Linear Algebra

Book 2

$f: \mathbb{R}^2 \to \mathbb{R}^2$

$f(x,y) = (3x+2y,\ x-5y)$ can be represented as a matrix transformation

$$\begin{pmatrix} x \\ y \end{pmatrix} \longmapsto \begin{bmatrix} 3 & 2 \\ 1 & -5 \end{bmatrix}\begin{bmatrix} x \\ y \end{bmatrix} = \begin{bmatrix} 3x+2y \\ x-5y \end{bmatrix}$$

Every linear operator can be expressed as matrix multiplication

eg. consider solutions of $y'' + y = 0$ i.e. $f(x) = \underbrace{a \sin x + b \cos x}_{\begin{bmatrix} a \\ b \end{bmatrix}}$

$$Df(x) = \underbrace{a \cos x - b \sin x}_{\begin{bmatrix} -b \\ a \end{bmatrix}}$$

$$D(rf + sg) = rDf + sDg$$

$$(rf+sg)' = rf' + sg'$$

$$\underbrace{\begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix}}_{M}\begin{bmatrix} a \\ b \end{bmatrix} = \begin{bmatrix} -b \\ a \end{bmatrix}$$

$M = \begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix}$

$M^2 = \begin{bmatrix} -1 & 0 \\ 0 & -1 \end{bmatrix}$

$M^3 = \begin{bmatrix} 0 & 1 \\ -1 & 0 \end{bmatrix}$

$M^4 = \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix}$

Every 2×2 real matrix A represents a linear transformation $T_A : \mathbb{R}^2 \to \mathbb{R}^2$ which is the matrix transformation $T_A\begin{bmatrix}x\\y\end{bmatrix} = A\begin{bmatrix}x\\y\end{bmatrix}$.

eg. $\underbrace{\begin{bmatrix}0 & -1\\1 & 0\end{bmatrix}}\begin{bmatrix}x\\y\end{bmatrix} = \begin{bmatrix}-y\\x\end{bmatrix}$ $\quad T_A$ is a counter-clockwise $90°$ rotation about the origin in $\mathbb{R}^2$:

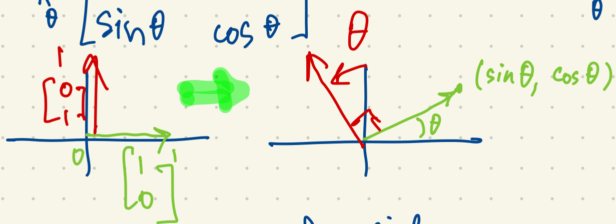
$$T_A\begin{bmatrix}1\\0\end{bmatrix} = \begin{bmatrix}0 & -1\\1 & 0\end{bmatrix}\begin{bmatrix}1\\0\end{bmatrix} = \begin{bmatrix}0\\1\end{bmatrix}$$

$$T_A\begin{bmatrix}0\\1\end{bmatrix} = \begin{bmatrix}0 & -1\\1 & 0\end{bmatrix}\begin{bmatrix}0\\1\end{bmatrix} = \begin{bmatrix}-1\\0\end{bmatrix}$$

$$T_A^4 = I \qquad I\begin{bmatrix}x\\y\end{bmatrix} = \begin{bmatrix}x\\y\end{bmatrix}$$

A counterclockwise rotation by angle θ about the origin in $\mathbb{R}^2$ represented by the matrix $R_\theta = \begin{bmatrix}\cos\theta & -\sin\theta\\ \sin\theta & \cos\theta\end{bmatrix}$

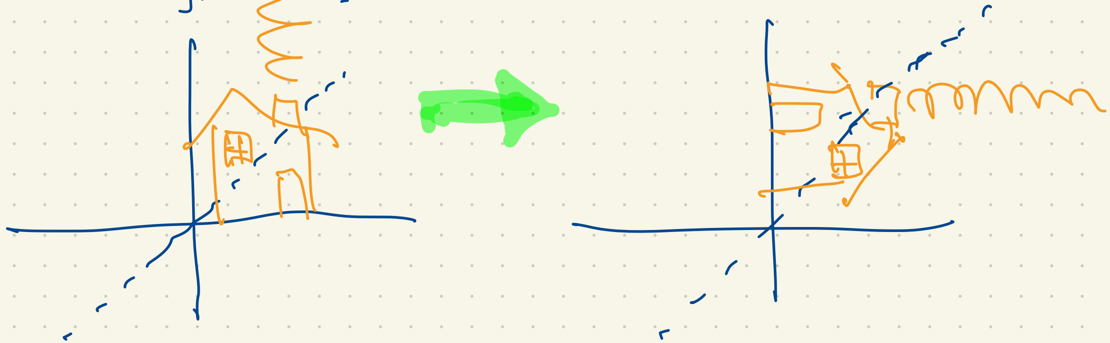
$$R_\theta\begin{bmatrix}1\\0\end{bmatrix} = \begin{bmatrix}\cos\theta\\ \sin\theta\end{bmatrix} \qquad R_\theta\begin{bmatrix}0\\1\end{bmatrix} = \begin{bmatrix}-\sin\theta\\ \cos\theta\end{bmatrix}$$



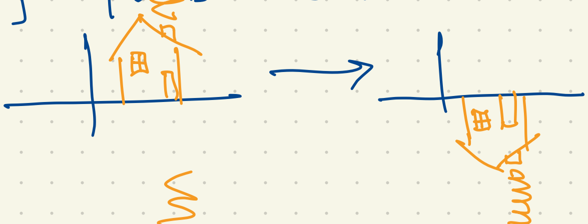
$$\cos(\alpha+\beta) = \cos\alpha\cos\beta - \sin\alpha\sin\beta$$
$$\sin(\alpha+\beta) = \sin\alpha\cos\beta + \cos\alpha\sin\beta$$

$$R_\beta R_\alpha = R_{\alpha+\beta} \qquad \begin{bmatrix}\cos\beta & -\sin\beta\\ \sin\beta & \cos\beta\end{bmatrix}\begin{bmatrix}\cos\alpha & -\sin\alpha\\ \sin\alpha & \cos\alpha\end{bmatrix} = \begin{bmatrix}\cos(\alpha+\beta) & -\sin(\alpha+\beta)\\ \sin(\alpha+\beta) & \cos(\alpha+\beta)\end{bmatrix}$$

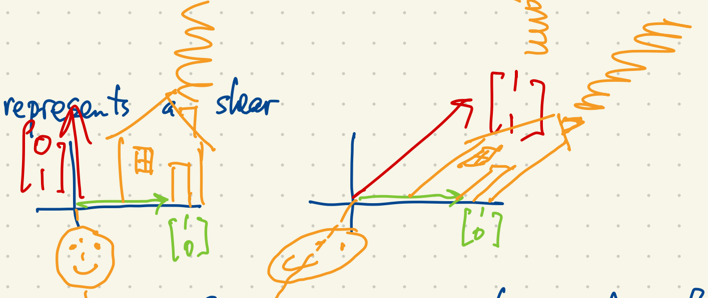
Eg. $\begin{bmatrix}0 & 1\\ 1 & 0\end{bmatrix}\begin{bmatrix}x\\ y\end{bmatrix} = \begin{bmatrix}y\\ x\end{bmatrix}$ is a reflection about the line $y = x$



$\begin{bmatrix}1 & 0\\ 0 & -1\end{bmatrix}$ represents a reflection in the x-axis



$\begin{bmatrix}1 & 1\\ 0 & 1\end{bmatrix}$ represents a shear



Every matrix transformation is a linear transformation: it takes 0 to 0 and it takes lines to lines or points. It may distort distances and angles.

Example of a "somewhat" generic linear transformation $\mathbb{R}^2 \to \mathbb{R}^2$:

Every linear transformation $T: \mathbb{R}^m \to \mathbb{R}^n$ takes 0 to 0,
takes lines to lines or points

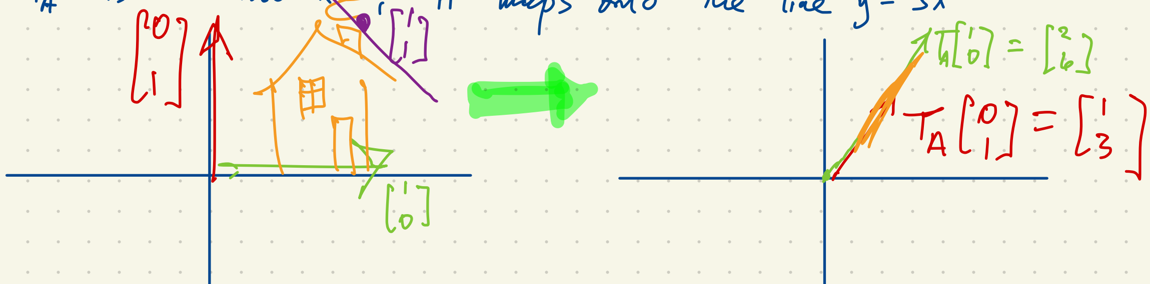
A function $f: A \to B$ is "one-to-one" if $f(x) = f(y)$ implies $x = y$. (No two inputs give the same output.)

f is "onto" if for every $b \in B$ there exists $a \in A$ such that $f(a) = b$.

e.g. $A = \begin{bmatrix}2 & 1\\6 & 3\end{bmatrix}$ defines a linear transformation $T_A: \mathbb{R}^2 \to \mathbb{R}^2$, $T_A\left(\begin{bmatrix}x\\y\end{bmatrix}\right) = A\begin{bmatrix}x\\y\end{bmatrix} = \begin{bmatrix}2x+y\\6x+3y\end{bmatrix}$.

This function is not one-to-one e.g. $T_A\left(\begin{bmatrix}1\\1\end{bmatrix}\right) = T_A\left(\begin{bmatrix}-1\\5\end{bmatrix}\right) = \begin{bmatrix}3\\9\end{bmatrix}$

And T_A is not onto $\mathbb{R}^2$; it maps onto the line $y = 3x$

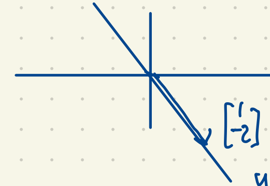


The null space of a linear transformation $\operatorname{Nul} T = \{\underline{v} : T\underline{v} = \underline{0}\}$. (the set of null vectors of T).

Recall: $T\underline{0} = \underline{0}$

$$\operatorname{Nul} \underbrace{\begin{bmatrix} 2 & 1 \\ 6 & 3 \end{bmatrix}}_{A} = \operatorname{Nul} T_A = \left\{ \begin{bmatrix} x \\ -2x \end{bmatrix} : x \in \mathbb{R} \right\}$$

$$A \begin{bmatrix} x \\ -2x \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \end{bmatrix}.$$



$\begin{bmatrix} 1 \\ -2 \end{bmatrix}$ is a null vector.

$y = -2x$

T is one-to-one iff $\operatorname{Nul} T = \{\underline{0}\}$ (the only null vector is $\underline{0}$).

This statement should be clear:

On the one hand, suppose T is one-to-one. If $\underline{v} \in \operatorname{Nul} T$ then $T\underline{v} = \underline{0} = T\underline{0}$ then $\underline{v} = \underline{0}$.

This says: if T is one-to-one then $\operatorname{Nul} T = \{\underline{0}\}$

Conversely, suppose $\operatorname{Nul} T = \{\underline{0}\}$. If $T\underline{v} = T\underline{w}$ then $T(\underline{v} - \underline{w}) = T\underline{v} - T\underline{w} = \underline{0}$

so $\underline{v} - \underline{w} \in \operatorname{Nul} T$ i.e. $\underline{v} - \underline{w} = \underline{0}$ i.e. $\underline{v} = \underline{w}$.

"Span" can be used as a noun or as a verb.

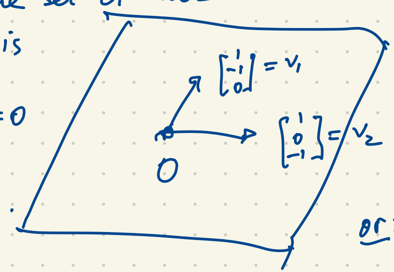
The span of a list of vectors $v_1, \dots, v_k$ is the set of all linear combinations of $v_1, \dots, v_k$.

eg. the span of the vectors $\underline{v}_1 = \begin{bmatrix} 1 \\ -1 \\ 0 \end{bmatrix}$, $\underline{v}_2 = \begin{bmatrix} 1 \\ 0 \\ -1 \end{bmatrix}$ in $\mathbb{R}^3$ is

the plane $x + y + z = 0$

in $\mathbb{R}^3$

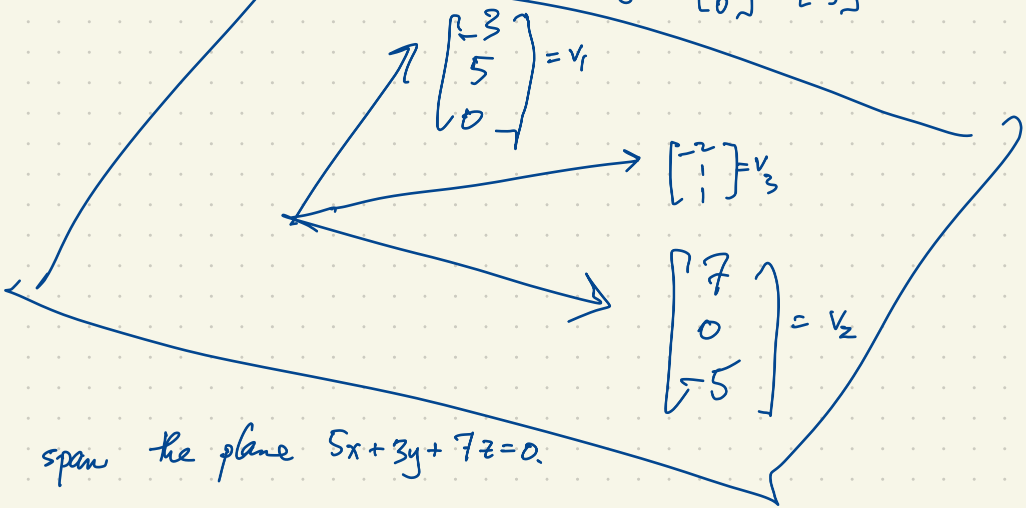
i.e. the plane $z = -x - y$.



We say that the span of v_1 and v_2 is the plane $x + y + z = 0$.

or: v_1 and v_2 span the plane $x + y + z = 0$.

eg. the plane $5x+3y+7z=0$ is spanned by $\begin{bmatrix}-3\\5\\0\end{bmatrix}, \begin{bmatrix}7\\0\\-5\end{bmatrix}$



v_1, v_2, v_3 span the plane $5x+3y+7z=0$.

Given any set of vectors $S \subset \mathbb{R}^3$, the <u>span</u> of S (denoted $\text{span}\, S = \{\text{linear combinations of vectors in } S\}$) is either $\{\underline{0}\}$ or a line through $\underline{0}$, or a plane through $\underline{0}$, or $\mathbb{R}^3$.

Friday: Quiz 5 on <u>Span</u>.

The <u>image</u> of T is $\{T_A \underline{v} : \underline{v} \in \text{domain of } T_A\}$ is the span of the columns of A.