A summary of Projective Geometric Algebra

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Abstract

I. Geometric numbers

$$1 + x^2 = 0$$
$$x = ?$$

x is not a real number; but if it's not real, why should the other numbers be real?

$$(e_1)^2 + (e_2)^2 = (e_0)^2$$
$$(e_1)^2 = 1;\ (e_2)^2 = -1;\ (e_0)^2 = 0$$

In fact, we can define as many of these as we want, the simplest examples being:

$a + be_1$ `// hyperbolic numbers`

$a + be_2$ `// complex numbers`

$a + be_0$ `// dual numbers`

We can multiply these numbers together using the geometric product:

$$e_i e_i = \{1, -1, 0\}$$
$$e_i e_j = -e_j e_i$$

This product is neither commutative nor anticommutative, but it is distributive and associative:

$$AB \neq BA$$
$$AB \neq -BA$$
$$A(B + C) = AB + AC$$
$$(AB)C = A(BC)$$
$$aB = Ba;\ a \in \mathbb{R}$$

Thus the product of two complex numbers:

$$\begin{aligned}
&(A_1 + A_2 e_2)(B_1 + B_2 e_2) \\
&= A_1 B_1 + A_1 B_2 e_2 + A_2 e_2 B_1 + A_2 e_2 B_2 e_2 \\
&= A_1 B_1 + A_1 B_2 e_2 + A_2 B_1 e_2 + A_2 B_2 \\
&= (A_1 B_1 + A_2 B_2) + (A_1 B_2 + A_2 B_1) e_2
\end{aligned}$$

II. Rotations

A multivector with n basis vectors consists of 2^n blades:

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- scalar = 0-vector
- vector = 1-vector
- bivector = 2-vector
- trivector = 3-vector
- ...
- (n-1)-vector = pseudovector
- n-vector = pseudoscalar
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Where a k-vector has $\binom{n}{k}$ blades, for example:

$$\begin{aligned}
A = A_1& \\
&+ A_2 e_0 + A_3 e_1 + A_4 e_2 \\
&+ A_5 e_{01} + A_6 e_{02} + A_7 e_{12} \\
&+ A_8 e_{012}
\end{aligned}$$

We can abbreviate blades like $e_1 e_2$ as e_{12}.

Multiplying two multivectors gives you another multivector, we can use the taylor series expansion of the exponential function to find a rotation e^A:

$$e^x = \sum_{k=0}^{\infty} \frac{x^k}{k!}$$

$$e^{ae_2} = 1 + ae_2 - \frac{a^2}{2} - \frac{a^3}{3}e_2 + ...$$

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// by the sum being convergent
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$$= (1 - \frac{a^2}{2} + ...) + (a - \frac{a^3}{3} + ...)e_2$$
$$= cos(a) + sin(a)e_2$$

Similarly you can find

$$e^{e_i} = \begin{cases} cos(a) + sin(a)e_i & ((e_i)^2 = -1) \\ cosh(a) + sinh(a)e_i & ((e_i)^2 = 1) \\ 1 + e_i & ((e_i)^2 = 0) \end{cases}$$

This gives us rotations, hyperbolic rotations and translations (rotations through infinity) respectively.

Then for a multivector we would have:

$$e^A = e^{A_1} e^{A_2 e_0} e^{A_3 e_1} ... e^{A_n e_I}$$

III. Shapes and sizes

TODO