Section 1.8

Introduction to Linear Transformations

Let A be an $m \times n$ matrix.

Let A be an $m \times n$ matrix. For the matrix equation Ax = b we have learned to describe

Let A be an $m \times n$ matrix. For the matrix equation Ax = b we have learned to describe

▶ the solution set: all x in \mathbb{R}^n making the equation true.

Let A be an $m \times n$ matrix. For the matrix equation Ax = b we have learned to describe

- ▶ the solution set: all x in \mathbb{R}^n making the equation true.
- ▶ the column span: the set of all b in \mathbf{R}^m making the equation consistent.

Let A be an $m \times n$ matrix. For the matrix equation Ax = b we have learned to describe

- ▶ the solution set: all x in \mathbb{R}^n making the equation true.
- ▶ the column span: the set of all b in \mathbf{R}^m making the equation consistent.

It turns out these two sets are very closely related to each other.

Let A be an $m \times n$ matrix. For the matrix equation Ax = b we have learned to describe

- \blacktriangleright the solution set: all x in \mathbb{R}^n making the equation true.
- ▶ the column span: the set of all b in R^m making the equation consistent.

It turns out these two sets are very closely related to each other.

In order to understand this relationship, it helps to think of the matrix A as a transformation from \mathbb{R}^n to \mathbb{R}^m .

Let A be an $m \times n$ matrix. For the matrix equation Ax = b we have learned to describe

- the solution set: all x in \mathbb{R}^n making the equation true.
- ▶ the column span: the set of all b in \mathbf{R}^m making the equation consistent.

It turns out these two sets are very closely related to each other.

In order to understand this relationship, it helps to think of the matrix A as a transformation from \mathbb{R}^n to \mathbb{R}^m .

It's a special kind of transformation called a linear transformation.

Let A be an $m \times n$ matrix. For the matrix equation Ax = b we have learned to describe

- \blacktriangleright the solution set: all x in \mathbb{R}^n making the equation true.
- \triangleright the column span: the set of all b in \mathbb{R}^m making the equation consistent.

It turns out these two sets are very closely related to each other.

In order to understand this relationship, it helps to think of the matrix A as a transformation from \mathbb{R}^n to \mathbb{R}^m .

It's a special kind of transformation called a linear transformation.

This is also a way to understand the geometry of matrices.

Definition

Definition

A **transformation** (or **function** or **map**) from \mathbb{R}^n to \mathbb{R}^m is a rule T that assigns to each vector x in \mathbb{R}^n a vector T(x) in \mathbb{R}^m .

 $ightharpoonup \mathbf{R}^n$ is called the **domain** of T (the inputs).



 \mathbf{R}^n domain

Definition

- $ightharpoonup \mathbf{R}^n$ is called the **domain** of T (the inputs).
- $ightharpoonup \mathbf{R}^m$ is called the **codomain** of T (the outputs).



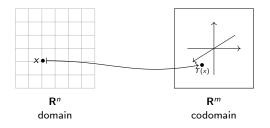
Rⁿ domain



R^m codomain

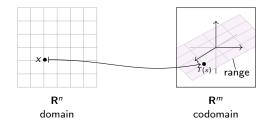
Definition

- $ightharpoonup \mathbf{R}^n$ is called the **domain** of T (the inputs).
- $ightharpoonup \mathbf{R}^m$ is called the **codomain** of T (the outputs).
- ▶ For x in \mathbb{R}^n , the vector T(x) in \mathbb{R}^m is the **image** of x under T. Notation: $x \mapsto T(x)$.



Definition

- $ightharpoonup \mathbf{R}^n$ is called the **domain** of T (the inputs).
- $ightharpoonup \mathbf{R}^m$ is called the **codomain** of T (the outputs).
- For x in \mathbb{R}^n , the vector T(x) in \mathbb{R}^m is the image of x under T. Notation: $x \mapsto T(x)$.
- ▶ The set of all images $\{T(x) \mid x \text{ in } \mathbf{R}^n\}$ is the **range** of T.



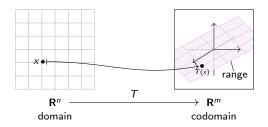
Definition

A transformation (or function or map) from \mathbb{R}^n to \mathbb{R}^m is a rule T that assigns to each vector x in \mathbb{R}^n a vector T(x) in \mathbb{R}^m .

- $ightharpoonup \mathbf{R}^n$ is called the **domain** of \mathcal{T} (the inputs).
- $ightharpoonup \mathbf{R}^m$ is called the **codomain** of T (the outputs).
- ▶ For x in \mathbb{R}^n , the vector T(x) in \mathbb{R}^m is the **image** of x under T. Notation: $x \mapsto T(x)$.
- ▶ The set of all images $\{T(x) \mid x \text{ in } \mathbf{R}^n\}$ is the **range** of T.

Notation:

 $T \colon \mathbf{R}^n \longrightarrow \mathbf{R}^m \quad \text{means} \quad T \text{ is a transformation from } \mathbf{R}^n \text{ to } \mathbf{R}^m.$



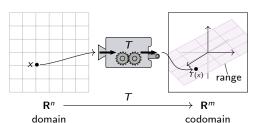
Definition

A transformation (or function or map) from \mathbb{R}^n to \mathbb{R}^m is a rule T that assigns to each vector x in \mathbb{R}^n a vector T(x) in \mathbb{R}^m .

- $ightharpoonup \mathbf{R}^n$ is called the **domain** of T (the inputs).
- $ightharpoonup \mathbf{R}^m$ is called the **codomain** of T (the outputs).
- ► For x in \mathbb{R}^n , the vector T(x) in \mathbb{R}^m is the **image** of x under T. Notation: $x \mapsto T(x)$.
- ▶ The set of all images $\{T(x) \mid x \text{ in } \mathbf{R}^n\}$ is the **range** of T.

Notation:

 $T: \mathbb{R}^n \longrightarrow \mathbb{R}^m$ means T is a transformation from \mathbb{R}^n to \mathbb{R}^m .



It may help to think of T as a "machine" that takes x as an input, and gives you T(x) as the output.

Many of the functions you know and love have domain and codomain ${\bf R}.$

Many of the functions you know and love have domain and codomain R.

$$\sin\colon \mathbf{R} \longrightarrow \mathbf{R} \qquad \sin(x) = \left(\begin{array}{l} \text{the length of the opposite edge over the} \\ \text{hypotenuse of a right triangle with angle} \\ x \text{ in radians} \end{array} \right)$$

Many of the functions you know and love have domain and codomain R.

$$\sin \colon \mathbf{R} \longrightarrow \mathbf{R}$$
 $\sin(x) = \begin{pmatrix} \text{the length of the opposite edge over the} \\ \text{hypotenuse of a right triangle with angle} \\ x \text{ in radians} \end{pmatrix}$

Note how I've written down the rule that defines the function sin.

Many of the functions you know and love have domain and codomain R.

$$\sin \colon \mathbf{R} \longrightarrow \mathbf{R}$$
 $\sin(x) = \begin{pmatrix} \text{the length of the opposite edge over the} \\ \text{hypotenuse of a right triangle with angle} \\ x \text{ in radians} \end{pmatrix}$

Note how I've written down the rule that defines the function sin.

$$f: \mathbf{R} \longrightarrow \mathbf{R} \qquad f(x) = x^2$$

Many of the functions you know and love have domain and codomain R.

$$\sin \colon \mathbf{R} \longrightarrow \mathbf{R}$$
 $\sin(x) = \begin{pmatrix} \text{the length of the opposite edge over the} \\ \text{hypotenuse of a right triangle with angle} \\ x \text{ in radians} \end{pmatrix}$

Note how I've written down the rule that defines the function sin.

$$f: \mathbf{R} \longrightarrow \mathbf{R}$$
 $f(x) = x^2$

Note that " x^2 " is sloppy (but common) notation for a function: it doesn't have a name!

Many of the functions you know and love have domain and codomain R.

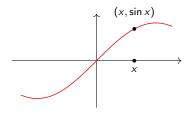
$$sin: \mathbf{R} \longrightarrow \mathbf{R}$$
 $sin(x) = \left(\begin{array}{c} \text{the length of the opposite edge over the} \\ \text{hypotenuse of a right triangle with angle} \\ x \text{ in radians} \end{array}\right)$

Note how I've written down the rule that defines the function sin.

$$f: \mathbf{R} \longrightarrow \mathbf{R}$$
 $f(x) = x^2$

Note that " x^2 " is sloppy (but common) notation for a function: it doesn't have a name!

You may be used to thinking of a function in terms of its graph.



Many of the functions you know and love have domain and codomain R.

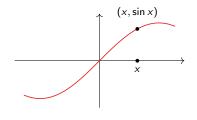
$$sin: \mathbf{R} \longrightarrow \mathbf{R}$$
 $sin(x) = \left(\begin{array}{c} \text{the length of the opposite edge over the} \\ \text{hypotenuse of a right triangle with angle} \\ x \text{ in radians} \end{array}\right)$

Note how I've written down the rule that defines the function sin.

$$f: \mathbf{R} \longrightarrow \mathbf{R}$$
 $f(x) = x^2$

Note that " x^2 " is sloppy (but common) notation for a function: it doesn't have a name!

You may be used to thinking of a function in terms of its graph.



The horizontal axis is the domain, and the vertical axis is the codomain.

Many of the functions you know and love have domain and codomain R.

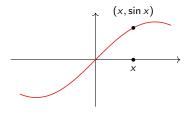
$$sin: \mathbf{R} \longrightarrow \mathbf{R}$$
 $sin(x) = \left(\begin{array}{c} \text{the length of the opposite edge over the} \\ \text{hypotenuse of a right triangle with angle} \\ x \text{ in radians} \end{array}\right)$

Note how I've written down the rule that defines the function sin.

$$f: \mathbf{R} \longrightarrow \mathbf{R}$$
 $f(x) = x^2$

Note that " x^2 " is sloppy (but common) notation for a function: it doesn't have a name!

You may be used to thinking of a function in terms of its graph.



The horizontal axis is the domain, and the vertical axis is the codomain.

This is fine when the domain and codomain are \mathbf{R} , but it's hard to do when they're \mathbf{R}^2 and \mathbf{R}^3 !

Many of the functions you know and love have domain and codomain R.

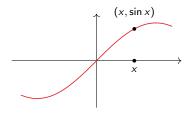
$$sin: \mathbf{R} \longrightarrow \mathbf{R}$$
 $sin(x) = \left(\begin{array}{c} the \ length \ of \ the \ opposite \ edge \ over \ the \\ hypotenuse \ of \ a \ right \ triangle \ with \ angle \\ x \ in \ radians \end{array}\right)$

Note how I've written down the rule that defines the function sin.

$$f: \mathbf{R} \longrightarrow \mathbf{R}$$
 $f(x) = x^2$

Note that " x^2 " is sloppy (but common) notation for a function: it doesn't have a name!

You may be used to thinking of a function in terms of its graph.



The horizontal axis is the domain, and the vertical axis is the codomain.

This is fine when the domain and codomain are \mathbf{R} , but it's hard to do when they're \mathbf{R}^2 and \mathbf{R}^3 ! You need ____ dimensions to draw that graph.

Many of the functions you know and love have domain and codomain R.

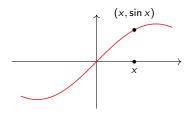
$$sin: \mathbf{R} \longrightarrow \mathbf{R}$$
 $sin(x) = \left(\begin{array}{c} the \ length \ of \ the \ opposite \ edge \ over \ the \\ hypotenuse \ of \ a \ right \ triangle \ with \ angle \\ x \ in \ radians \end{array}\right)$

Note how I've written down the rule that defines the function sin.

$$f: \mathbf{R} \longrightarrow \mathbf{R}$$
 $f(x) = x^2$

Note that " x^2 " is sloppy (but common) notation for a function: it doesn't have a name!

You may be used to thinking of a function in terms of its graph.



The horizontal axis is the domain, and the vertical axis is the codomain.

This is fine when the domain and codomain are \mathbf{R} , but it's hard to do when they're \mathbf{R}^2 and \mathbf{R}^3 ! You need five dimensions to draw that graph.

Most of the transformations we encounter in this class will come from (surprise) matrices!

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

In other words, T takes the vector x in \mathbf{R}^n to the vector Ax in \mathbf{R}^m .

► The *domain* of *T* is

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

In other words, T takes the vector x in \mathbf{R}^n to the vector Ax in \mathbf{R}^m .

▶ The *domain* of T is \mathbb{R}^n , which is the number of _____ of A.

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

In other words, T takes the vector x in \mathbf{R}^n to the vector Ax in \mathbf{R}^m .

▶ The *domain* of T is \mathbb{R}^n , which is the number of *columns* of A.

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

- ▶ The domain of T is \mathbb{R}^n , which is the number of columns of A.
- ► The *codomain* of *T* is

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

- ▶ The *domain* of T is \mathbb{R}^n , which is the number of *columns* of A.
- ▶ The *codomain* of T is \mathbb{R}^m , which is the number of ____ of A.

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

- ▶ The *domain* of T is \mathbb{R}^n , which is the number of *columns* of A.
- ▶ The *codomain* of T is \mathbb{R}^m , which is the number of *rows* of A.

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

In other words, T takes the vector x in \mathbf{R}^n to the vector Ax in \mathbf{R}^m .

- ► The domain of T is Rⁿ, which is the number of columns of A.
- ▶ The *codomain* of T is \mathbb{R}^m , which is the number of *rows* of A.
- ▶ The *range* of *T* is the set of all images of *T*:

$$T(x) = Ax = \begin{pmatrix} | & | & & | \\ v_1 & v_2 & \cdots & v_n \\ | & | & & | \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{pmatrix} = x_1v_1 + x_2v_2 + \cdots + x_nv_n.$$

This is the

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

In other words, T takes the vector x in \mathbf{R}^n to the vector Ax in \mathbf{R}^m .

- The domain of T is \mathbb{R}^n , which is the number of columns of A.
- ▶ The *codomain* of T is \mathbb{R}^m , which is the number of *rows* of A.
- ▶ The *range* of *T* is the set of all images of *T*:

$$T(x) = Ax = \begin{pmatrix} | & | & & | \\ v_1 & v_2 & \cdots & v_n \\ | & | & & | \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{pmatrix} = x_1v_1 + x_2v_2 + \cdots + x_nv_n.$$

This is the *column span* of A. It is a span of vectors in the codomain.

Most of the transformations we encounter in this class will come from (surprise) matrices!

Definition

Let A be an $m \times n$ matrix. The **matrix transformation** associated to A is the transformation

$$T: \mathbf{R}^n \longrightarrow \mathbf{R}^m$$
 defined by $T(x) = Ax$.

In other words, T takes the vector x in \mathbb{R}^n to the vector Ax in \mathbb{R}^m .

- ▶ The *domain* of T is \mathbb{R}^n , which is the number of *columns* of A.
- ▶ The *codomain* of T is \mathbb{R}^m , which is the number of *rows* of A.
- ▶ The *range* of *T* is the set of all images of *T*:

$$T(x) = Ax = \begin{pmatrix} | & | & & | \\ v_1 & v_2 & \cdots & v_n \\ | & | & & | \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{pmatrix} = x_1v_1 + x_2v_2 + \cdots + x_nv_n.$$

This is the column span of A. It is a span of vectors in the codomain.

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^{\perp} \to \mathbf{R}^{\perp}$.

Let
$$A=\begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x)=Ax$, so $T\colon \mathbf{R}^2\to \mathbf{R}^-$.

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^3$.

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^3$.

▶ If
$$u = \begin{pmatrix} 3 \\ 4 \end{pmatrix}$$
 then $T(u) =$

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbb{R}^2 \to \mathbb{R}^3$.

▶ If
$$u = \begin{pmatrix} 3 \\ 4 \end{pmatrix}$$
 then $T(u) =$

▶ Let
$$b = \begin{pmatrix} 7 \\ 5 \\ 7 \end{pmatrix}$$
. Find v in \mathbf{R} - such that $T(v) = b$.

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbb{R}^2 \to \mathbb{R}^3$.

▶ If
$$u = \begin{pmatrix} 3 \\ 4 \end{pmatrix}$$
 then $T(u) =$

▶ Let
$$b = \begin{pmatrix} 7 \\ 5 \\ 7 \end{pmatrix}$$
. Find v in \mathbb{R}^2 such that $T(v) = b$.

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^3$.

▶ If
$$u = \begin{pmatrix} 3 \\ 4 \end{pmatrix}$$
 then $T(u) =$

Let
$$b = \begin{pmatrix} 7 \\ 5 \\ 7 \end{pmatrix}$$
. Find v in \mathbf{R}^2 such that $T(v) = b$. Is there more than one?

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^3$.

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^3$.

▶ Is there any c in \mathbb{R}^3 such that there is more than one v in \mathbb{R}^2 with T(v) = c?

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^3$.

Is there any c in \mathbb{R}^3 such that there is more than one v in \mathbb{R}^2 with T(v)=c?

Translation: is there any c in \mathbb{R}^3 such that the solution set of Ax = c has more than one vector v in it?

Let
$$A=\begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x)=Ax$, so $T\colon \mathbf{R}^2\to \mathbf{R}^3$.

▶ Is there any c in \mathbb{R}^3 such that there is more than one v in \mathbb{R}^2 with T(v) = c?

Translation: is there any c in \mathbf{R}^3 such that the solution set of Ax = c has more than one vector v in it?

The solution set of Ax = c is a translate of the solution set of Ax = b (from before), which has vector in it.

Let
$$A=\begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x)=Ax$, so $T\colon \mathbf{R}^2\to \mathbf{R}^3$.

▶ Is there any c in \mathbb{R}^3 such that there is more than one v in \mathbb{R}^2 with T(v) = c?

Translation: is there any c in \mathbf{R}^3 such that the solution set of Ax = c has more than one vector v in it?

The solution set of Ax = c is a translate of the solution set of Ax = b (from before), which has one vector in it.

Example, continued

Let
$$A=\begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x)=Ax$, so $T\colon \mathbf{R}^2\to \mathbf{R}^3$.

▶ Is there any c in \mathbb{R}^3 such that there is more than one v in \mathbb{R}^2 with T(v) = c?

Translation: is there any c in \mathbb{R}^3 such that the solution set of Ax = c has more than one vector v in it?

The solution set of Ax = c is a translate of the solution set of Ax = b (from before), which has one vector in it. So the solution set to Ax = c has only one vector.

Example, continued

Let
$$A=\begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x)=Ax$, so $T\colon \mathbf{R}^2\to \mathbf{R}^3$.

▶ Is there any c in \mathbb{R}^3 such that there is more than one v in \mathbb{R}^2 with T(v) = c?

Translation: is there any c in \mathbb{R}^3 such that the solution set of Ax = c has more than one vector v in it?

The solution set of Ax = c is a translate of the solution set of Ax = b (from before), which has one vector in it. So the solution set to Ax = c has only one vector. So no!

Example, continued

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^3$.

▶ Is there any c in \mathbb{R}^3 such that there is more than one v in \mathbb{R}^2 with T(v) = c?

Translation: is there any c in \mathbf{R}^3 such that the solution set of Ax = c has more than one vector v in it?

The solution set of Ax = c is a translate of the solution set of Ax = b (from before), which has one vector in it. So the solution set to Ax = c has only one vector. So no!

Find c such that there is no v with T(v) = c.

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^3$.

Translation: is there any c in \mathbf{R}^3 such that the solution set of Ax = c has more than one vector v in it?

The solution set of Ax = c is a translate of the solution set of Ax = b (from before), which has one vector in it. So the solution set to Ax = c has only one vector. So no!

Find c such that there is no v with T(v) = c.

Translation: Find c such that Ax = c is inconsistent.

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^3$.

Translation: is there any c in \mathbf{R}^3 such that the solution set of Ax = c has more than one vector v in it?

The solution set of Ax = c is a translate of the solution set of Ax = b (from before), which has one vector in it. So the solution set to Ax = c has only one vector. So no!

Find c such that there is no v with T(v) = c.

Translation: Find c such that Ax = c is inconsistent.

Translation: Find c not in the column span of A (i.e., the range of T).

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbb{R}^2 \to \mathbb{R}^3$.

Translation: is there any c in \mathbb{R}^3 such that the solution set of Ax = c has more than one vector v in it?

The solution set of Ax = c is a translate of the solution set of Ax = b (from before), which has one vector in it. So the solution set to Ax = c has only one vector. So no!

Find c such that there is no v with T(v) = c.

Translation: Find c such that Ax = c is inconsistent.

Translation: Find c not in the column span of A (i.e., the range of T).

We could draw a picture, or notice:
$$a \begin{pmatrix} 1 \\ 0 \\ 1 \end{pmatrix} + b \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix} = \begin{pmatrix} a+b \\ b \\ a+b \end{pmatrix}$$
.

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbb{R}^2 \to \mathbb{R}^3$.

Translation: is there any c in \mathbf{R}^3 such that the solution set of Ax = c has more than one vector v in it?

The solution set of Ax = c is a translate of the solution set of Ax = b (from before), which has one vector in it. So the solution set to Ax = c has only one vector. So no!

Find c such that there is no v with T(v) = c.

Translation: Find c such that Ax = c is inconsistent.

Translation: Find c not in the column span of A (i.e., the range of T).

We could draw a picture, or notice: $a \begin{pmatrix} 1 \\ 0 \\ 1 \end{pmatrix} + b \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix} = \begin{pmatrix} a+b \\ b \\ a+b \end{pmatrix}$. So anything in the column span has the same first and last coordinate.

Example, continued

Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^3$.

▶ Is there any c in \mathbb{R}^3 such that there is more than one v in \mathbb{R}^2 with T(v) = c?

Translation: is there any c in \mathbf{R}^3 such that the solution set of Ax = c has more than one vector v in it?

The solution set of Ax = c is a translate of the solution set of Ax = b (from before), which has one vector in it. So the solution set to Ax = c has only one vector. So no!

Find c such that there is no v with T(v) = c.

Translation: Find c such that Ax = c is inconsistent.

Translation: Find c not in the column span of A (i.e., the range of T).

We could draw a picture, or notice:
$$a \begin{pmatrix} 1 \\ 0 \\ 1 \end{pmatrix} + b \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix} = \begin{pmatrix} a+b \\ b \\ a+b \end{pmatrix}$$
. So

anything in the column span has the same first and last coordinate. So $c=\binom{1}{2}$ is not in the column span (for example).

Let
$$A = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^{\perp} \to \mathbf{R}^{\perp}$.

Let
$$A = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^3 \to \mathbf{R}^3$.

Let
$$A = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T : \mathbb{R}^3 \to \mathbb{R}^3$. Then

$$T\begin{pmatrix} x \\ y \\ z \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{pmatrix} \begin{pmatrix} x \\ y \\ z \end{pmatrix} = \begin{pmatrix} x \\ y \\ 0 \end{pmatrix}.$$

Let
$$A = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T : \mathbb{R}^3 \to \mathbb{R}^3$. Then

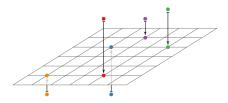
$$T\begin{pmatrix} x \\ y \\ z \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{pmatrix} \begin{pmatrix} x \\ y \\ z \end{pmatrix} = \begin{pmatrix} x \\ y \\ 0 \end{pmatrix}.$$

This is

Geometric example

Let
$$A = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T : \mathbf{R}^3 \to \mathbf{R}^3$. Then
$$T \begin{pmatrix} x \\ y \\ z \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{pmatrix} \begin{pmatrix} x \\ y \\ z \end{pmatrix} = \begin{pmatrix} x \\ y \\ 0 \end{pmatrix}.$$

This is projection onto the xy-axis. Picture:



Let
$$A = \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^{\perp} \to \mathbf{R}^{\perp}$.

Let
$$A = \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^2$.

Let
$$A = \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T : \mathbf{R}^2 \to \mathbf{R}^2$. Then
$$T \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix} \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -x \\ y \end{pmatrix}.$$

Let
$$A = \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T : \mathbb{R}^2 \to \mathbb{R}^2$. Then

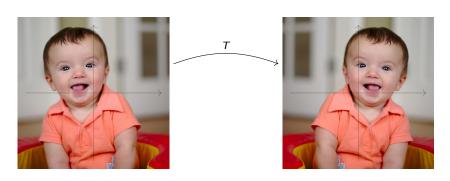
$$T\begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix} \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -x \\ y \end{pmatrix}.$$

This is

Geometric example

Let
$$A = \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T : \mathbf{R}^2 \to \mathbf{R}^2$. Then
$$T \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix} \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -x \\ y \end{pmatrix}.$$

This is reflection over the y-axis. Picture:

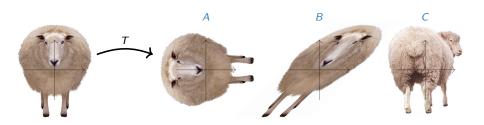


Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^2$. (T is called a **shear**.)

Poll

What does T do to this sheep?

Hint: first draw a picture what it does to the box *around* the sheep.

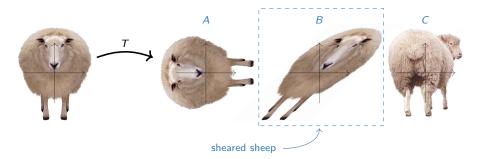


Let
$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \end{pmatrix}$$
 and let $T(x) = Ax$, so $T \colon \mathbf{R}^2 \to \mathbf{R}^2$. (T is called a **shear**.)

Poll

What does T do to this sheep?

Hint: first draw a picture what it does to the box *around* the sheep.



Linear Transformations

Recall: If A is a matrix, u, v are vectors, and c is a scalar, then

$$A(u+v) = Au + Av$$
 $A(cv) = cAv$.

Linear Transformations

Recall: If A is a matrix, u, v are vectors, and c is a scalar, then

$$A(u+v) = Au + Av$$
 $A(cv) = cAv$.

So if T(x) = Ax is a matrix transformation then,

$$T(u+v) = T(u) + T(v)$$
 $T(cv) = cT(v)$.

Recall: If A is a matrix, u, v are vectors, and c is a scalar, then

$$A(u+v) = Au + Av$$
 $A(cv) = cAv$.

So if T(x) = Ax is a matrix transformation then,

$$T(u+v) = T(u) + T(v)$$
 $T(cv) = cT(v)$.

This property is so special that it has its own name.

Recall: If A is a matrix, u, v are vectors, and c is a scalar, then

$$A(u+v) = Au + Av$$
 $A(cv) = cAv$.

So if T(x) = Ax is a matrix transformation then,

$$T(u+v) = T(u) + T(v)$$
 $T(cv) = cT(v)$.

This property is so special that it has its own name.

Definition

A transformation $T: \mathbf{R}^n \to \mathbf{R}^m$ is **linear** if it satisfies the above equations for all vectors u, v in \mathbf{R}^n and all scalars c.

Recall: If A is a matrix, u, v are vectors, and c is a scalar, then

$$A(u+v) = Au + Av$$
 $A(cv) = cAv$.

So if T(x) = Ax is a matrix transformation then,

$$T(u+v) = T(u) + T(v)$$
 $T(cv) = cT(v)$.

This property is so special that it has its own name.

Definition

A transformation $T: \mathbf{R}^n \to \mathbf{R}^m$ is **linear** if it satisfies the above equations for all vectors u, v in \mathbf{R}^n and all scalars c.

In other words, T "respects" addition and scalar multiplication.

Recall: If A is a matrix, u, v are vectors, and c is a scalar, then

$$A(u+v) = Au + Av$$
 $A(cv) = cAv$.

So if T(x) = Ax is a matrix transformation then,

$$T(u+v) = T(u) + T(v)$$
 $T(cv) = cT(v)$.

This property is so special that it has its own name.

Definition

A transformation $T \colon \mathbf{R}^n \to \mathbf{R}^m$ is **linear** if it satisfies the above equations for all vectors u, v in \mathbf{R}^n and all scalars c.

In other words, T "respects" addition and scalar multiplication.

Check: if T is linear, then

$$T(0) = 0 T(cu + dv) = cT(u) + dT(v)$$

for all vectors u, v and scalars c, d.

Recall: If A is a matrix, u, v are vectors, and c is a scalar, then

$$A(u+v) = Au + Av$$
 $A(cv) = cAv$.

So if T(x) = Ax is a matrix transformation then,

$$T(u+v) = T(u) + T(v)$$
 $T(cv) = cT(v)$.

This property is so special that it has its own name.

Definition

A transformation $T \colon \mathbf{R}^n \to \mathbf{R}^m$ is **linear** if it satisfies the above equations for all vectors u, v in \mathbf{R}^n and all scalars c.

In other words, T "respects" addition and scalar multiplication.

Check: if T is linear, then

$$T(0) = 0 T(cu + dv) = cT(u) + dT(v)$$

for all vectors u, v and scalars c, d. More generally,

$$T\big(c_1v_1+c_2v_2+\cdots+c_nv_n\big)=c_1T(v_1)+c_2T(v_2)+\cdots+c_nT(v_n).$$

Recall: If A is a matrix, u, v are vectors, and c is a scalar, then

$$A(u+v) = Au + Av$$
 $A(cv) = cAv$.

So if T(x) = Ax is a matrix transformation then,

$$T(u+v) = T(u) + T(v)$$
 $T(cv) = cT(v)$.

This property is so special that it has its own name.

Definition

A transformation $T \colon \mathbf{R}^n \to \mathbf{R}^m$ is **linear** if it satisfies the above equations for all vectors u, v in \mathbf{R}^n and all scalars c.

In other words, T "respects" addition and scalar multiplication.

Check: if T is linear, then

$$T(0) = 0 T(cu + dv) = cT(u) + dT(v)$$

for all vectors u, v and scalars c, d. More generally,

$$T(c_1v_1 + c_2v_2 + \cdots + c_nv_n) = c_1T(v_1) + c_2T(v_2) + \cdots + c_nT(v_n).$$

In engineering this is called **superposition**.

Define $T: \mathbf{R}^2 \to \mathbf{R}^2$ by T(x) = 1.5x. Is T linear? Check:

Define $T \colon \mathbf{R}^2 \to \mathbf{R}^2$ by T(x) = 1.5x. Is T linear? Check:

$$T(u+v) =$$
$$T(cv) =$$

Define $T \colon \mathbf{R}^2 \to \mathbf{R}^2$ by T(x) = 1.5x. Is T linear? Check:

$$T(u+v) =$$
$$T(cv) =$$

So ${\cal T}$ satisfies the two equations, hence ${\cal T}$ is linear.

Define $T: \mathbf{R}^2 \to \mathbf{R}^2$ by T(x) = 1.5x. Is T linear? Check:

$$T(u+v) = T(cv) =$$

So T satisfies the two equations, hence T is linear.

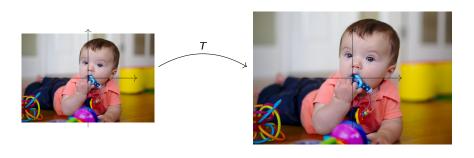
This is called **dilation** or **scaling** (by a factor of 1.5). Picture:

Define $T: \mathbf{R}^2 \to \mathbf{R}^2$ by T(x) = 1.5x. Is T linear? Check:

$$T(u+v) =$$
$$T(cv) =$$

So T satisfies the two equations, hence T is linear.

This is called dilation or scaling (by a factor of 1.5). Picture:



Linear Transformations Rotation

Define $\mathcal{T}\colon \mathbf{R}^2 \to \mathbf{R}^2$ by

$$T\begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -y \\ x \end{pmatrix}.$$

Is T linear? Check:

Linear Transformations Rotation

Define $T \colon \mathbf{R}^2 \to \mathbf{R}^2$ by

$$T \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -y \\ x \end{pmatrix}.$$

Is T linear? Check:

$$T\left(\begin{pmatrix} u_1 \\ u_2 \end{pmatrix} + \begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) =$$

$$T\left(c\begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) =$$

Linear Transformations Rotation

Define $T\colon \mathbf{R}^2 \to \mathbf{R}^2$ by

$$T \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -y \\ x \end{pmatrix}.$$

Is T linear? Check:

$$T\left(\begin{pmatrix} u_1 \\ u_2 \end{pmatrix} + \begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) =$$

$$T\left(c\begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) =$$

So ${\cal T}$ satisfies the two equations, hence ${\cal T}$ is linear.

Define $T\colon \mathbf{R}^2 \to \mathbf{R}^2$ by

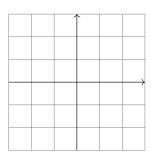
$$T \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -y \\ x \end{pmatrix}.$$

Is T linear? Check:

$$T\left(\begin{pmatrix} u_1 \\ u_2 \end{pmatrix} + \begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) =$$

$$T\left(c\begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) =$$

So T satisfies the two equations, hence T is linear. This is called **rotation** (by 90°). Picture:



Define $T \colon \mathbf{R}^2 \to \mathbf{R}^2$ by

$$T \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -y \\ x \end{pmatrix}.$$

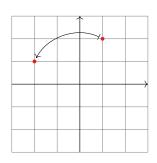
Is T linear? Check:

$$T\left(\begin{pmatrix} u_1 \\ u_2 \end{pmatrix} + \begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) =$$

$$T\left(c\begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) =$$

So T satisfies the two equations, hence T is linear. This is called **rotation** (by 90°). Picture:

$$T\begin{pmatrix}1\\2\end{pmatrix}=\begin{pmatrix}-2\\1\end{pmatrix}$$



Define $T \colon \mathbf{R}^2 \to \mathbf{R}^2$ by

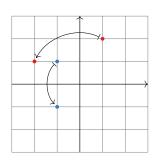
$$T\begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -y \\ x \end{pmatrix}.$$

Is T linear? Check:

$$\begin{split} T\left(\begin{pmatrix} u_1 \\ u_2 \end{pmatrix} + \begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) &= \\ T\left(c\begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) &= \end{split}$$

So T satisfies the two equations, hence T is linear. This is called **rotation** (by 90°). Picture:

$$T \begin{pmatrix} 1 \\ 2 \end{pmatrix} = \begin{pmatrix} -2 \\ 1 \end{pmatrix}$$
$$T \begin{pmatrix} -1 \\ 1 \end{pmatrix} = \begin{pmatrix} -1 \\ -1 \end{pmatrix}$$



Define $T\colon \mathbf{R}^2 \to \mathbf{R}^2$ by

$$T \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} -y \\ x \end{pmatrix}.$$

Is T linear? Check:

$$\begin{split} T\left(\begin{pmatrix} u_1 \\ u_2 \end{pmatrix} + \begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) &= \\ T\left(c\begin{pmatrix} v_1 \\ v_2 \end{pmatrix}\right) &= \end{split}$$

So T satisfies the two equations, hence T is linear. This is called **rotation** (by 90°). Picture:

$$T \begin{pmatrix} 1 \\ 2 \end{pmatrix} = \begin{pmatrix} -2 \\ 1 \end{pmatrix}$$
$$T \begin{pmatrix} -1 \\ 1 \end{pmatrix} = \begin{pmatrix} -1 \\ -1 \end{pmatrix}$$
$$T \begin{pmatrix} 0 \\ -2 \end{pmatrix} = \begin{pmatrix} 2 \\ 0 \end{pmatrix}$$

