

Polygons & Transformations Cheatsheet

3.AB PreIB Math

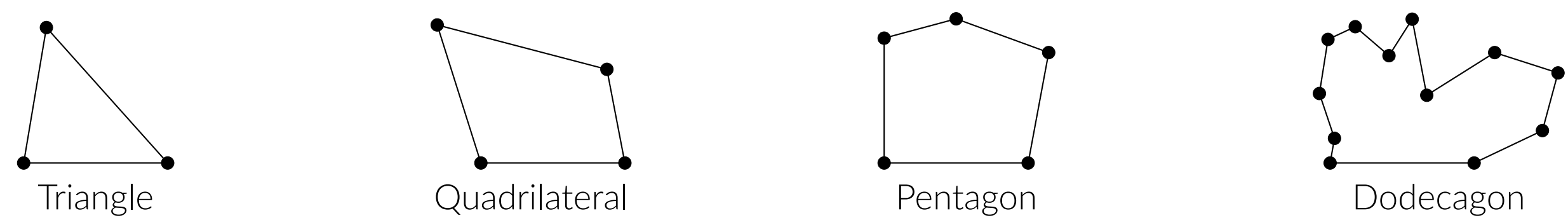
Adam Klepáč



Polygons

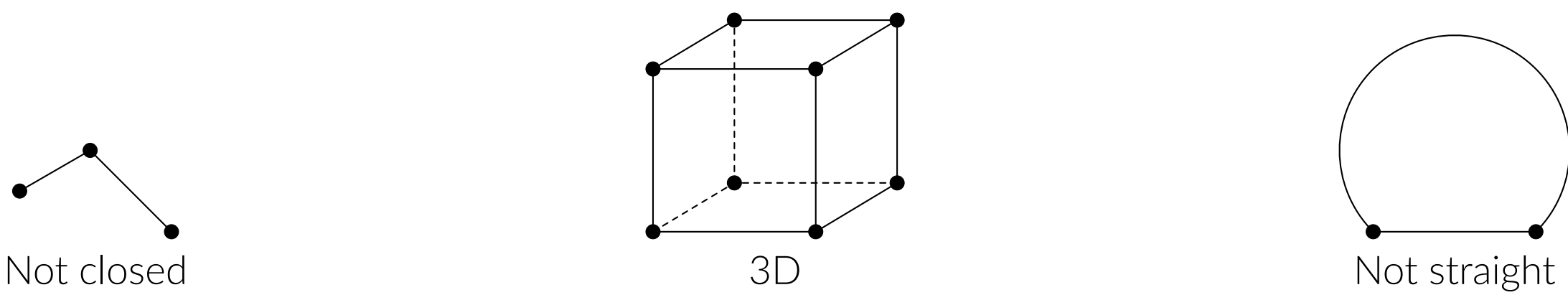
Polygon is a **closed** 2D shape **made only of segments**. We call the endpoints of those segments, **vertices**, and the segments themselves, **edges**.

Examples



Polygons with n sides are called **n -gons**.

Counterexamples

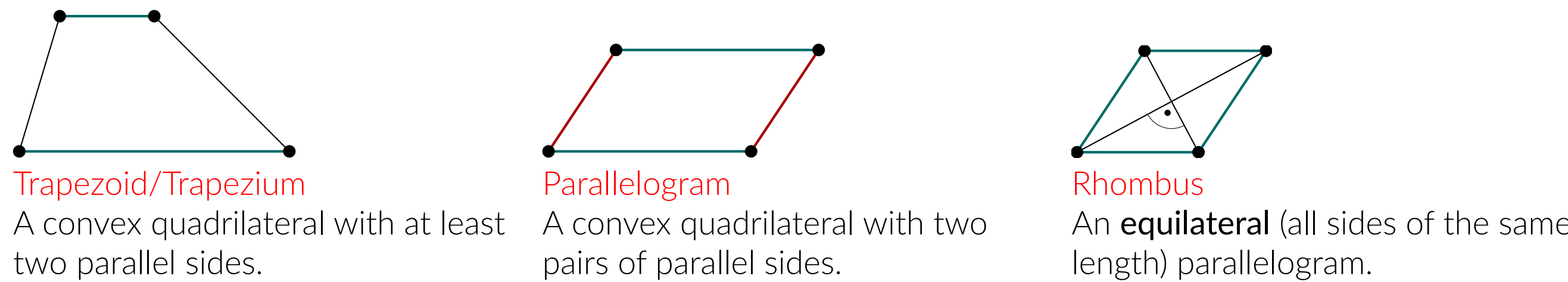


Convex Polygons

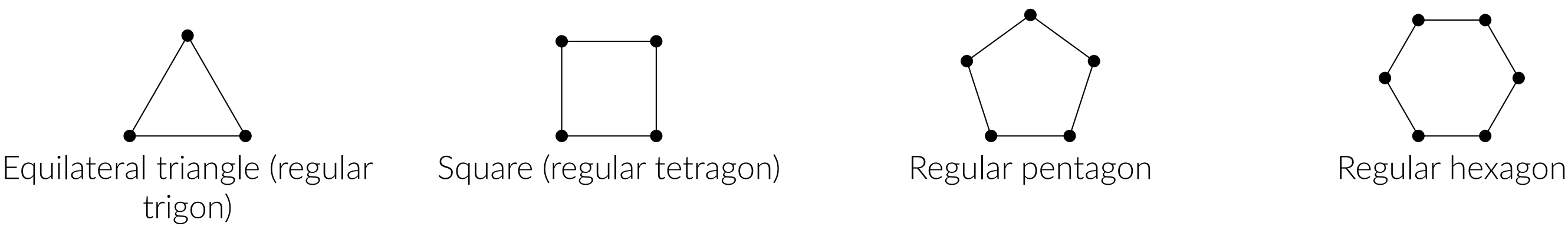
A polygon is called **convex** if it has no internal angle greater than 180° .



Special types of convex polygons

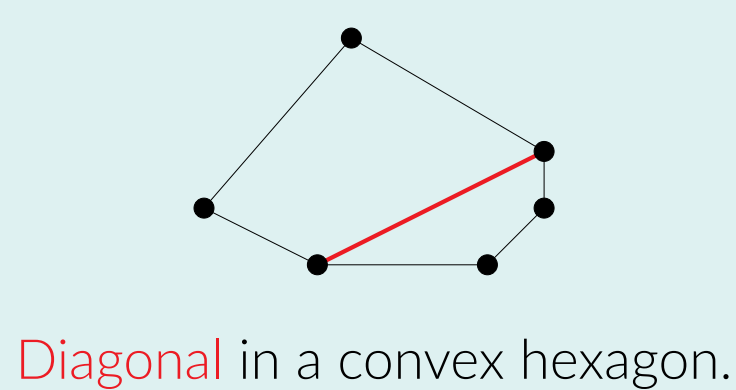


In addition, if a **convex** polygon has **all sides of the same length** and **all angles of the same size**, it is called **regular**.

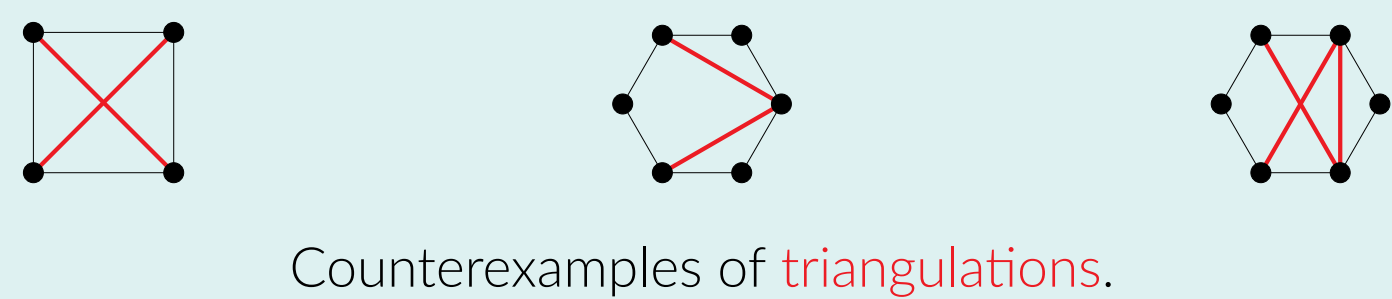
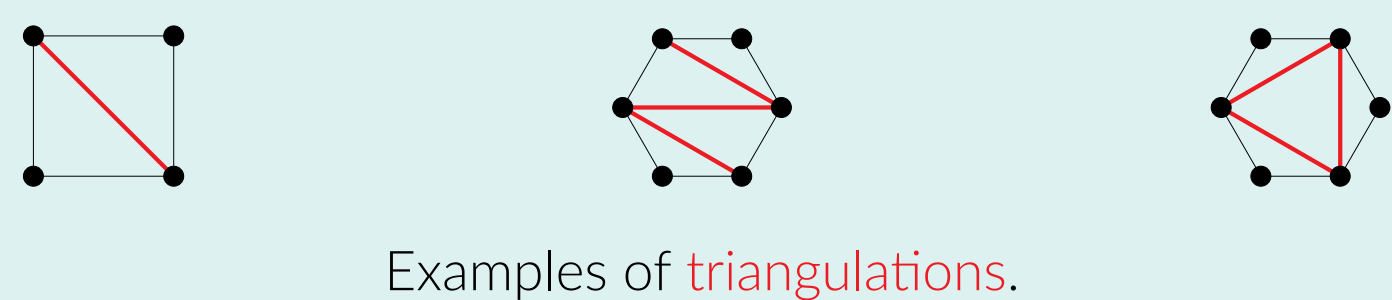


Diagonals & Triangulations

A **diagonal** in a **convex** polygon is a segment connecting two of its **non-adjacent** vertices.



A **triangulation** of a **convex** polygon is its division into triangles by **non-intersecting** diagonals.

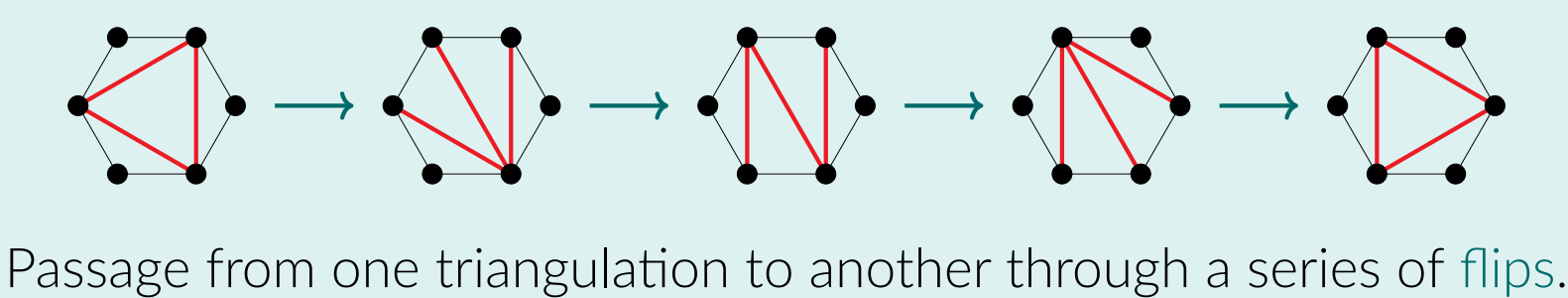
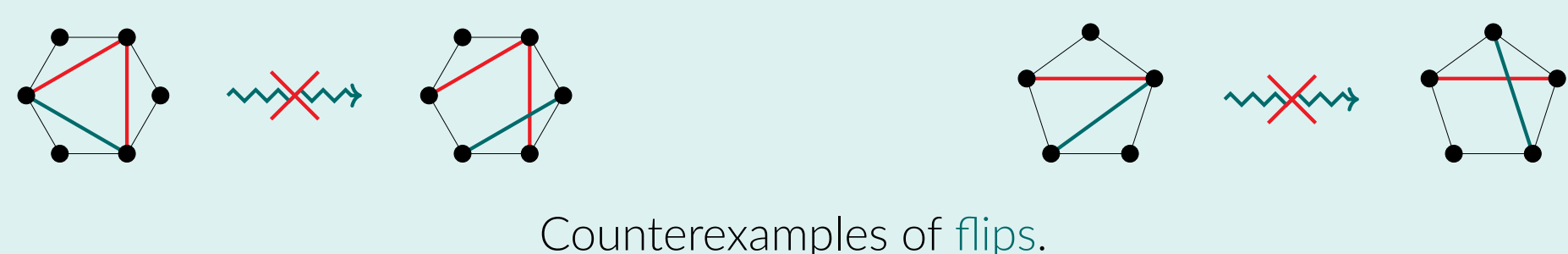


The total number of different triangulations of a convex n -gon is

$$\frac{n \cdot (n+1) \cdot \dots \cdot (2n-4)}{(n-2)!},$$

which you **of course don't have to remember**. Interestingly enough, every triangulation can be transformed into any other by a series of **flips**.

A **flip** is a swap of one diagonal for the other in a chosen quadrilateral so that the **result is again a triangulation**.

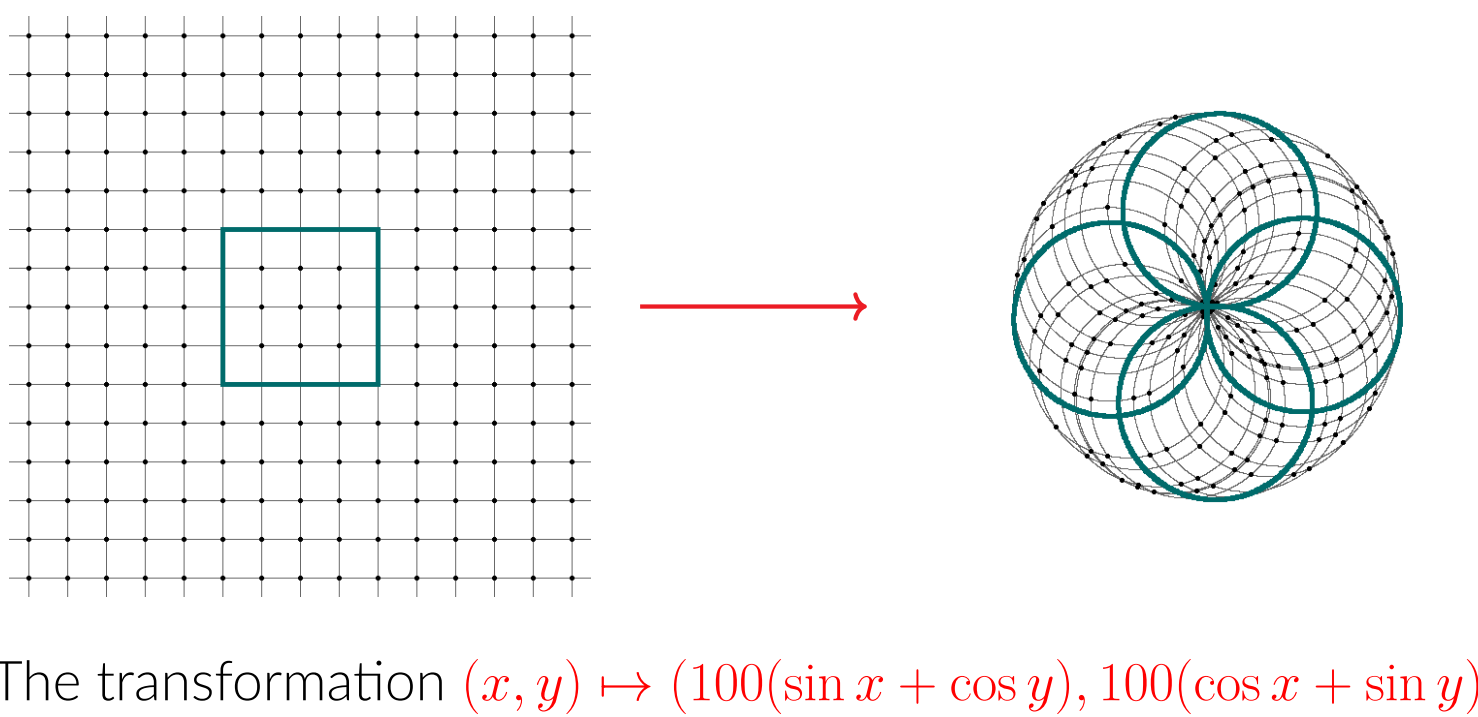
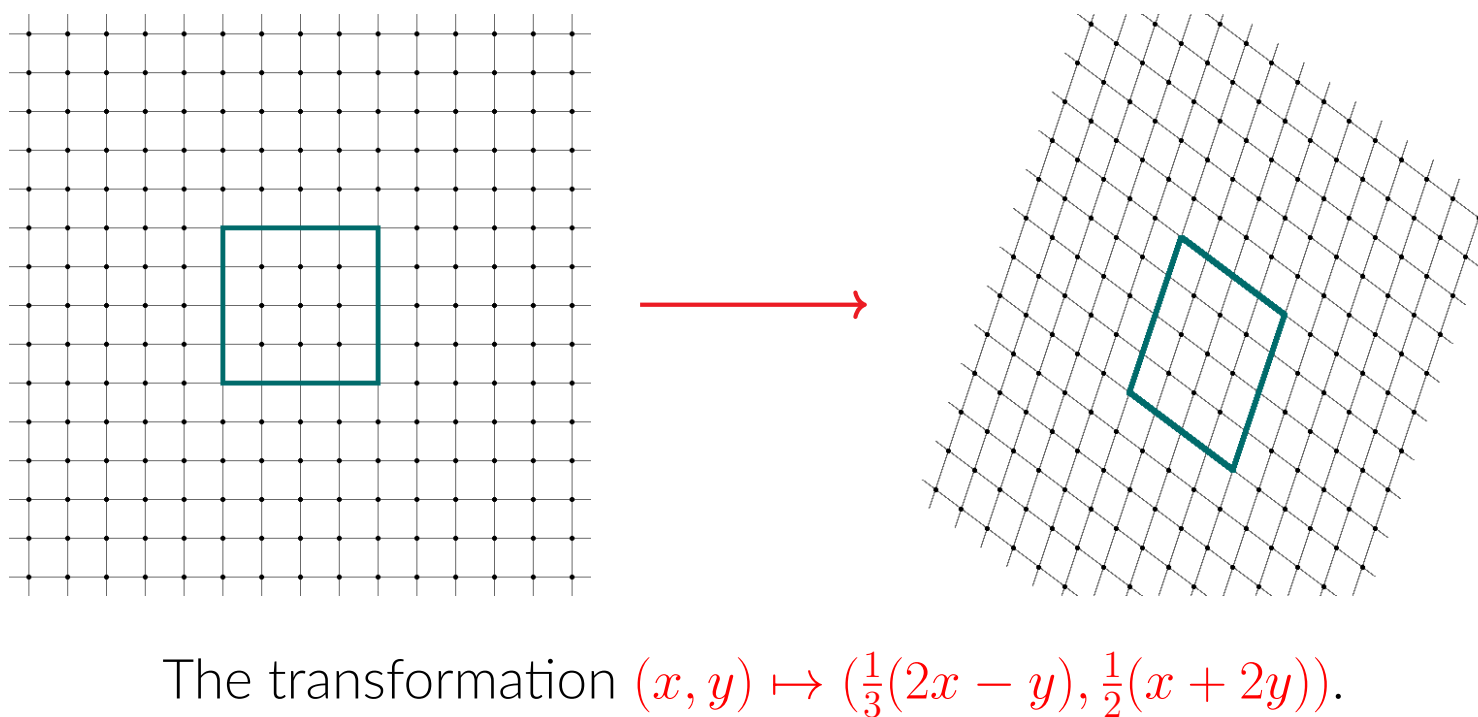


I encourage you to think about how to determine the number of flips necessary to pass from one triangulation to another. Can I have made the passage above in fewer flips?

Plane Transformations

The **plane** is basically just the set \mathbb{R}^2 of all **pairs of real numbers**. A pair $(x, y) \in \mathbb{R}^2$ is typically called a **point**. Then, a plane **transformation** is a **function** which maps points to points. In symbols, it's a function $\mathbb{R}^2 \rightarrow \mathbb{R}^2$.

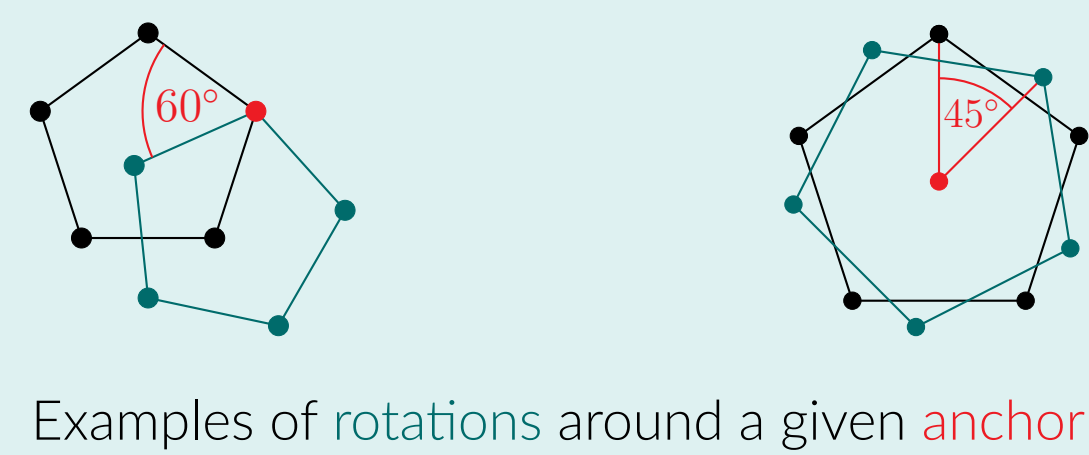
We can visualise what a transformation does for example by look at the image of a square (or an entire grid).



Rotations & Reflections

We shall be interested in two specific plane transformations – **rotations** and **reflections**.

Rotations are plane transformations that, well ..., rotates the entire plane around a fixed point called **anchor**. Applied to polygons, rotations may look like this:



Reflections are basically 'mirrors'. They mirror each point in the plane through a given line called **axis** (of reflection).



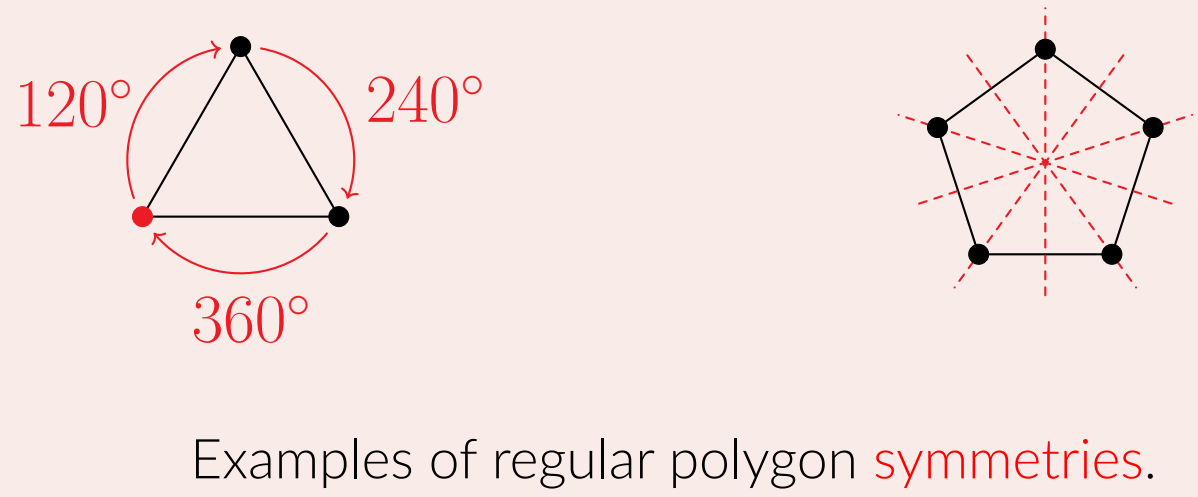
Symmetries of Regular Polygons

Some **rotations** and **reflections** get along nicely with **regular polygons**. By this, we mean that they **keep them intact**. We call them the **symmetries** of the polygon.

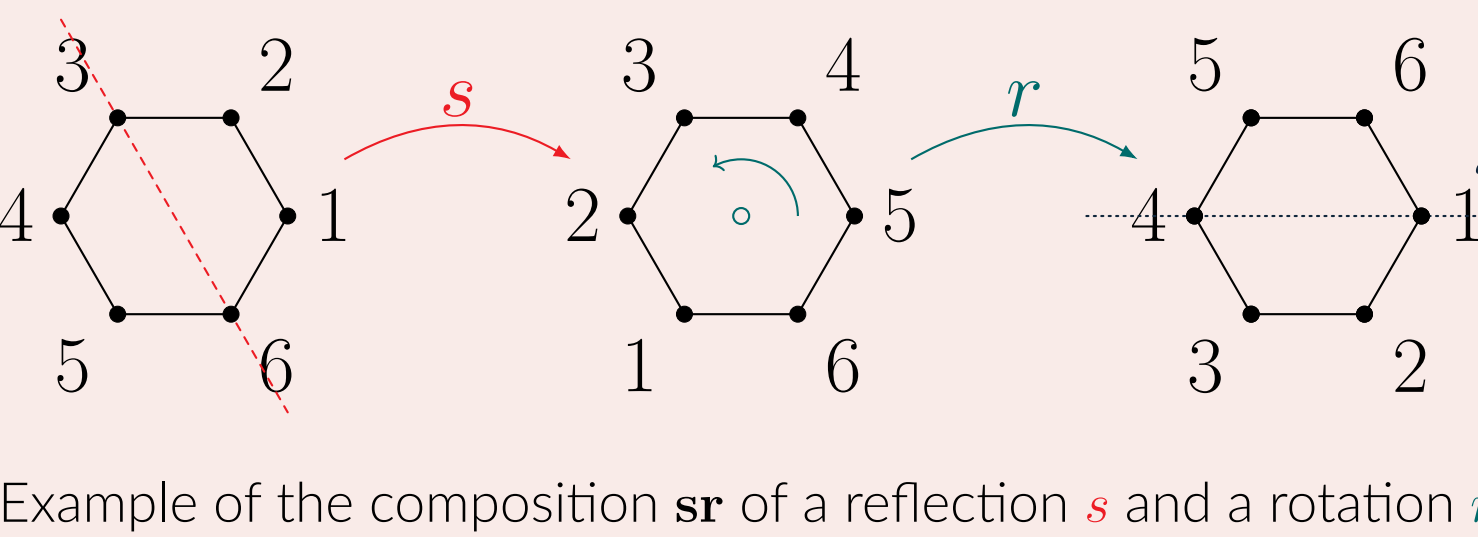
Each regular n -gon has multiple symmetries:

- (r) **rotation** by $k \cdot 360^\circ/n$ for any k between 1 and n .
- (s) **reflection**
 - over lines passing through centres of opposite sides or through opposite vertices if n is **even**;
 - over lines passing through a centre of a side and the opposite vertex if n is **odd**.

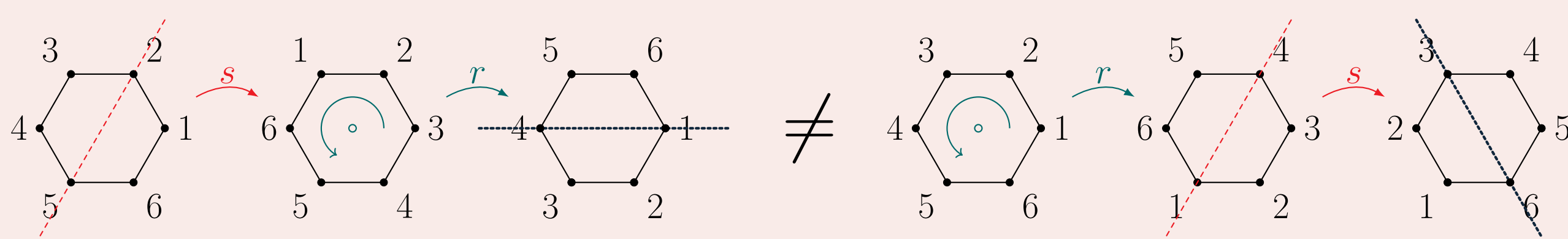
Therefore, an n -gon has n rotational and n reflectional symmetries.



Moreover, symmetries (being functions) can be **chained** or **composed**, creating new symmetries. We'll label rotations by the letter r and reflections by s . A **chain** or **composition** is read left-to-right, that is, sr means 'apply s first, then r '.



The order of composition matters!



In general, a composition of

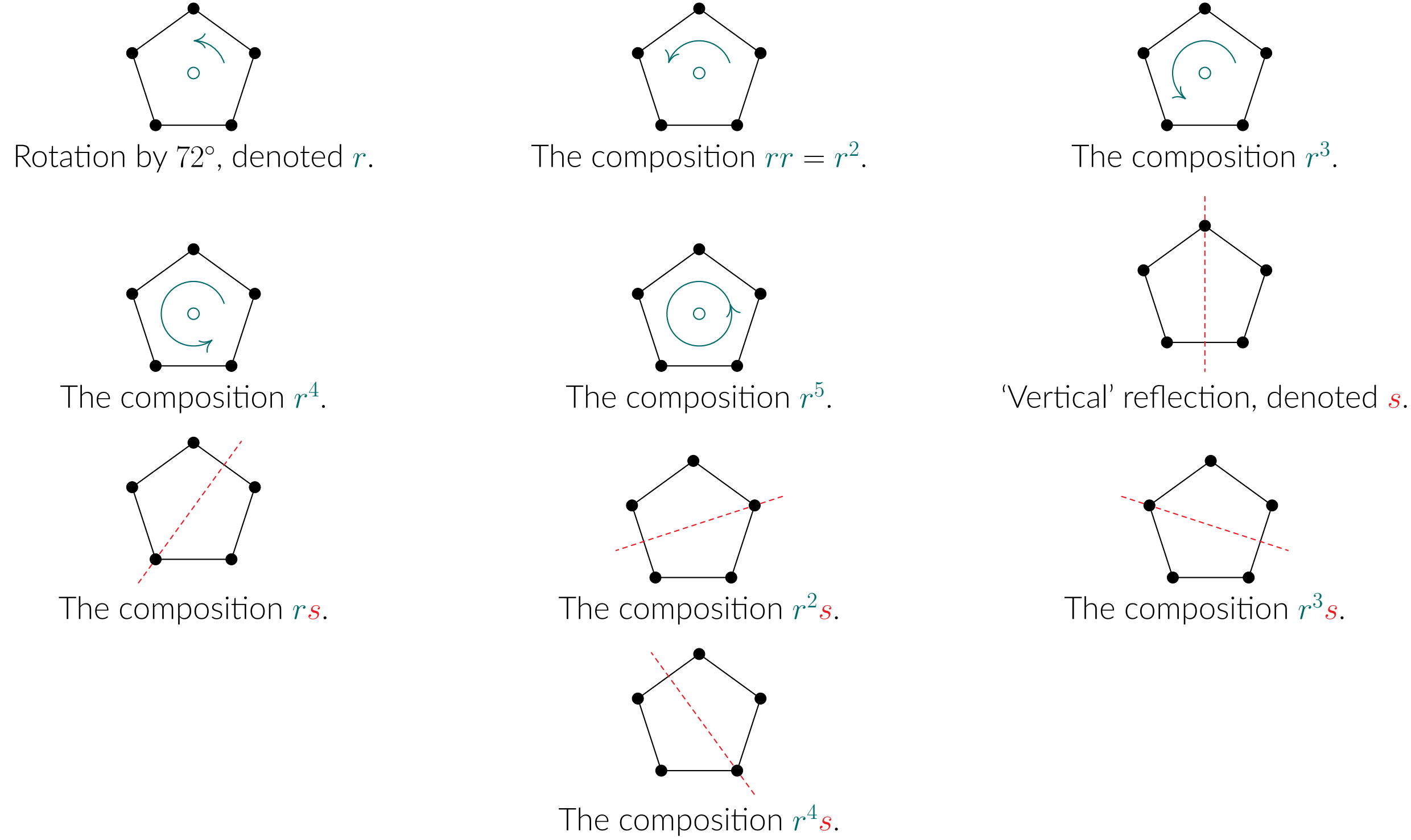
- a **rotation** and a **rotation** is again a **rotation**,
- a **rotation** and a **reflection** (in any order) is a **reflection**,
- a **reflection** and a **reflection** is a **rotation**.

Generating Symmetries

Question: If I can compose symmetries, how many (and which) symmetries are enough to generate (create by composition) all the others?

Answer: Just two are enough. Basically, I need to be able to generate the smallest rotation (that is, rotation by $360^\circ/n$) and any reflection. Composing these two gives me all the other rotations and reflections.

Let's see this on a regular pentagon. Here, r denotes the rotation by $360^\circ/5 = 72^\circ$ and s denotes the 'vertical' reflection.



All symmetries of the regular pentagon written as compositions of r and s .

Question: Given two symmetries, how do I know I can generate the rest using only these two?

Answer: It of course depends on their type.

- If I'm given 2 rotations, I can never generate all symmetries because composing rotations doesn't yield a reflection.
- If I'm given a rotation and a reflection, then the rotation must be by $k \cdot 360^\circ/n$ with k **coprime to n** . Otherwise I can never generate the rotation by $360^\circ/n$. The reflection can be of any kind.
- If I'm given two reflections, their composition must be a rotation by $k \cdot 360^\circ/n$ with k **coprime to n** for the same reason as above.

Vocabulary

English	Czech	Definition
Segment	Úsečka	Straight finite line connecting two points.
Polygon	Mnohoúhelník	Closed 2D shape made of segments.
Vertex	Vrchol	Any of the endpoints of the segments forming a polygon.
Edge	Hrana	Any of the segments forming a polygon.
Triangle	Trojúhelník	A polygon with 3 vertices.
Quadrilateral	Čtyřúhelník	A polygon with 4 vertices.
Internal/External angle	Vnitřní/Vnější úhel	The angle on the inside/outside of a polygon formed by its edges.
Convex	Konvexní	A polygon whose internal angles don't exceed 180° .
Equilateral	Rovnostranný	Describes a polygon with all sides of equal length.
Trapezoid	Lichoběžník	A quadrilateral with a pair of parallel sides.
Parallelogram	Rovnoběžník	A quadrilateral with two pairs of parallel sides.
Rhombus	Kosočtverec	An equilateral parallelogram.
Regular	Pravidelný	Describes an equilateral polygon with all angles of the same size.
Square	Čtverec	A regular quadrilateral.
Diagonal	Uhlopříčka	A segment contained inside a (convex) polygon connecting two of its non-adjacent vertices.
Triangulation	Triangulace	Division of a (convex) polygon into triangles by non-intersecting diagonals.
Plane	Rovina	The 2D space \mathbb{R}^2 .
Plane transformation	Rovinná transformace	Any function $\mathbb{R}^2 \rightarrow \mathbb{R}^2$.
Rotation	Rotace/otočení	A plane transformation which rotates all points by a given angle around a given point.
Anchor of rotation	Střed otáčení	The point around which a rotation is performed.
Reflection	Reflexe/osová souměrnost	A plane transformation which mirrors all points over a given line.
Axis of reflection	Osa reflexe/souměrnosti	The line over which points are reflected.
Symmetry	Souměrnost	A plane transformation which keeps the specified object intact.
Composition	Složení	The act of applying two functions in sequence.
Coprime	Nesoudělný	Describes a pair of numbers sharing no prime divisors.