

subject

Linear Algebra

date

6 March 2024

keywords

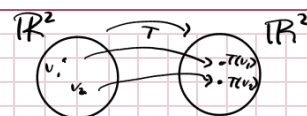
Matrix Representation
Coordinate Vectors

topic

The Day of Cookies (Also 35 More Matrix Stuff)

Example

$$T: \mathbb{R}^2 \rightarrow \mathbb{R} \text{ via } \begin{bmatrix} x \\ y \end{bmatrix} \mapsto \begin{bmatrix} x+2y \\ y-3x \end{bmatrix}$$



$$\begin{aligned} \text{Note: } T\left(\begin{bmatrix} x \\ y \end{bmatrix}\right) &= T(x\begin{bmatrix} 1 \\ 0 \end{bmatrix} + y\begin{bmatrix} 0 \\ 1 \end{bmatrix}) = xT\left(\begin{bmatrix} 1 \\ 0 \end{bmatrix}\right) + yT\left(\begin{bmatrix} 0 \\ 1 \end{bmatrix}\right) \\ &= \begin{bmatrix} T\left(\begin{bmatrix} 1 \\ 0 \end{bmatrix}\right) & T\left(\begin{bmatrix} 0 \\ 1 \end{bmatrix}\right) \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix} = A\vec{x} \\ \rightarrow A &= \begin{bmatrix} T\left(\begin{bmatrix} 1 \\ 0 \end{bmatrix}\right) & T\left(\begin{bmatrix} 0 \\ 1 \end{bmatrix}\right) \end{bmatrix} \in \mathcal{M}_{2 \times 2} \\ A &= \begin{bmatrix} 1 & 2 \\ -3 & 1 \end{bmatrix} \end{aligned}$$

The Fundamental Theorem of Linear Algebra:
Every linear transformation has an associated matrix representation.

Example Continued

$$\mathcal{B} = \left\{ \begin{bmatrix} 1 \\ 3 \end{bmatrix}, \begin{bmatrix} -1 \\ 1 \end{bmatrix} \right\} \subseteq \mathbb{R}^2$$

$$\begin{aligned} \text{But also } T\left(\begin{bmatrix} x \\ y \end{bmatrix}\right) &= T(a\vec{b}_1 + b\vec{b}_2) \\ &= \dots = \begin{bmatrix} T(\vec{b}_1) & T(\vec{b}_2) \end{bmatrix} \begin{bmatrix} a \\ b \end{bmatrix} \\ &= \begin{bmatrix} 3 & -1 \\ -2 & 1 \end{bmatrix} \begin{bmatrix} a \\ b \end{bmatrix} \\ &= A \begin{bmatrix} x \\ y \end{bmatrix}_{\mathcal{B}} \\ &\quad \uparrow \\ &\quad A \text{ depends on the basis used} \end{aligned}$$

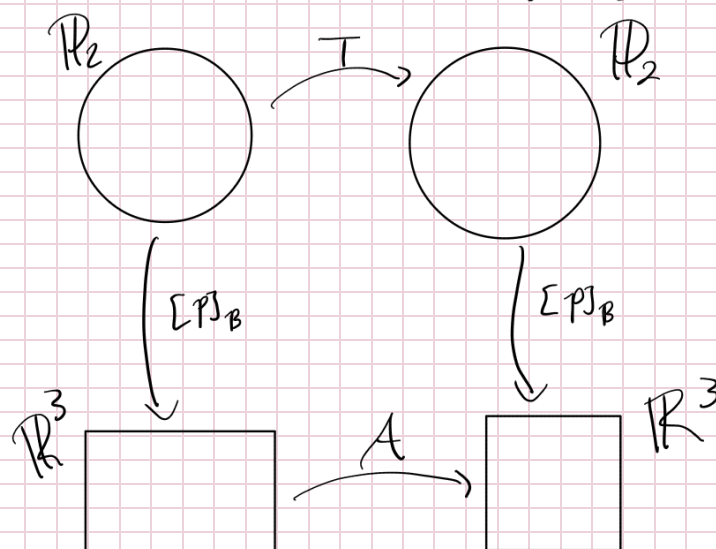
Example 2

$$T: \mathbb{P}_2 \rightarrow \mathbb{P}_2 \text{ via } ax^2 + bx + c \mapsto (2c-b)x^2 + (a-b)$$

$$T(ax^2 + bx + c) = aT(x^2) + bT(x) + cT(1)$$

Not column vectors!

Where We're Heading
to be continued...



$$\mathcal{B} = \{\vec{b}_1, \vec{b}_2, \vec{b}_3\}$$

basis for domain and codomain

$$A = \begin{bmatrix} [T(\vec{b}_1)]_{\mathcal{B}} & \dots & [T(\vec{b}_3)]_{\mathcal{B}} \end{bmatrix}$$