Recall that a tunction f is a rule that assigns to each element in a set A one and only one element in a set B. If f assigns the value to to the element a in A, we write

and call b the image of a under f.

The set A is the domain of definition of f (even if IA is not a domain in the sense of chapter 1), and the set of all images f(a) is the range of f.

We sometimes refer to fas a mapping of A into B.

We will concern ourselves with complex-valued tunctions of a complex variable, so that the domains of definition and the ranges are subsets of the complex numbers.

Sory 
$$f(z) = \frac{z^2 - 1}{z^2 + 1}$$

then, unless stated otherwise, we take the domain of f to be the set of all 7 for which the formula is well-defined.

If  $\omega$  denotes the value of the function f at the point z, we then write  $\omega = f(z)$ .

Just as Z decomposes into

Z = x + iy (real + imaginary part)

the real + imaginary parts of w are each (real-valued)

the real + imaginary parts of w are each (real-valued functions of z or, equivalently, of x and y, and so we customarily write

with u,v denoting the real + imaginary parts, respectively, of w.

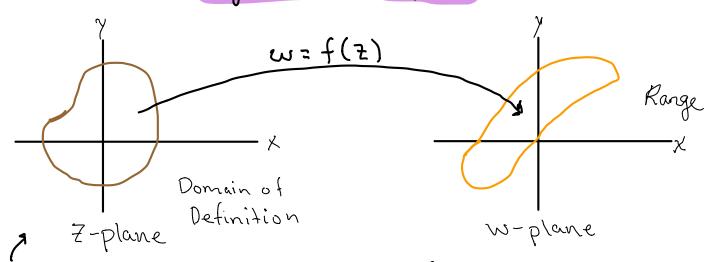
Thus a complex-valued function of a complex variable is, in essence, a pair of real functions of two variables.

Example 1. Write  $\omega = f(z) = z^2 + 2z$  in the form  $\omega = u(x,y) + i v(x,y)$ Setting z = x + i y,  $\omega = f(z) = (x + i y)^2 + 2(x + i y)$   $\omega = (x^2 - y^2 + i 2xy + 2x + i 2y)$  $\omega = (x^2 - y^2 + 2x) + i (2xy + 2y)$ 

Unfortunately, it is generally impossible to draw the graph of a complex function; to display two real functions of two real variables graphically would require tour dimensions.

We can visualize some of the properties of a complex function

by sketching its dornain of definition in the zplane and its rounge in the w-plane.



Representation of a complex function

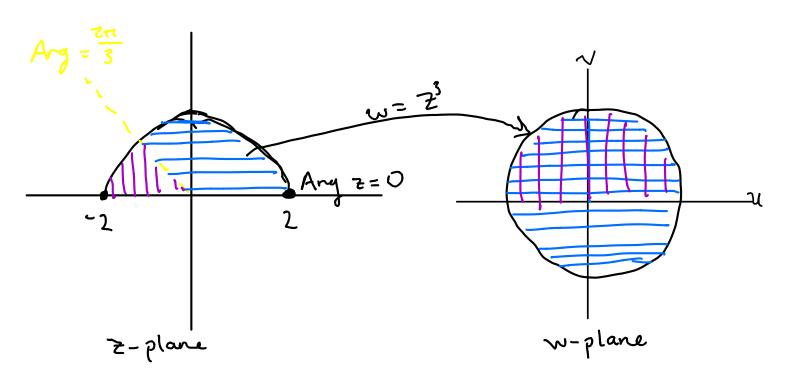
Example 2: Describe the range of the function f(z) = x2 + 2i defined on the closed unit disk

We have

We have 
$$U(x,y) = x^2$$
  $V(x,y) = 2$   
Thus as  $z$  varies over the closed unit disk,  $u$  varies between 0 and 1, and  $v$  is constant.

The range is therefore the line segment from  $\omega = 0 + 2i$  to  $\omega = (+2i)$ 

**Example 3:** Describe the function  $f(z) = Z^3$  for z in the semidesk given by  $|z| \le 2$ , Im  $Z^2$ 0 (figure below)



The points z in the sector of the semidisk from Arg z=0 to Arg z=2<sup>n</sup>/3, when cubed, ower the entire disk lw1 = 8. The cubes of the remaining z-points also fall on this disk, overlapping it in the upper healf. Depicted above.

The function f(z)=1/2 is called the inversion mapping. It is an example of a one-to-one function because it maps distinct points to distinct points. 1.e if  $z_1 \neq z_2$ ,  $f(z_1) \neq f(z_2)$  **Example 4:** Show that the inversion mapping  $\omega = 1/2$  corresponds to a rotation of the Riemann sphere by  $180^{\circ}$  about the  $x_1$ -axis.

Let  $Z = (x_1, x_2, x_3)$  devote the stereographic projection of the point 2 Let  $W = (\widehat{x}_1, \widehat{x}_2, \widehat{x}_3)$  devote the gateroraphic projection 1/2

$$X_1 = \frac{2 \text{ Re}(z)}{171^2+1}$$
,  $X_2 = \frac{2 \text{ Im}(z)}{171^2+1}$ ,  $X_3 = \frac{171^2-1}{171^2+1}$ 

$$\hat{X}_{1} = 2 \operatorname{Re}(\frac{1}{2})$$
 $\hat{X}_{2} = 2 \operatorname{Im}(\frac{1}{2})$ 
 $\hat{X}_{3} = \frac{\left|\frac{1}{2}\right|^{2} - 1}{\left|\frac{1}{2}\right|^{2} + 1}$ 
 $\hat{X}_{3} = \frac{\left|\frac{1}{2}\right|^{2} - 1}{\left|\frac{1}{2}\right|^{2} + 1}$ 

Using Re ( = ) = Re ( = ) / | = | 2 | | = | Im ( = ) / | = | 2 | | = | 2 | | = | 2 | | = | 2 | | = | 2 | | = | 2 | | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | = | 2 | =

We get after simplification that

$$\hat{X}_{1} = \frac{2 \operatorname{Re}(2)}{1 + |2|^{2}} \quad \hat{X}_{2} = \frac{-2 \operatorname{Im}(2)}{1 + |2|^{2}}, \quad \hat{X}_{3} = \frac{(-|2|^{2})^{2}}{1 + |2|^{2}}$$

$$\dot{\chi}_1 = \chi_1$$
 $\dot{\chi}_2 = -\chi_2$ 
 $\dot{\chi}_3 = -\chi_3$ 

A rotation about x,-axis preserves x, and regates x, x; so indeed Wis the stated rotation of Z.

A consequence of this example is the fact that an inversion mapping preserves the class of circles and lines (Prob 17)