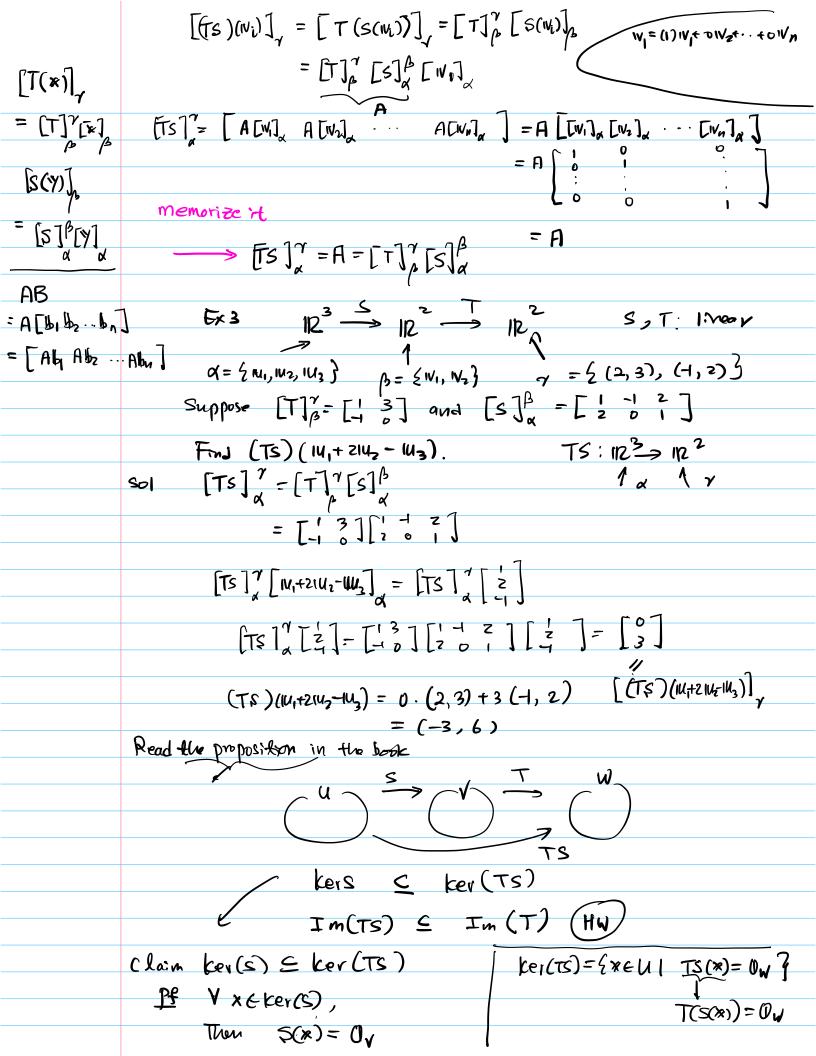
```
Let U, V and W be real vector spaces
                               Let S: U → V and T: V → W be livear transformation
                               Then TS is a linear transformation from U to W
              (TS)(*)
             = T(s(*))
                        \underbrace{\text{Pf}} \quad \forall \quad \text{IM}_1, \, \text{IM}_2 \in \mathcal{U} \quad (TS)(\text{IM}_1 + \text{IM}_2) = T(S(\text{IM}_1 + \text{IM}_2)) = T(S(\text{IM}_1) + S(\text{IM}_2))
                                                                  T(\xi(u_1)) + T(\xi(u_2)) = (Ts)(u_1) + (Ts)(u_1)
                               Hus show that YINGU, YKER, (TS )(HIN) = K(TS)(IN)
                                   3 $ 1124 T 1R2
                       EXI \mathbb{R} \xrightarrow{\longrightarrow} \mathbb{R}^2 \longrightarrow \mathbb{R}^2

S(x_1, x_2, x_3) = (x_1 + x_2, x_1 - x_2, x_3, x_1 + x_3)
                              T(x_1, x_2, x_3, x_4) = (x_1 - x_4, x_2 + x_3)
Find (TS)
               Zeview
              of MATER3
                         \underline{S_{D}}I = \left(TS\right)(x_{1}, x_{2}, x_{3}) = T\left(s(x_{1}, x_{2}, x_{3})\right) = T\left(x_{1} + x_{2}, x_{1} - x_{2}, x_{1} + x_{3}\right)
                                                   z = ((\chi_1 + \chi_2) - (\chi_1 + \chi_2), (\chi_1 - \chi_2) + \chi_3)
                                                   = (x2-x3, x,-x2+x3)
                                   [TS] = [T][S] = \begin{bmatrix} 0 & 0 & -1 \end{bmatrix} \begin{bmatrix} 0 & -1 & 0 \\ 0 & 1 & 0 \end{bmatrix} = \begin{bmatrix} 0 & 1 & -1 \\ 1 & -1 & 1 \end{bmatrix}
             Remark:
                                  (TS)(\lambda_1, \lambda_2, \lambda_3) = \begin{bmatrix} 0 & 1 & -1 \\ 1 & -1 & 1 \end{bmatrix} \begin{bmatrix} \chi_1 \\ \chi_2 \\ \chi_3 \end{bmatrix} = (\chi_2 - \chi_3, \chi_1 - \chi_2 + \chi_3) 
                            S: Pz(IR) > Pi(IR) defined by S(p(x) = p'(x)
            Gx2
                            T: P_1(m) \rightarrow P_2(m) " by T(p(x)) = x p(x)
                        EMJ TS
              SOI & PLAN & PECIE), (TE)(P(X))= T(S(P(X)) = T(p'(X)) = xp'(X)
Theorem Let &, B and & be bases for U, V and W respectively
                                                                                       S, T: linear transformation
                                        U \xrightarrow{S} V \xrightarrow{T} W
TS : U \xrightarrow{} W
                         [TS]_{\alpha}^{\gamma} = [T]_{\beta}^{\gamma} [S]_{\alpha}^{\beta}
                         Suy & = { W1, ... Wn} [TS] = [(TS)(N1)] ... [(TS)(W1)] ... [(TS)(Wn)]
          (H)
```

4025 Composition of Linear Transform.



 $T(S(x))=T(OV)=OW \Rightarrow x \in \ker(TS)$