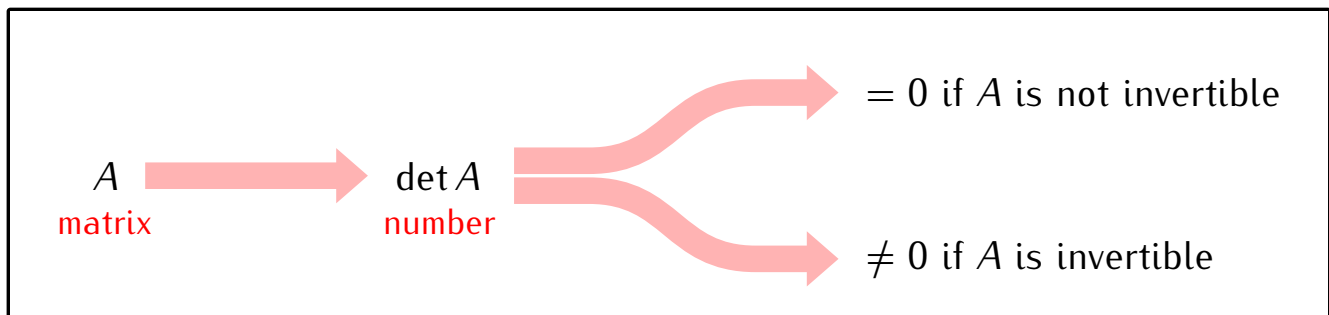
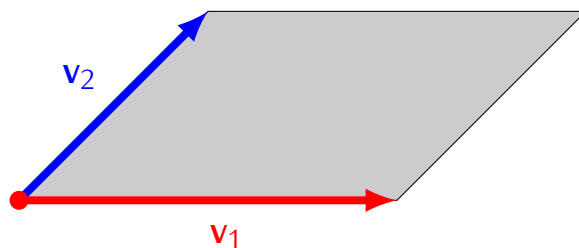


Recall:



Note. Any two vectors in \mathbb{R}^2 define a parallelogram:



Notation

$$\text{area}(v_1, v_2) = \left(\begin{array}{l} \text{area of the parallelogram} \\ \text{defined by } v_1 \text{ and } v_2 \end{array} \right)$$

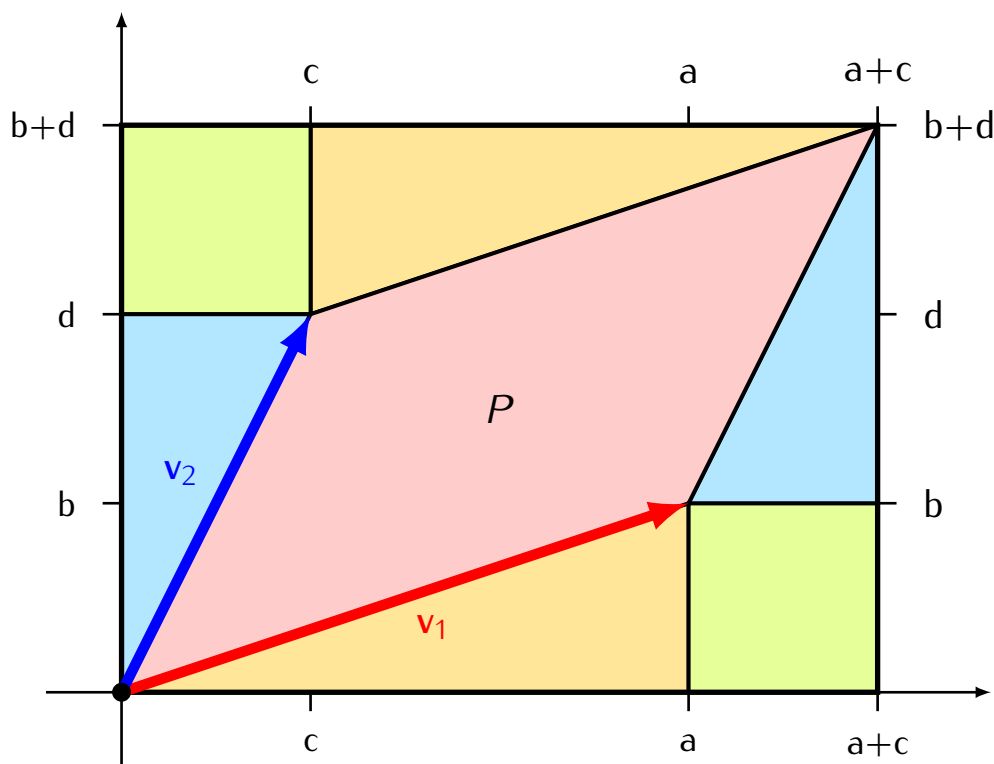
Theorem

If $\mathbf{v}_1, \mathbf{v}_2 \in \mathbb{R}^2$ then

$$\text{area}(\mathbf{v}_1, \mathbf{v}_2) = \left| \det \begin{bmatrix} \mathbf{v}_1 & \mathbf{v}_2 \end{bmatrix} \right|$$

Idea of the proof.

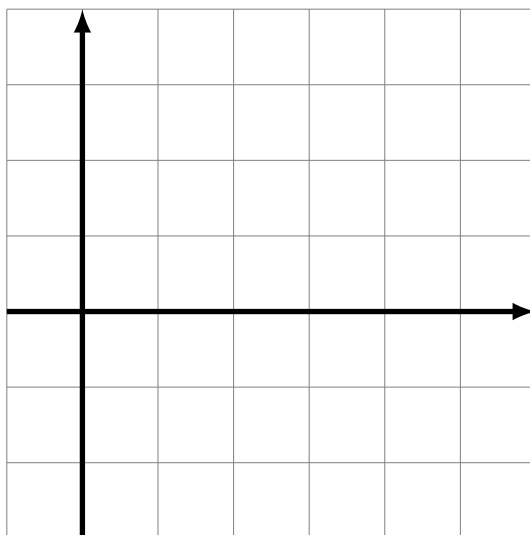
$$\mathbf{v}_1 = \begin{bmatrix} a \\ b \end{bmatrix}, \quad \mathbf{v}_2 = \begin{bmatrix} c \\ d \end{bmatrix}$$



$$\begin{aligned}
 & \text{area}(P) \\
 & + \frac{1}{2}ab \\
 & + \frac{1}{2}ab \\
 & + \frac{1}{2}cd \\
 & + \frac{1}{2}cd \\
 & + cb \\
 & + cb \\
 & \hline
 & (a+c)(b+d)
 \end{aligned}$$

Example.

$$\mathbf{v}_1 = \begin{bmatrix} 2 \\ 3 \end{bmatrix}, \quad \mathbf{v}_2 = \begin{bmatrix} 2 \\ -2 \end{bmatrix}$$

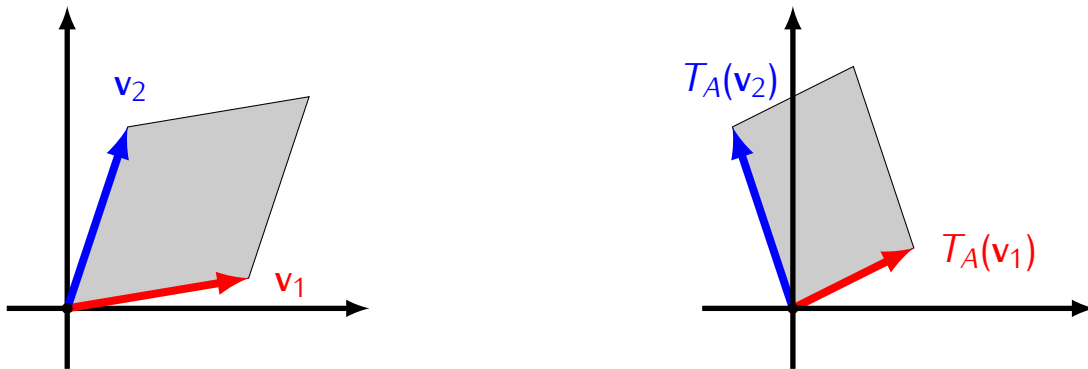


Determinants and linear transformations

Recall: If A is a 2×2 matrix then it defines a linear transformation

$$T_A: \mathbb{R}^2 \rightarrow \mathbb{R}^2 \quad T_A(\mathbf{v}) = A\mathbf{v}$$

Note. T_A maps parallelograms to parallelograms:



Theorem

If A is a 2×2 matrix and $\mathbf{v}_1, \mathbf{v}_2 \in \mathbb{R}^2$ then

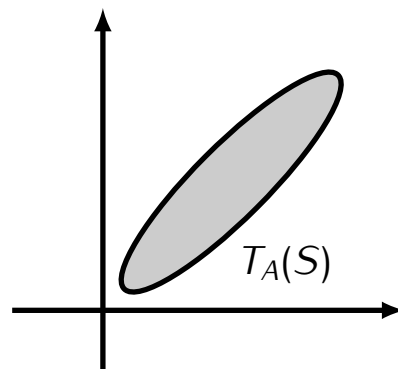
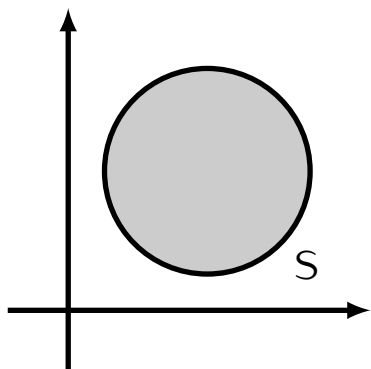
$$\text{area}(T_A(\mathbf{v}_1), T_A(\mathbf{v}_2)) = |\det A| \cdot \text{area}(\mathbf{v}_1, \mathbf{v}_2)$$

Generalization:

Theorem

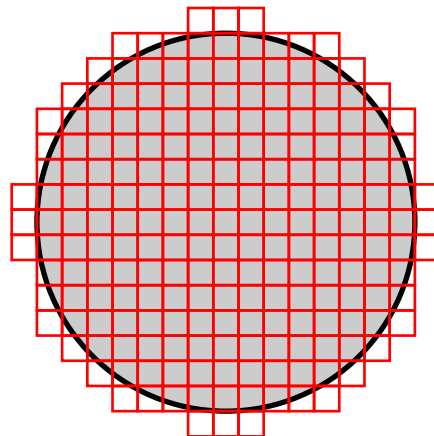
If A is a 2×2 matrix then for any region S of \mathbb{R}^2 we have:

$$\text{area}(T_A(S)) = |\det A| \cdot \text{area}(S)$$



Idea of the proof.

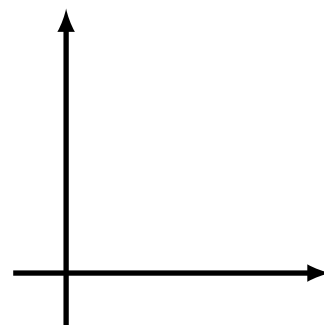
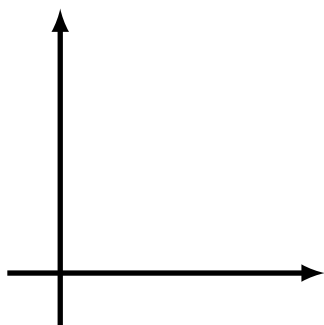
The area of S can be approximated by the sum of small squares covering S .



Sign of the determinant

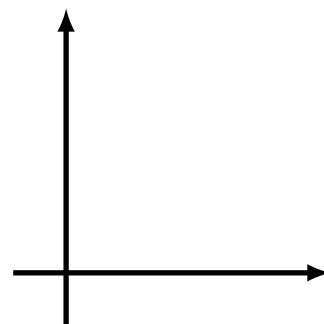
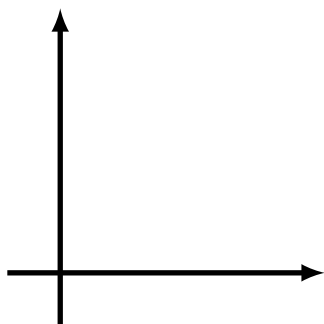
Example.

$$A = \begin{bmatrix} 2 & 1 \\ 1 & 3 \end{bmatrix}$$



Example.

$$A = \begin{bmatrix} 2 & 3 \\ 2 & 1 \end{bmatrix}$$



Theorem

If A is a 2×2 matrix then the linear transformation $T_A: \mathbb{R}^2 \rightarrow \mathbb{R}^2$ preserves orientation if $\det A > 0$ and reverses orientation if $\det A < 0$.