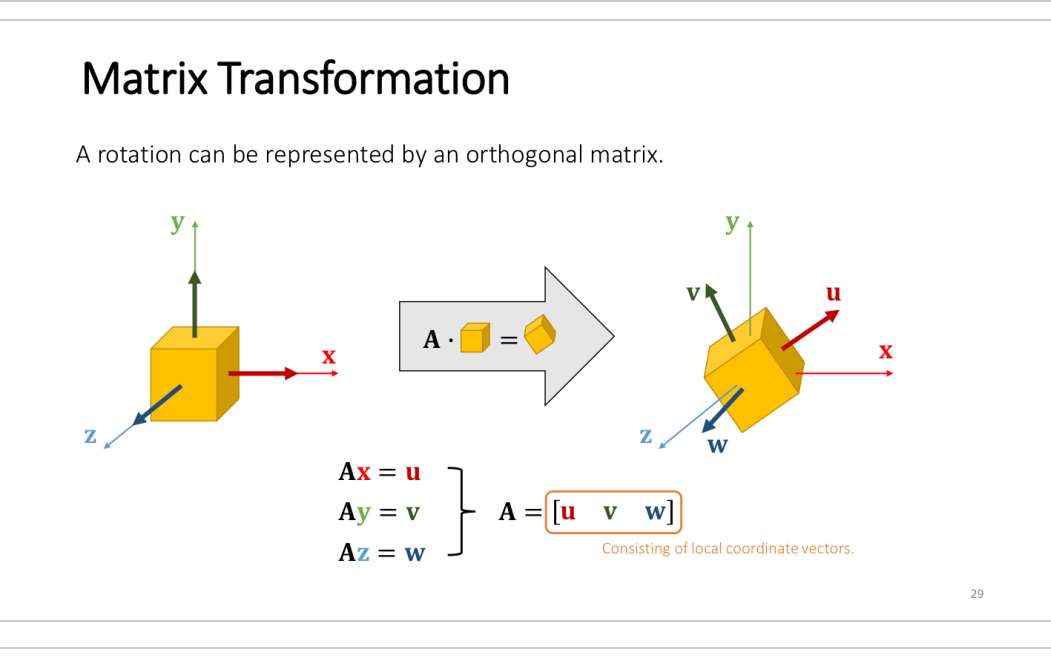
Matrix: Orthogonality

An orthogonal matrix is a matrix made of orthogonal unit vectors.

$\mathbf{A}=[\mathbf{a}_0\ \ \mathbf{a}_1\ \ \mathbf{a}_2]$ such that $\mathbf{a}_i^\mathrm{T}\mathbf{a}_j=\begin{cases}1, & \text{if } i=j\\0. & \text{if } i\neq j\end{cases}$

$\mathbf{A}^\mathrm{T}\mathbf{A}=\begin{bmatrix}\mathbf{a}_0^\mathrm{T}\\\mathbf{a}_1^\mathrm{T}\\\mathbf{a}_2^\mathrm{T}\end{bmatrix}[\mathbf{a}_0\ \ \mathbf{a}_1\ \ \mathbf{a}_2]=\begin{bmatrix}\mathbf{a}_0^\mathrm{T}\mathbf{a}_0&\mathbf{a}_0^\mathrm{T}\mathbf{a}_1&\mathbf{a}_0^\mathrm{T}\mathbf{a}_2\\\mathbf{a}_1^\mathrm{T}\mathbf{a}_0&\mathbf{a}_1^\mathrm{T}\mathbf{a}_1&\mathbf{a}_1^\mathrm{T}\mathbf{a}_2\\\mathbf{a}_2^\mathrm{T}\mathbf{a}_0&\mathbf{a}_2^\mathrm{T}\mathbf{a}_1&\mathbf{a}_2^\mathrm{T}\mathbf{a}_2\end{bmatrix}=\mathbf{I}$

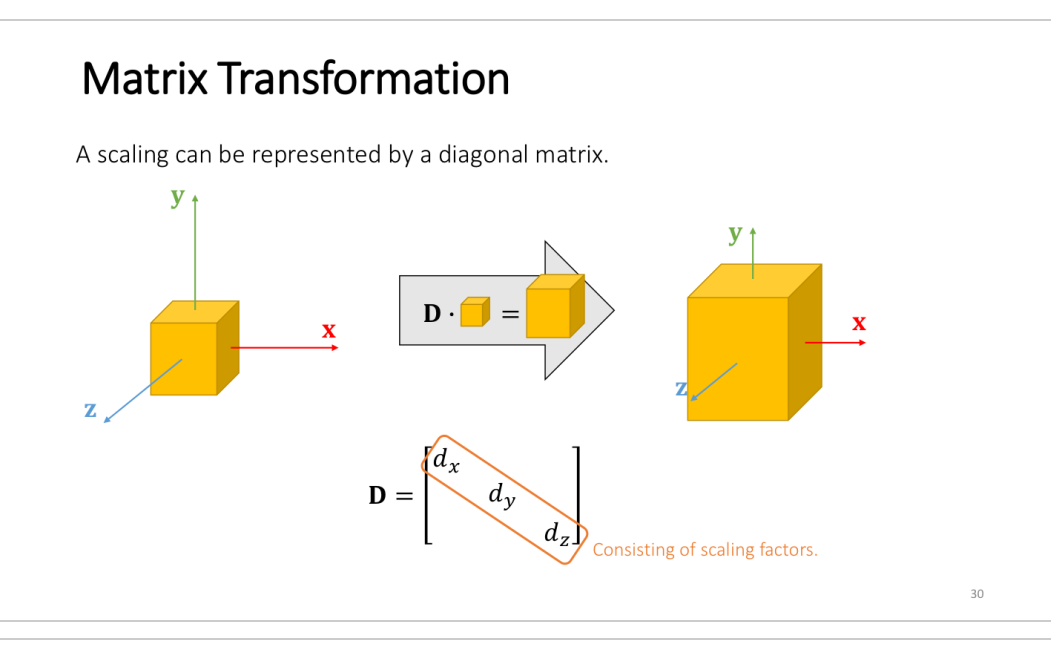
$\mathbf{A}^\mathrm{T}=\mathbf{A}^{-1}$



Matrix Transformation

A rotation can be represented by an orthogonal matrix.

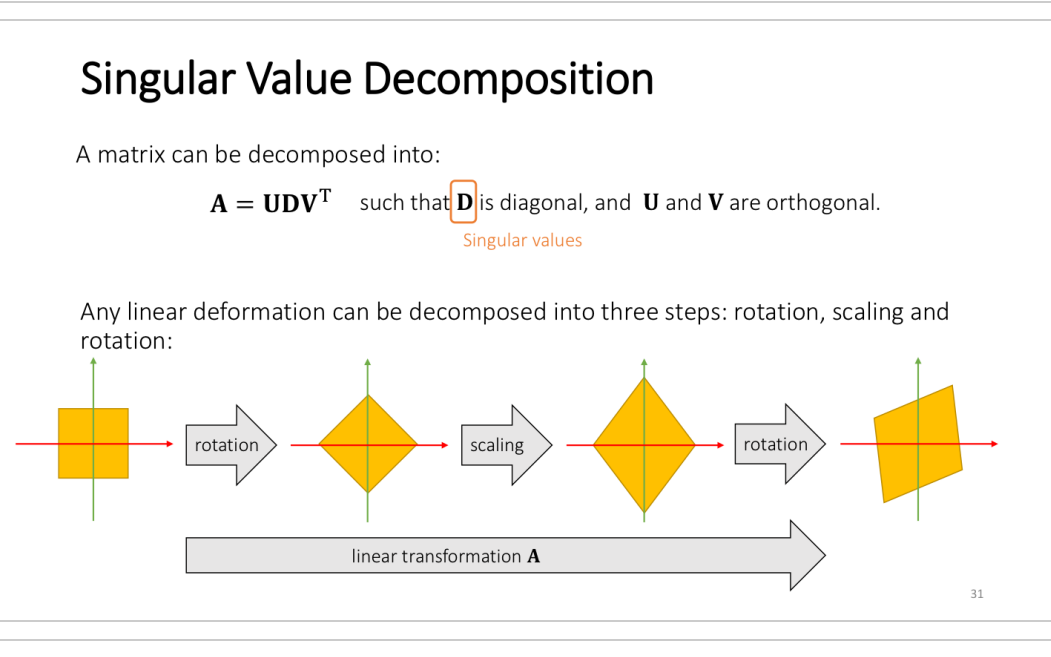
$\left.\begin{aligned}\mathbf{Ax}=\mathbf{u}\\\mathbf{Ay}=\mathbf{v}\\\mathbf{Az}=\mathbf{w}\end{aligned}\right\}\ \mathbf{A}=\boxed{[\mathbf{u}\ \ \mathbf{v}\ \ \mathbf{w}]}$ Consisting of local coordinate vectors.



Matrix Transformation

A scaling can be represented by a diagonal matrix.

$\mathbf{D}=\begin{bmatrix}d_x&&\\&d_y&\\&&d_z\end{bmatrix}$ Consisting of scaling factors.

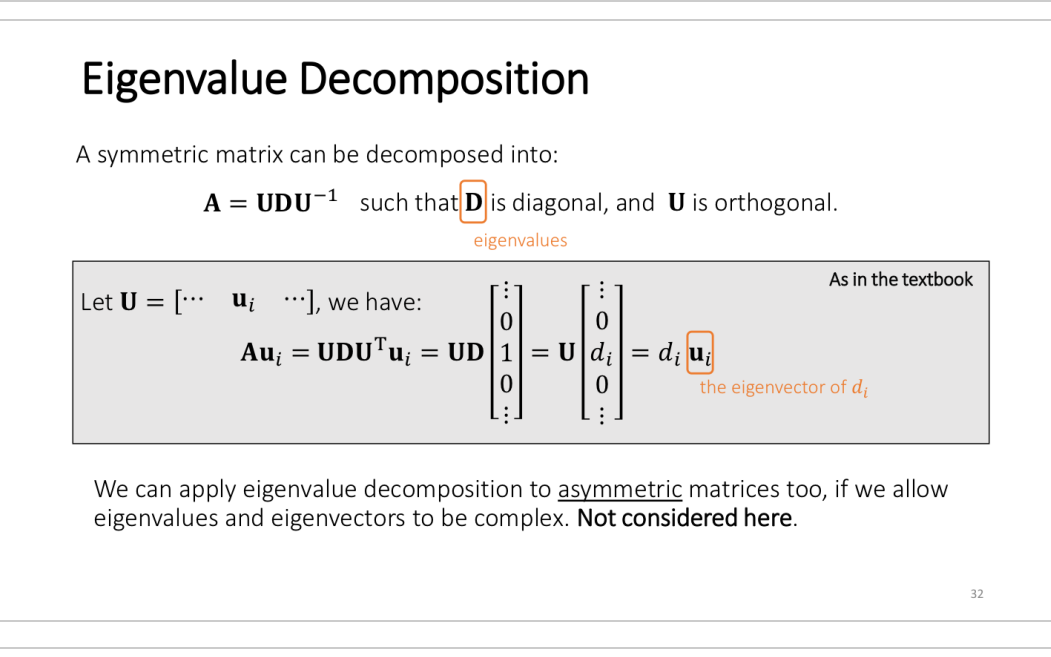


Singular Value Decomposition

A matrix can be decomposed into:

$\mathbf{A}=\mathbf{UDV}^\mathrm{T}$ such that $\boxed{\mathbf{D}}$ is diagonal, and **U** and **V** are orthogonal.
Singular values

Any linear deformation can be decomposed into three steps: rotation, scaling and rotation:



Eigenvalue Decomposition

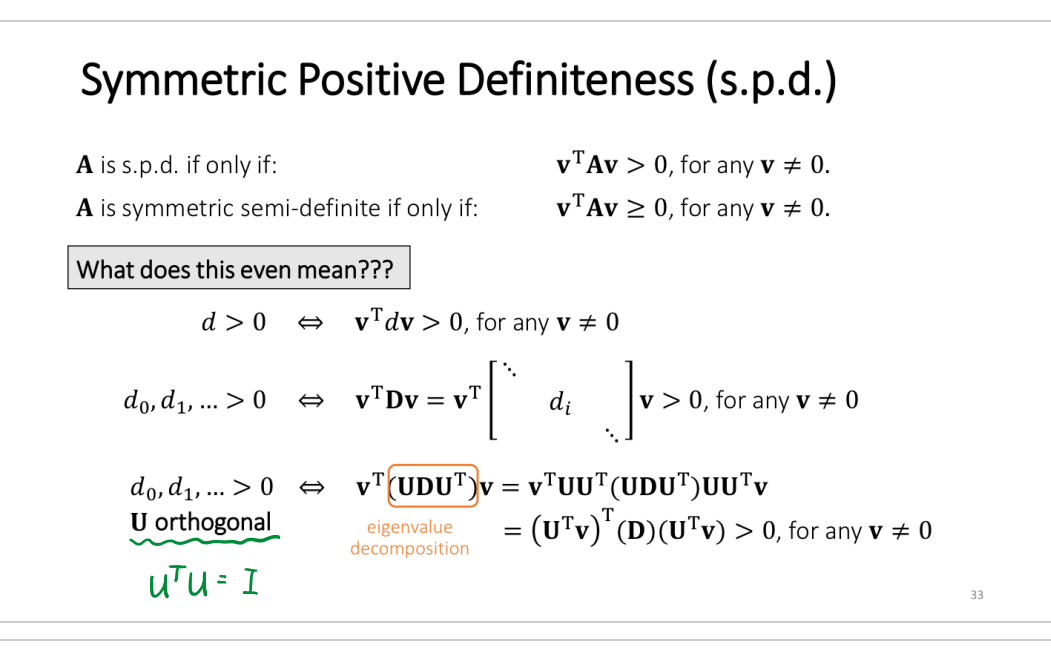
A symmetric matrix can be decomposed into:

$\mathbf{A}=\mathbf{UDU}^{-1}$ such that $\boxed{\mathbf{D}}$ is diagonal, and **U** is orthogonal.
eigenvalues

As in the textbook

Let $\mathbf{U}=[\cdots\ \ \mathbf{u}_i\ \ \cdots]$, we have:
$\mathbf{Au}_i=\mathbf{UDU}^\mathrm{T}\mathbf{u}_i=\mathbf{UD}\begin{bmatrix}\vdots\\0\\1\\0\\\vdots\end{bmatrix}=\mathbf{U}\begin{bmatrix}\vdots\\0\\d_i\\0\\\vdots\end{bmatrix}=d_i\boxed{\mathbf{u}_i}$ the eigenvector of d_i

We can apply eigenvalue decomposition to asymmetric matrices too, if we allow eigenvalues and eigenvectors to be complex. Not considered here.



Symmetric Positive Definiteness (s.p.d.)

A is s.p.d. if only if: $\mathbf{v}^\mathrm{T}\mathbf{Av}>0$, for any $\mathbf{v}\neq\mathbf{0}$.

A is symmetric semi-definite if only if: $\mathbf{v}^\mathrm{T}\mathbf{Av}\ge0$, for any $\mathbf{v}\neq\mathbf{0}$.

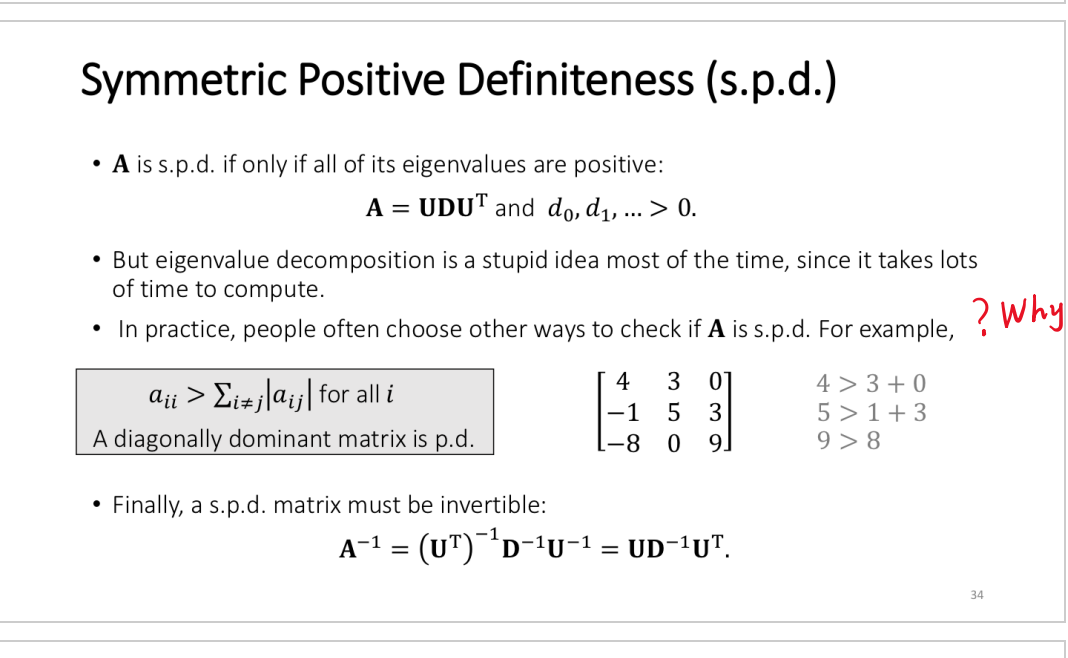
What does this even mean???

$d>0 \Leftrightarrow \mathbf{v}^\mathrm{T}d\mathbf{v}>0$, for any $\mathbf{v}\neq0$

$d_0,d_1,\ldots>0 \Leftrightarrow \mathbf{v}^\mathrm{T}\mathbf{Dv}=\mathbf{v}^\mathrm{T}\begin{bmatrix}\ddots&&\\&d_i&\\&&\ddots\end{bmatrix}\mathbf{v}>0$, for any $\mathbf{v}\neq0$

$d_0,d_1,\ldots>0 \Leftrightarrow \mathbf{v}^\mathrm{T}\boxed{\mathbf{UDU}^\mathrm{T}}\mathbf{v}=\mathbf{v}^\mathrm{T}\mathbf{UU}^\mathrm{T}(\mathbf{UDU}^\mathrm{T})\mathbf{UU}^\mathrm{T}\mathbf{v}$
U orthogonal eigenvalue decomposition $=(\mathbf{U}^\mathrm{T}\mathbf{v})^\mathrm{T}(\mathbf{D})(\mathbf{U}^\mathrm{T}\mathbf{v})>0$, for any $\mathbf{v}\neq0$

$U^TU=I$



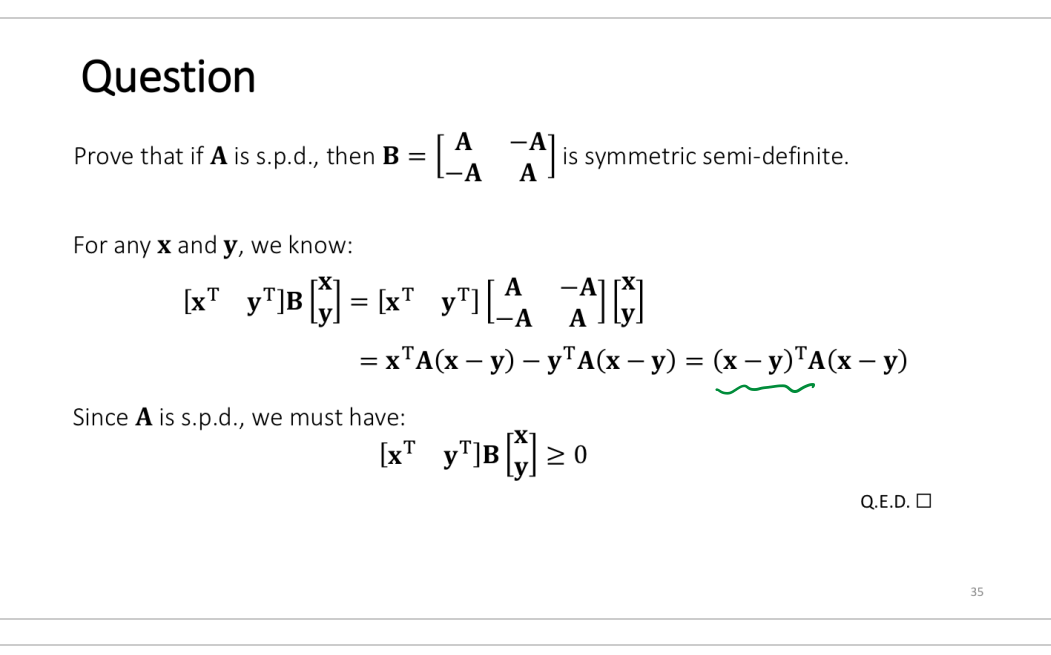
Symmetric Positive Definiteness (s.p.d.)

- **A** is s.p.d. if only if all of its eigenvalues are positive:
  $\mathbf{A}=\mathbf{UDU}^\mathrm{T}$ and $d_0,d_1,\ldots>0$.
- But eigenvalue decomposition is a stupid idea most of the time, since it takes lots of time to compute.
- In practice, people often choose other ways to check if **A** is s.p.d. For example, ? Why

$a_{ii}>\sum_{i\neq j}|a_{ij}|$ for all i
A diagonally dominant matrix is p.d.

$\begin{bmatrix}4&3&0\\-1&5&3\\-8&0&9\end{bmatrix}$ $4>3+0$ $5>1+3$ $9>8$

- Finally, a s.p.d. matrix must be invertible:
  $\mathbf{A}^{-1}=(\mathbf{U}^\mathrm{T})^{-1}\mathbf{D}^{-1}\mathbf{U}^{-1}=\mathbf{UD}^{-1}\mathbf{U}^\mathrm{T}$.



Question

Prove that if **A** is s.p.d., then $\mathbf{B}=\begin{bmatrix}\mathbf{A}&-\mathbf{A}\\-\mathbf{A}&\mathbf{A}\end{bmatrix}$ is symmetric semi-definite.

For any **x** and **y**, we know:

$[\mathbf{x}^\mathrm{T}\ \ \mathbf{y}^\mathrm{T}]\mathbf{B}\begin{bmatrix}\mathbf{x}\\\mathbf{y}\end{bmatrix}=[\mathbf{x}^\mathrm{T}\ \ \mathbf{y}^\mathrm{T}]\begin{bmatrix}\mathbf{A}&-\mathbf{A}\\-\mathbf{A}&\mathbf{A}\end{bmatrix}\begin{bmatrix}\mathbf{x}\\\mathbf{y}\end{bmatrix}$
$=\mathbf{x}^\mathrm{T}\mathbf{A}(\mathbf{x}-\mathbf{y})-\mathbf{y}^\mathrm{T}\mathbf{A}(\mathbf{x}-\mathbf{y})=(\mathbf{x}-\mathbf{y})^\mathrm{T}\mathbf{A}(\mathbf{x}-\mathbf{y})$

Since **A** is s.p.d., we must have:

$[\mathbf{x}^\mathrm{T}\ \ \mathbf{y}^\mathrm{T}]\mathbf{B}\begin{bmatrix}\mathbf{x}\\\mathbf{y}\end{bmatrix}\ge0$

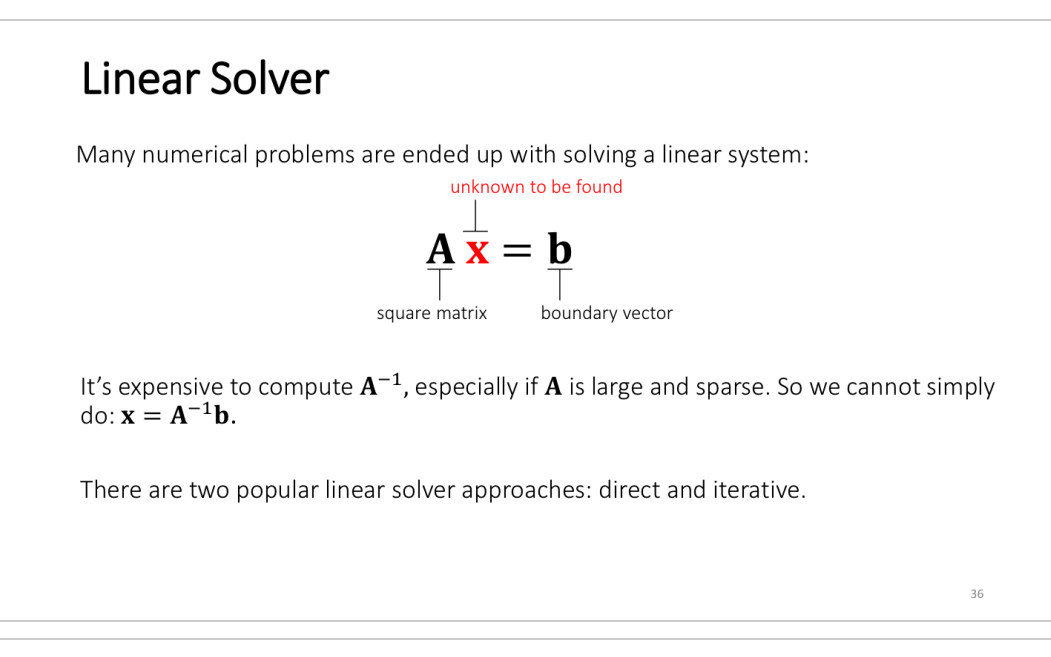
Q.E.D. □

$[x^T\ y^T]\begin{bmatrix}A&-A\\-A&A\end{bmatrix}\begin{bmatrix}x\\y\end{bmatrix}$
$=[x^TA-y^TA\ \ -x^TA+y^TA]\begin{bmatrix}x\\y\end{bmatrix}$
$=x^TAx-y^TAx\ \ -x^TAy+y^TAy$
$=x^TA(x-y)-y^TA(x-y)$
$=(x^T-y^T)A(x-y)$

$x:\begin{pmatrix}2&3&4\\5&6&7\end{pmatrix}$ $y:\begin{pmatrix}1&2&3\\4&5&6\end{pmatrix}$

$x-y=\begin{pmatrix}1&1&1\\1&1&1\end{pmatrix}$ $(x-y)^T=\begin{pmatrix}1&1\\1&1\\1&1\end{pmatrix}$

$x^T=\begin{pmatrix}2&5\\3&6\\4&7\end{pmatrix}$ $y^T=\begin{pmatrix}1&4\\2&5\\3&6\end{pmatrix}$ $x^T-y^T=\begin{pmatrix}1&1\\1&1\\1&1\end{pmatrix}$



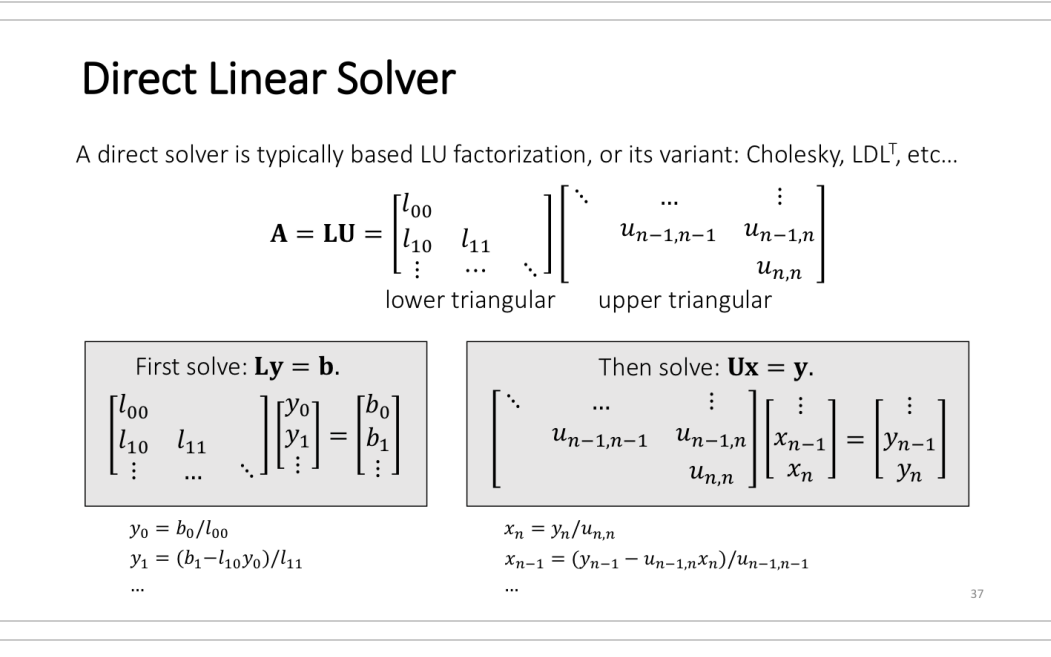
Linear Solver

Many numerical problems are ended up with solving a linear system:

$\underset{\text{square matrix}}{\mathbf{A}}\overset{\text{unknown to be found}}{\mathbf{x}}=\underset{\text{boundary vector}}{\mathbf{b}}$

It's expensive to compute $\mathbf{A}^{-1}$, especially if **A** is large and sparse. So we cannot simply do: $\mathbf{x}=\mathbf{A}^{-1}\mathbf{b}$.

There are two popular linear solver approaches: direct and iterative.



Direct Linear Solver

A direct solver is typically based LU factorization, or its variant: Cholesky, LDL^T, etc…

$\mathbf{A}=\mathbf{LU}=\underset{\text{lower triangular}}{\begin{bmatrix}l_{00}&&\\l_{10}&l_{11}&\\\vdots&\cdots&\ddots\end{bmatrix}}\underset{\text{upper triangular}}{\begin{bmatrix}\ddots&\cdots&\vdots\\&u_{n-1,n-1}&u_{n-1,n}\\&&u_{n,n}\end{bmatrix}}$

First solve: $\mathbf{Ly}=\mathbf{b}$.
$\begin{bmatrix}l_{00}&&\\l_{10}&l_{11}&\\\vdots&\cdots&\ddots\end{bmatrix}\begin{bmatrix}y_0\\y_1\\\vdots\end{bmatrix}=\begin{bmatrix}b_0\\b_1\\\vdots\end{bmatrix}$

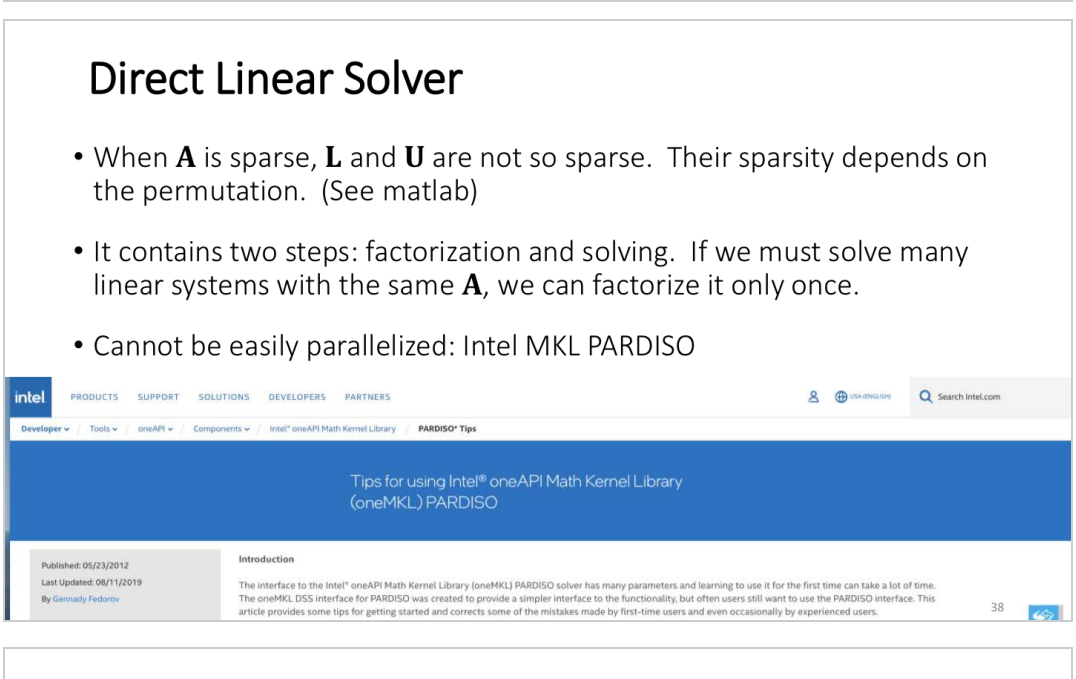
$y_0=b_0/l_{00}$
$y_1=(b_1-l_{10}y_0)/l_{11}$
…

Then solve: $\mathbf{Ux}=\mathbf{y}$.
$\begin{bmatrix}\ddots&\cdots&\vdots\\&u_{n-1,n-1}&u_{n-1,n}\\&&u_{n,n}\end{bmatrix}\begin{bmatrix}\vdots\\x_{n-1}\\x_n\end{bmatrix}=\begin{bmatrix}\vdots\\y_{n-1}\\y_n\end{bmatrix}$

$x_n=y_n/u_{n,n}$
$x_{n-1}=(y_{n-1}-u_{n-1,n}x_n)/u_{n-1,n-1}$
…

① factorization

② solving



Direct Linear Solver

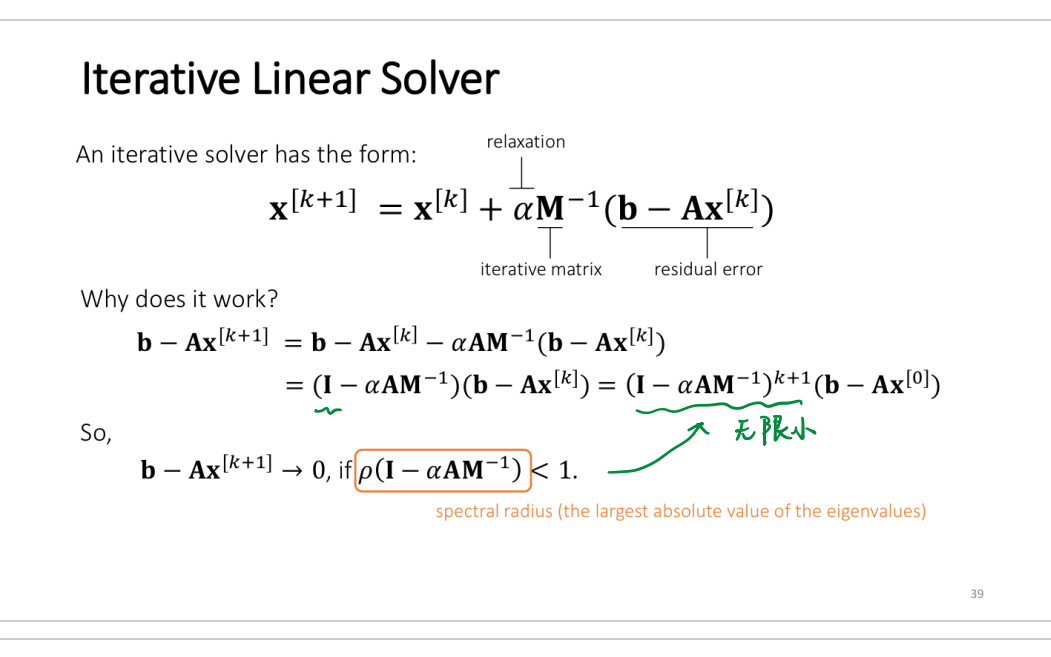
- When **A** is sparse, **L** and **U** are not so sparse. Their sparsity depends on the permutation. (See matlab)
- It contains two steps: factorization and solving. If we must solve many linear systems with the same **A**, we can factorize it only once.
- Cannot be easily parallelized: Intel MKL PARDISO

Tips for using Intel® oneAPI Math Kernel Library (oneMKL) PARDISO

Published: 05/23/2012
Last Updated: 08/11/2019

Introduction

The interface to the Intel® oneAPI Math Kernel Library (oneMKL) PARDISO solver has many parameters and learning to use it for the first time can take a lot of time. The oneMKL DSS interface for PARDISO was created to provide a simpler interface to the functionality, but often users still want to use the PARDISO interface. This article provides some tips for getting started and corrects some of the mistakes made by first-time users and even occasionally by experienced users.



Iterative Linear Solver

An iterative solver has the form:

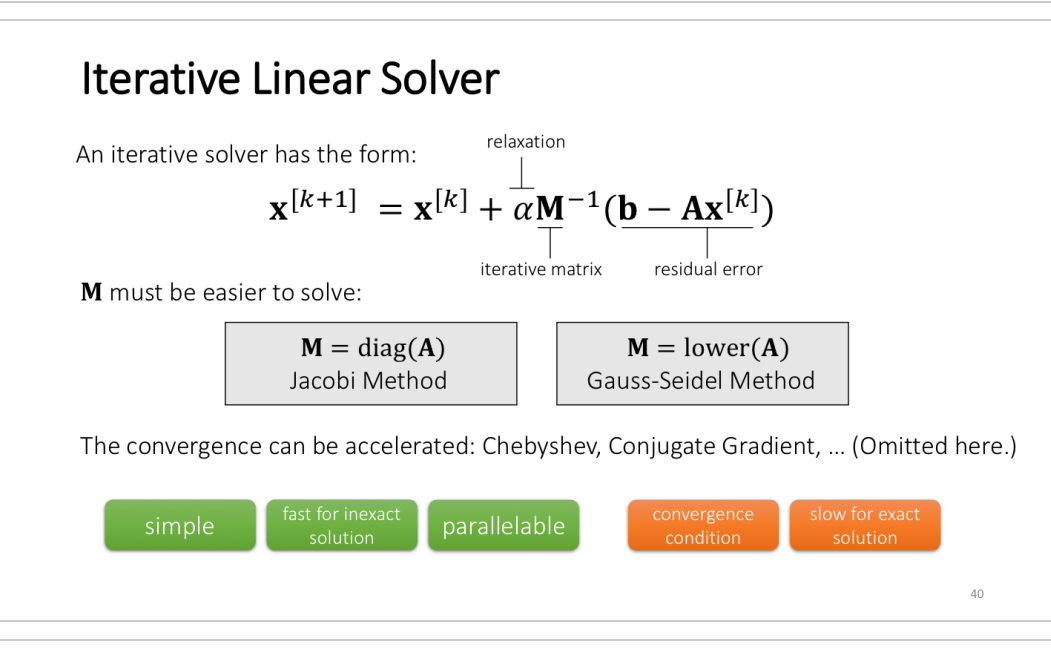
$\mathbf{x}^{[k+1]}=\mathbf{x}^{[k]}+\overset{\text{relaxation}}{\alpha}\underset{\text{iterative matrix}}{\mathbf{M}^{-1}}\underbrace{(\mathbf{b}-\mathbf{Ax}^{[k]})}_{\text{residual error}}$

Why does it work?

$\mathbf{b}-\mathbf{Ax}^{[k+1]}=\mathbf{b}-\mathbf{Ax}^{[k]}-\alpha\mathbf{AM}^{-1}(\mathbf{b}-\mathbf{Ax}^{[k]})$
$=(\mathbf{I}-\alpha\mathbf{AM}^{-1})(\mathbf{b}-\mathbf{Ax}^{[k]})=(\mathbf{I}-\alpha\mathbf{AM}^{-1})^{k+1}(\mathbf{b}-\mathbf{Ax}^{[0]})$ 无限小

So,

$\mathbf{b}-\mathbf{Ax}^{[k+1]}\to0$, if $\boxed{\rho(\mathbf{I}-\alpha\mathbf{AM}^{-1})}<1$.
spectral radius (the largest absolute value of the eigenvalues)



Iterative Linear Solver

An iterative solver has the form:

$\mathbf{x}^{[k+1]}=\mathbf{x}^{[k]}+\overset{\text{relaxation}}{\alpha}\underset{\text{iterative matrix}}{\mathbf{M}^{-1}}\underbrace{(\mathbf{b}-\mathbf{Ax}^{[k]})}_{\text{residual error}}$

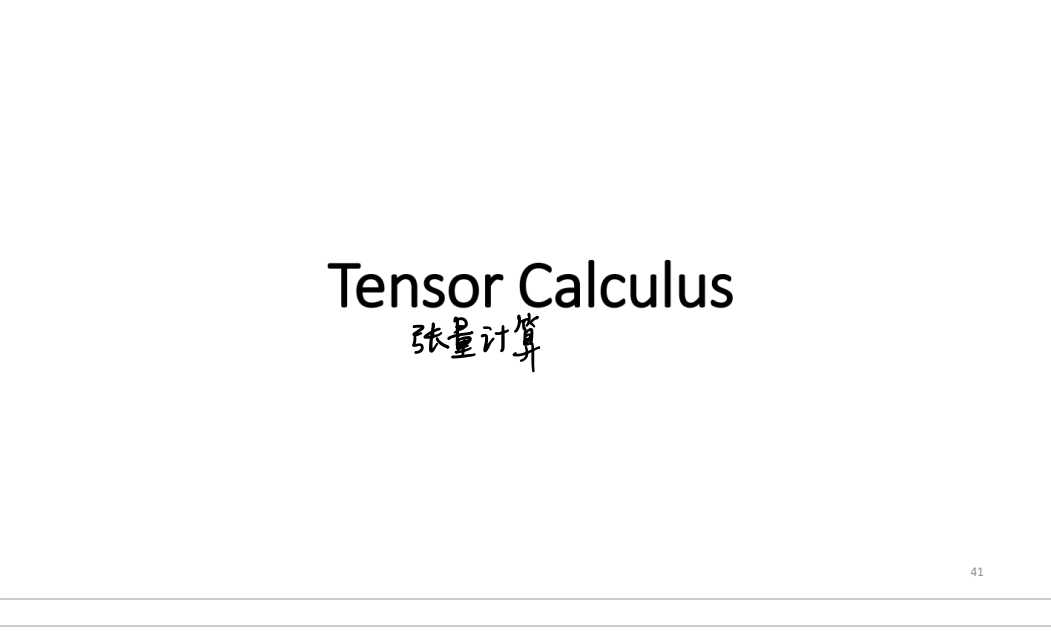
M must be easier to solve:

$\mathbf{M}=\mathrm{diag}(\mathbf{A})$ Jacobi Method

$\mathbf{M}=\mathrm{lower}(\mathbf{A})$ Gauss-Seidel Method

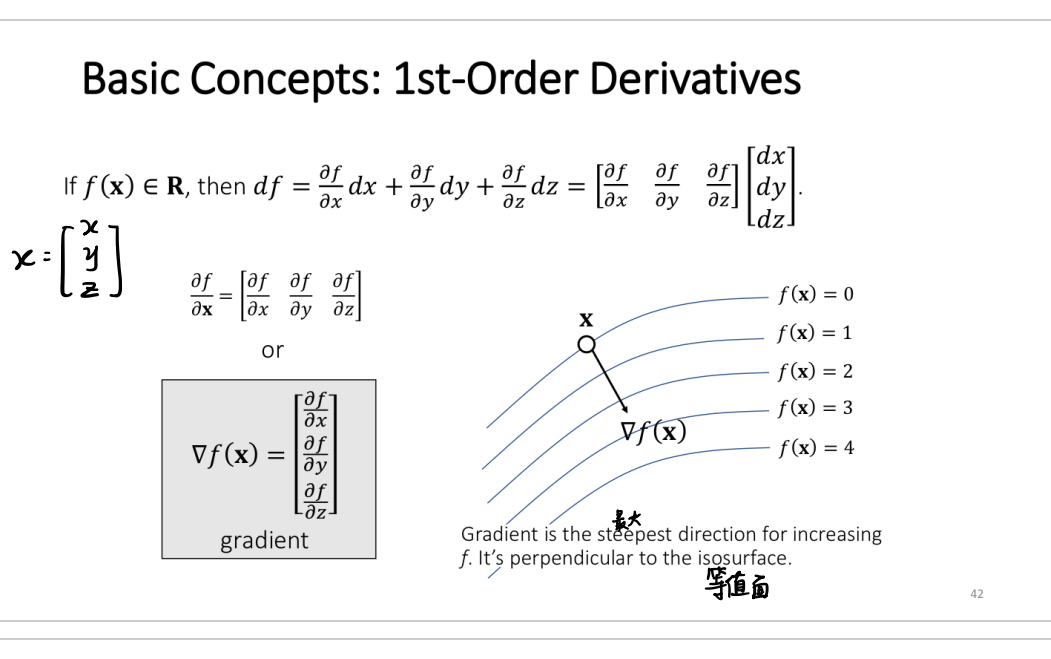
The convergence can be accelerated: Chebyshev, Conjugate Gradient, … (Omitted here.)

simple
fast for inexact solution
parallelable
convergence condition
slow for exact solution



Tensor Calculus

张量计算



Basic Concepts: 1st-Order Derivatives

If $f(\mathbf{x})\in\mathbf{R}$, then $df=\frac{\partial f}{\partial x}dx+\frac{\partial f}{\partial y}dy+\frac{\partial f}{\partial z}dz=\begin{bmatrix}\frac{\partial f}{\partial x}&\frac{\partial f}{\partial y}&\frac{\partial f}{\partial z}\end{bmatrix}\begin{bmatrix}dx\\dy\\dz\end{bmatrix}$.

$x=\begin{bmatrix}x\\y\\z\end{bmatrix}$

$\frac{\partial f}{\partial\mathbf{x}}=\begin{bmatrix}\frac{\partial f}{\partial x}&\frac{\partial f}{\partial y}&\frac{\partial f}{\partial z}\end{bmatrix}$

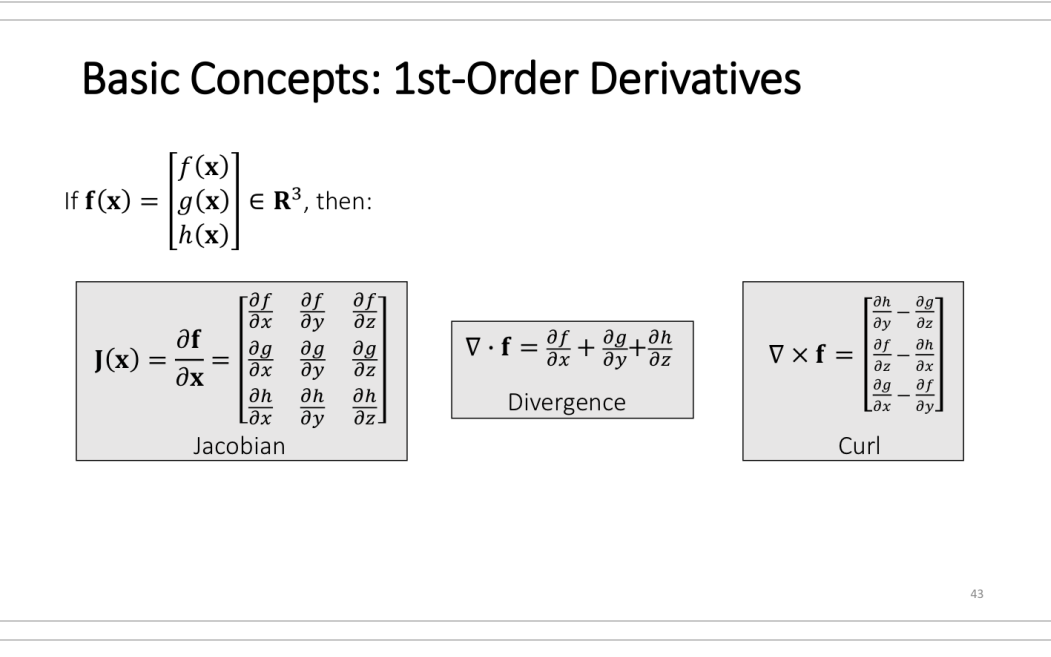
or

$\nabla f(\mathbf{x})=\begin{bmatrix}\frac{\partial f}{\partial x}\\\frac{\partial f}{\partial y}\\\frac{\partial f}{\partial z}\end{bmatrix}$ gradient

Gradient is the steepest direction for increasing *f*. It's perpendicular to the isosurface.

最大

等值面



Basic Concepts: 1st-Order Derivatives

If $\mathbf{f}(\mathbf{x})=\begin{bmatrix}f(\mathbf{x})\\g(\mathbf{x})\\h(\mathbf{x})\end{bmatrix}\in\mathbf{R}^3$, then:

$\mathbf{J}(\mathbf{x})=\frac{\partial\mathbf{f}}{\partial\mathbf{x}}=\begin{bmatrix}\frac{\partial f}{\partial x}&\frac{\partial f}{\partial y}&\frac{\partial f}{\partial z}\\\frac{\partial g}{\partial x}&\frac{\partial g}{\partial y}&\frac{\partial g}{\partial z}\\\frac{\partial h}{\partial x}&\frac{\partial h}{\partial y}&\frac{\partial h}{\partial z}\end{bmatrix}$ Jacobian

$\nabla\cdot\mathbf{f}=\frac{\partial f}{\partial x}+\frac{\partial g}{\partial y}+\frac{\partial h}{\partial z}$ Divergence

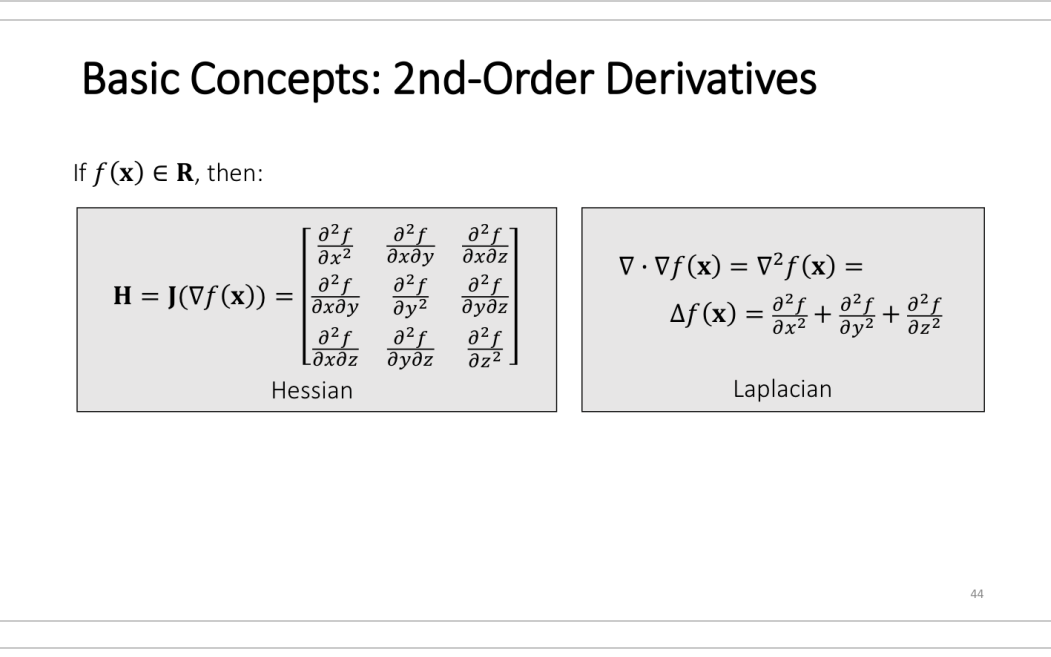
$\nabla\times\mathbf{f}=\begin{bmatrix}\frac{\partial h}{\partial y}-\frac{\partial g}{\partial z}\\\frac{\partial f}{\partial z}-\frac{\partial h}{\partial x}\\\frac{\partial g}{\partial x}-\frac{\partial f}{\partial y}\end{bmatrix}$ Curl

Curl:

$\nabla=\vec i\frac{\partial}{\partial x}+\vec j\frac{\partial}{\partial y}+\vec k\frac{\partial}{\partial z}$

$\nabla\cdot f=\vec i\frac{\partial f}{\partial x}+\vec j\frac{\partial f}{\partial y}+\vec k\frac{\partial f}{\partial z}$
$=\frac{\partial f}{\partial x}\vec i+\frac{\partial f}{\partial y}\vec j+\frac{\partial f}{\partial z}\vec k$

$\nabla\times F=\begin{vmatrix}\vec i&\vec j&\vec k\\\frac{\partial}{\partial x}&\frac{\partial}{\partial y}&\frac{\partial}{\partial z}\\f&g&h\end{vmatrix}$
$=(\frac{\partial h}{\partial y}-\frac{\partial g}{\partial z})\vec i+(\frac{\partial f}{\partial z}-\frac{\partial h}{\partial x})\vec j+(\frac{\partial g}{\partial x}-\frac{\partial f}{\partial y})\vec k$



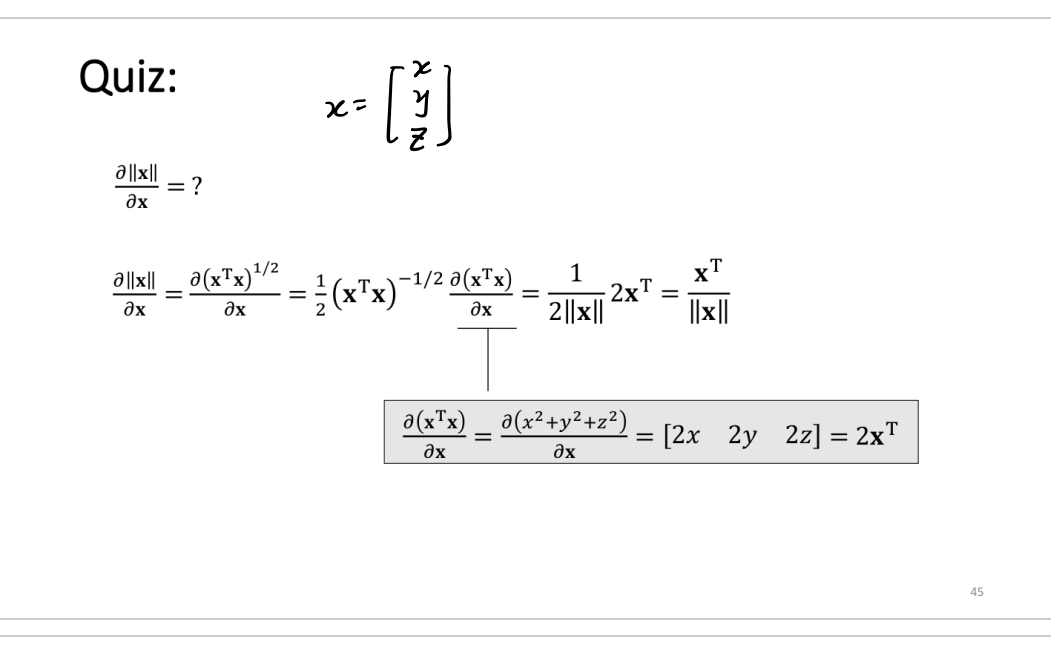
Basic Concepts: 2nd-Order Derivatives

If $f(\mathbf{x})\in\mathbf{R}$, then:

$\mathbf{H}=\mathbf{J}(\nabla f(\mathbf{x}))=\begin{bmatrix}\frac{\partial^2f}{\partial x^2}&\frac{\partial^2f}{\partial x\partial y}&\frac{\partial^2f}{\partial x\partial z}\\\frac{\partial^2f}{\partial x\partial y}&\frac{\partial^2f}{\partial y^2}&\frac{\partial^2f}{\partial y\partial z}\\\frac{\partial^2f}{\partial x\partial z}&\frac{\partial^2f}{\partial y\partial z}&\frac{\partial^2f}{\partial z^2}\end{bmatrix}$ Hessian

$\nabla\cdot\nabla f(\mathbf{x})=\nabla^2f(\mathbf{x})=\Delta f(\mathbf{x})=\frac{\partial^2f}{\partial x^2}+\frac{\partial^2f}{\partial y^2}+\frac{\partial^2f}{\partial z^2}$ Laplacian

- Hessian contains more information than Laplacian.
- For a smooth, multivariable function that returns a scalar, the Hessian matrix contains all possible second partial derivatives.
- The trace of the Hessian (the sum of the diagonal elements) is the Laplace operator.



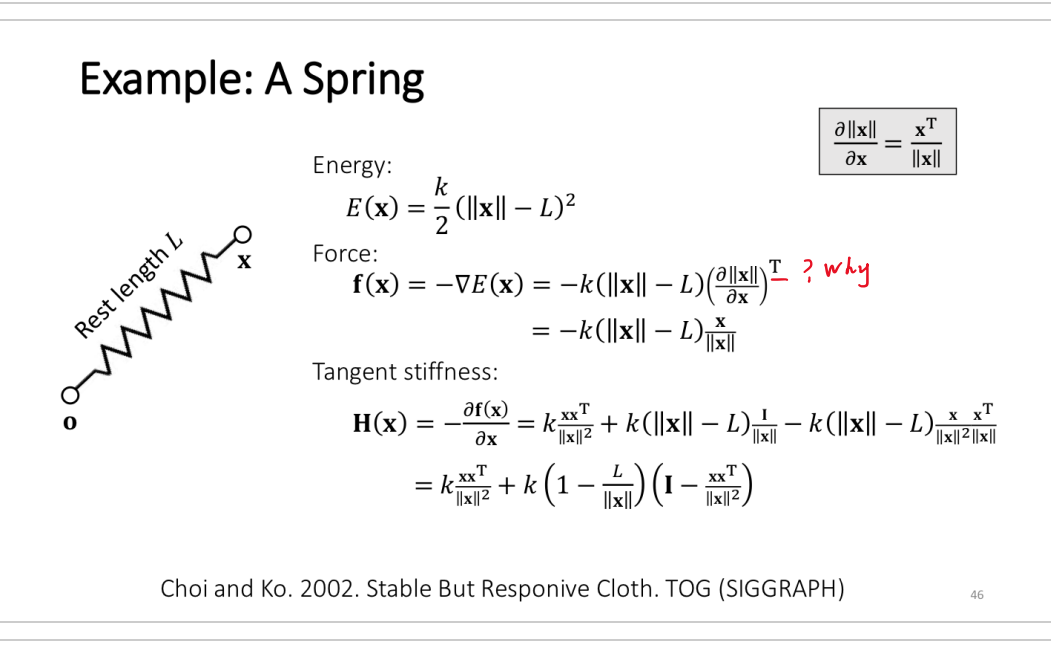
Quiz:

$x=\begin{bmatrix}x\\y\\z\end{bmatrix}$

$\frac{\partial\|\mathbf{x}\|}{\partial\mathbf{x}}=?$

$\frac{\partial\|\mathbf{x}\|}{\partial\mathbf{x}}=\frac{\partial(\mathbf{x}^\mathrm{T}\mathbf{x})^{1/2}}{\partial\mathbf{x}}=\frac12(\mathbf{x}^\mathrm{T}\mathbf{x})^{-1/2}\frac{\partial(\mathbf{x}^\mathrm{T}\mathbf{x})}{\partial\mathbf{x}}=\frac{1}{2\|\mathbf{x}\|}2\mathbf{x}^\mathrm{T}=\frac{\mathbf{x}^\mathrm{T}}{\|\mathbf{x}\|}$

$\frac{\partial(\mathbf{x}^\mathrm{T}\mathbf{x})}{\partial\mathbf{x}}=\frac{\partial(x^2+y^2+z^2)}{\partial\mathbf{x}}=[2x\ \ 2y\ \ 2z]=2\mathbf{x}^\mathrm{T}$



Example: A Spring

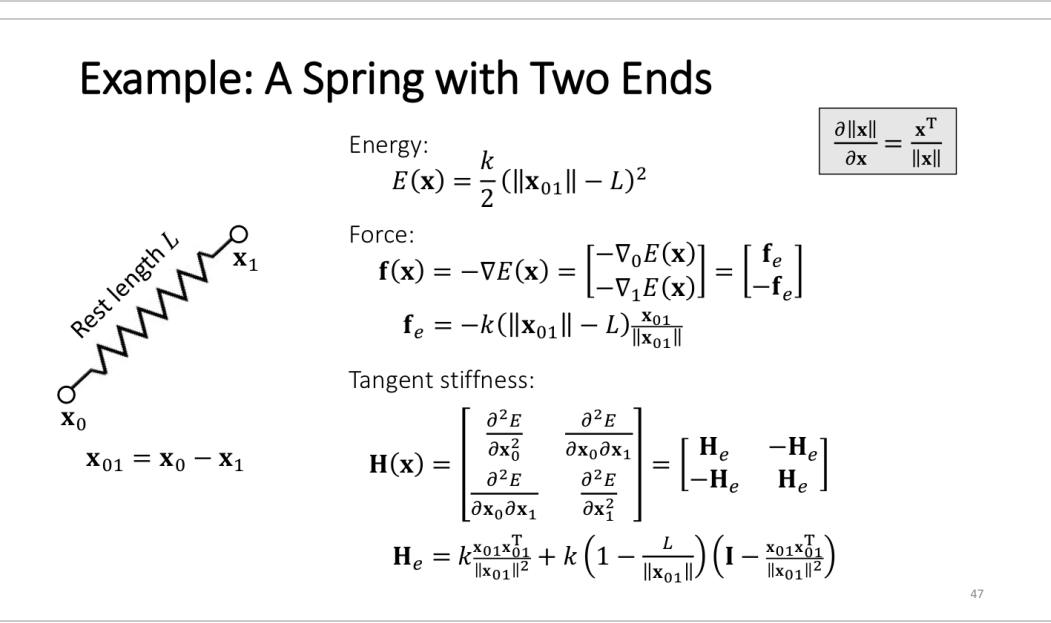
$\frac{\partial\|\mathbf{x}\|}{\partial\mathbf{x}}=\frac{\mathbf{x}^\mathrm{T}}{\|\mathbf{x}\|}$

Energy:
$E(\mathbf{x})=\frac{k}{2}(\|\mathbf{x}\|-L)^2$

Force:
$\mathbf{f}(\mathbf{x})=-\nabla E(\mathbf{x})=-k(\|\mathbf{x}\|-L)\left(\frac{\partial\|\mathbf{x}\|}{\partial\mathbf{x}}\right)^\mathrm{T}$? why
$=-k(\|\mathbf{x}\|-L)\frac{\mathbf{x}}{\|\mathbf{x}\|}$

Tangent stiffness:
$\mathbf{H}(\mathbf{x})=-\frac{\partial\mathbf{f}(\mathbf{x})}{\partial\mathbf{x}}=k\frac{\mathbf{xx}^\mathrm{T}}{\|\mathbf{x}\|^2}+k(\|\mathbf{x}\|-L)\frac{\mathbf{I}}{\|\mathbf{x}\|}-k(\|\mathbf{x}\|-L)\frac{\mathbf{x}}{\|\mathbf{x}\|^2}\frac{\mathbf{x}^\mathrm{T}}{\|\mathbf{x}\|}$
$=k\frac{\mathbf{xx}^\mathrm{T}}{\|\mathbf{x}\|^2}+k\left(1-\frac{L}{\|\mathbf{x}\|}\right)\left(\mathbf{I}-\frac{\mathbf{xx}^\mathrm{T}}{\|\mathbf{x}\|^2}\right)$

Choi and Ko. 2002. Stable But Responive Cloth. TOG (SIGGRAPH)



Example: A Spring with Two Ends

$\frac{\partial\|\mathbf{x}\|}{\partial\mathbf{x}}=\frac{\mathbf{x}^\mathrm{T}}{\|\mathbf{x}\|}$

$\mathbf{x}_{01}=\mathbf{x}_0-\mathbf{x}_1$

Energy:
$E(\mathbf{x})=\frac{k}{2}(\|\mathbf{x}_{01}\|-L)^2$

Force:
$\mathbf{f}(\mathbf{x})=-\nabla E(\mathbf{x})=\begin{bmatrix}-\nabla_0E(\mathbf{x})\\-\nabla_1E(\mathbf{x})\end{bmatrix}=\begin{bmatrix}\mathbf{f}_e\\-\mathbf{f}_e\end{bmatrix}$
$\mathbf{f}_e=-k(\|\mathbf{x}_{01}\|-L)\frac{\mathbf{x}_{01}}{\|\mathbf{x}_{01}\|}$

Tangent stiffness:
$\mathbf{H}(\mathbf{x})=\begin{bmatrix}\frac{\partial^2E}{\partial\mathbf{x}_0^2}&\frac{\partial^2E}{\partial\mathbf{x}_0\partial\mathbf{x}_1}\\\frac{\partial^2E}{\partial\mathbf{x}_0\partial\mathbf{x}_1}&\frac{\partial^2E}{\partial\mathbf{x}_1^2}\end{bmatrix}=\begin{bmatrix}\mathbf{H}_e&-\mathbf{H}_e\\-\mathbf{H}_e&\mathbf{H}_e\end{bmatrix}$
$\mathbf{H}_e=k\frac{\mathbf{x}_{01}\mathbf{x}_{01}^\mathrm{T}}{\|\mathbf{x}_{01}\|^2}+k\left(1-\frac{L}{\|\mathbf{x}_{01}\|}\right)\left(\mathbf{I}-\frac{\mathbf{x}_{01}\mathbf{x}_{01}^\mathrm{T}}{\|\mathbf{x}_{01}\|^2}\right)$