

# Interpreting graphical representation of asymmetric data

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## Abstract

Given an asymmetric matrix ( $n \times n$ ) of observations  $O = (o_{jk})$ , construct a symmetric matrix  $S = (O + O')/2$  and a skew-symmetric matrix  $A = (O - O')/2$ . Applying Gower's procedure or Escoufier & Grorud procedure to those data matrices, we obtain a graphical representation of objects in 2 dimensions. For interpretation of the configuration, this paper suggests that we can examine Euclidean distance which corresponds to some quantity in terms of data.

In Gower's approach, starting with  $O$  whose  $o_{jj}$  may or may not be defined, we perform the singular value decomposition of  $A$ . Assume that  $\text{rank } A = 2r$ . Let  $\mathbf{u}_t = (u_{jt})$  and  $\mathbf{v}_t = (v_{jt})$  be the pair of singular vectors associated with singular value  $\mu_t$ . Then we have a plot of  $n$  points in terms of  $(u_{jt}, v_{jt})$  on the  $u$ - $v$  plane ( $t = 1, 2, \dots, r$ ). For the  $t$ -th plane, denote the Euclidean distance between points  $j$  and  $k$  by  $d_{jk}(t)$ . For data transformed by (1), we obtain relation (2).

$$c_{jk} = \frac{1}{4} \sum_{i=1}^n (o_{ij} - o_{ik} + o_{ki} - o_{ji})^2 \quad (1)$$

$$c_{jk} = \sum_{t=1}^r \mu_t^2 d_{jk}^2(t) \quad (2)$$

In Escoufier & Grorud' approach, starting with  $O$  whose  $o_{jj}$  should be defined, we deal with an Hermitian matrix  $H = S + iA$  ( $i^2 = -1$ ). Write the eigenvalue problem as  $H\mathbf{z}_t = \lambda_t\mathbf{z}_t$  where  $\mathbf{z}_t = \mathbf{x}_t + i\mathbf{y}_t$ ,  $\mathbf{x}_t = (x_{jt})$  and  $\mathbf{y}_t = (y_{jt})$ . Assume that  $\text{rank } H = r$ . In the plot of  $n$  objects in terms of  $(x_{jt}, y_{jt})$  for each  $t (= 1, 2, \dots, r)$ , denote the Euclidean distance between points  $j$  and  $k$  by  $d_{jk}(t)$  on the  $x$ - $y$  plane. For data transformed by (3), we obtain relation (4).

$$p_{jk} = o_{jj} + o_{kk} - o_{jk} - o_{kj} \quad (3)$$

$$p_{jk} = \sum_{t=1}^r \lambda_t d_{jk}^2(t) \quad (4)$$

## References

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