Esso può esprimersi nella forma

$$\nu = (a^{s_1}_{h_1}\mathbf{b}^{h_1}, \dots, a^{s_p}_{h_p}\mathbf{b}^{h_p}, c^{k_1}_{t_1}\mathbf{b}_{k_1}, \dots, c^{k_q}_{t_q}\mathbf{b}_{k_q}).$$

Con l'ausilio della (2.11), sfruttando la multilinearità, si ottiene:

$$\begin{aligned}
\mathsf{U}(\nu) &= a^{s_1}_{h_1}\cdots a^{s_p}_{h_p}c^{k_1}_{t_1}\cdots c^{k_q}_{t_q}\mathsf{U}(\mathbf{b}^{h_1}, \dots, \mathbf{b}^{h_p}, \mathbf{b}_{k_1}, \dots, \mathbf{b}_{k_q}) = \\
&= a^{s_1}_{h_1}\cdots a^{s_p}_{h_p}c^{k_1}_{t_1}\cdots c^{k_q}_{t_q}\mathsf{T}(\mathbf{b}^{h_1}, \dots, \mathbf{b}^{h_p}, \mathbf{b}_{k_1}, \dots, \mathbf{b}_{k_q}) = \\
&= \mathsf{T}(\nu). \qquad (2.12)
\end{aligned}$$