



## Why

When is a linear transformation between  $V$  and  $W$  one-to-one? In other words, when does

$$Tx = Ty \Rightarrow x = y$$

Rearranging, and using additivity, we ask when

$$T(x - y) = 0 \Rightarrow x - y = 0$$

Clearly we are interested in vectors  $z$  for which  $Tz = 0$ .

## Definition

Suppose  $T \in \mathcal{L}(V, W)$ . The *null space* (or *kernel*) of  $T$  is the set of vectors in  $V$  which are mapped to 0 under  $T$ . In symbols, the null space of  $T$  is the set

$$T = \{v \in V \mid Tv = 0\}$$

The word “null” means “zero” in German.

## A subspace

Why use the term *space*? Well,  $T$  is a *subspace* of  $V$ .

**Proposition 1.** *Suppose  $T \in \mathcal{L}(V, W)$ . Then  $(T)$  is a subspace of  $V$ .*

*Proof.* We verify that  $(T)$  contains 0 and is closed under vector addition and scalar multiplication. First,  $0 \in T$  since  $T0 = 0$  by homogeneity. Second, by additivity, if  $x, y \in T$ , then

$$T(x + y) = Tx + Ty = 0 + 0 = 0$$

Third, if  $u \in T$  and  $\alpha \in \mathbf{F}$ , then

$$T(\lambda u) = \lambda(Tu) = \lambda 0 = 0$$

□

## Characterization of injectivity

**Proposition 2.** *Suppose  $T \in \mathcal{L}(V, W)$ . Then*

$$T = \{0\} \longleftrightarrow T \text{ is one-to-one}$$

If  $T = \{0\}$  we say that  $T$  has *zero nullspace* or *trivial nullspace*.

## Examples

*Zero map.* Suppose  $T$  is the zero map from  $V$  to  $W$ . In other words,

$$Tv = 0 \quad \text{for all } v \in V$$

Then  $T = \{0\}$ . I.e., the null space is the whole space.

*Simple function on  $\mathbf{C}^3$ .* Define  $\phi \in \mathcal{L}(\mathbf{C}^3, \mathbf{C})$  by

$$\phi(z_1, z_2, z_3) = z_1 + 2z_2 + 3z_3$$

Then  $\phi$  is

$$\{(z_1, z_2, z_3) \in \mathbf{C}^3 \mid z_1 + 2z_2 + 3z_3 = 0\}$$

This is the *solution set* of a linear equation.

*Polynomial differentiation.* Suppose  $D \in \mathcal{L}(\mathcal{P}(\mathbf{R}), \mathcal{P}(\mathbf{R}))$  is the linear map defined by

$$Dp = p' \quad \text{for all } p \in \mathcal{P}(\mathbf{R})$$

In other words,  $Dp$  is the derivative of the polynomial  $p$ . Then  $(D)$  is the set of constant functions.

*Multiplication by  $x^2$ .* Define  $T \in \mathcal{L}(\mathcal{P}(\mathbf{R}), \mathcal{P}(\mathbf{R}))$  by

$$(Tp)(x) = x^2p(x) \quad \text{for all } x \in \mathbf{R} \text{ and } p \in \mathcal{P}(\mathbf{R})$$

Then  $(T) = \{0\}$ , since no other polynomial satisfies  $x^2p(x) = 0$  for all  $x \in \mathbf{R}$ .

*Backward shift.* Define  $T \in \mathcal{L}(\mathbf{F}^{\mathbf{N}}, \mathbf{F}^{\mathbf{N}})$  by

$$T(x_1, x_2, x_3, \dots) = (x_2, x_3, \dots)$$

so that  $T$  is the backward shift. Then  $T(x_1, x_2, x_3, \dots) = 0$  if and only if  $x_2 = x_3 = \dots = 0$ . So

$$T = \{(\alpha, 0, 0, \dots) \mid \alpha \in \mathbf{F}\}$$



