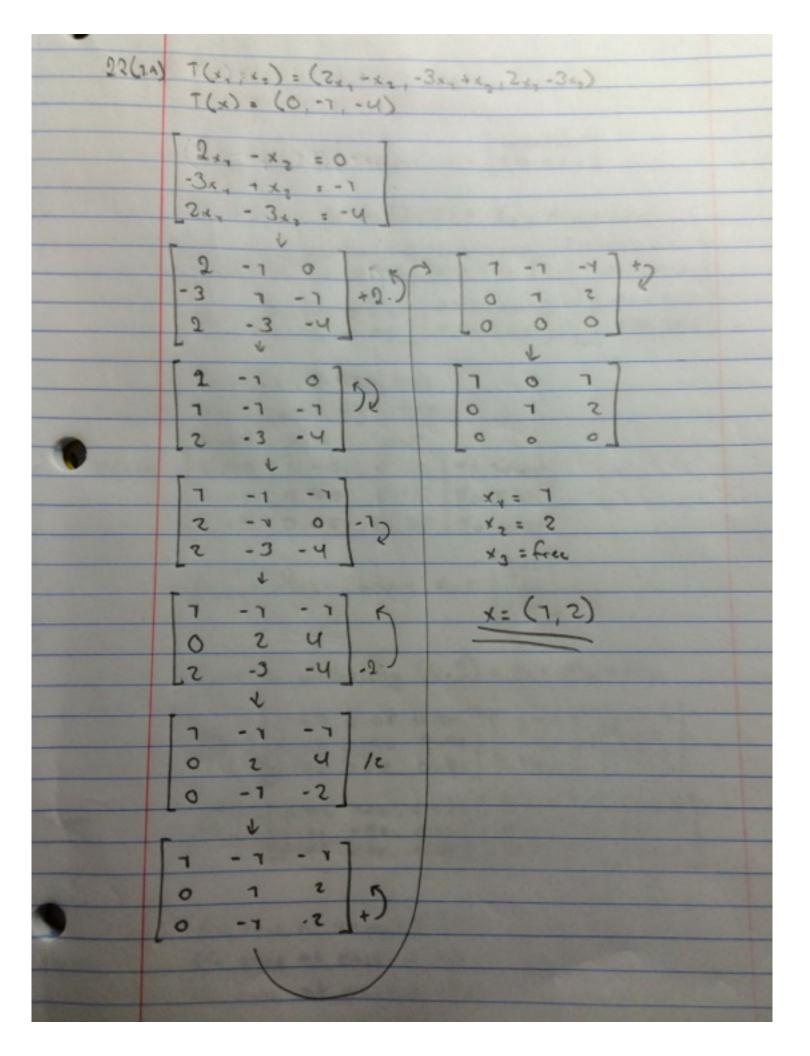
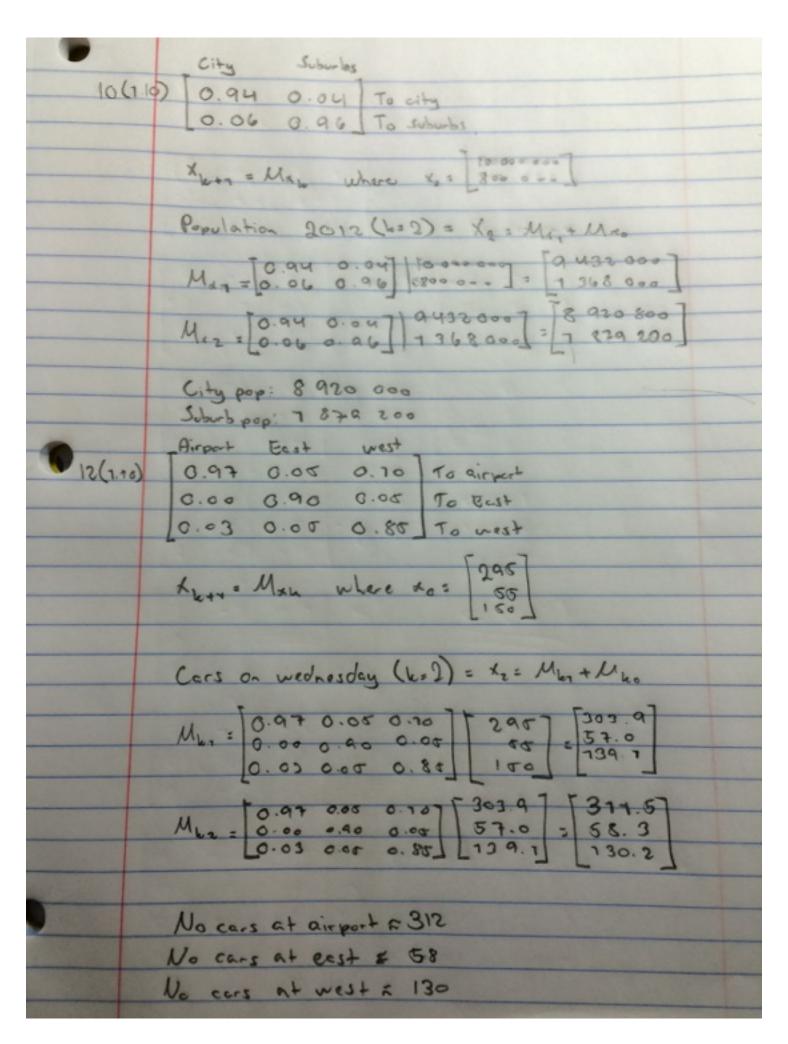


20 (1.8)	T(x) = x, V, + x, V2 = [V, V2] [1]
	-3 7 7 × = Ax
	$A = \begin{bmatrix} -3 & 7 \\ 5 & -2 \end{bmatrix}$
	7- [3 -2]
	10 41

2(1.9) [T(e,) T(e,) T(e,)] 4(1.9) T(e) = [7] T(ez) = Cz + 2en = [] + 2 [] = [[en(e)]=[1 2] 6 (1.9) sotate [] gives] >T(e) rotate of sives [-1] > [t(an) T(en)]

14 (7.9) Wat 18(10) T(x, x,) = (x, + 42, 0, x, -32, x,) T(x, x2, x2, x4) = (3x, +4x, -2x4) 20(1.9) +(x)= 34+ 0x+ 4xy -2x4=





```
In [1]: migrationMatrix = np.array([[0.94, 0.04], [0.06, 0.96]])
In [2]: migrationMatrix
Out[2]:
array([[ 0.94, 0.04],
       [ 0.06, 0.96]])
In [3]: populationMatrix0 = np.array([10000000, 800000])
In [4]: populationMatrix0
Out[4]: array([10000000, 800000])
In [7]: AxIP(migrationMatrix, populationMatrix0)
Out[7]: array([ 9432000., 1368000.])
In [8]: populationMatrix1 = AxIP(migrationMatrix, populationMatrix0)
In [9]: AxIP(migrationMatrix, populationMatrix1)
Out[9]: array([ 8920800., 1879200.])
See previous page for explanation of results. Should be pretty self explanatory.
In [11]: deliveryMatrix = np.array([[0.97, 0.05, 0.10], [0.00, 0.90, 0.05],
[0.03, 0.05, 0.85]])
In [12]: deliveryMatrix
Out[12]:
array([[ 0.97, 0.05, 0.1 ],
       [ 0. , 0.9 , 0.05],
       [ 0.03, 0.05, 0.85]])
In [13]: carMatrix0 = np.array([295.0, 55.0, 150.0])
In [14]: carMatrix0
Out[14]: array([ 295., 55., 150.])
In [15]: AxIP(deliveryMatrix, carMatrix0)
Out[15]: array([ 303.9, 57. , 139.1])
In [16]: carMatrix1 = AxIP(deliveryMatrix, carMatrix0)
In [17]: AxIP(deliveryMatrix, carMatrix1)
Out[17]: array([ 311.543, 58.255, 130.202])
```