February 6 Math 3260 sec. 56 Spring 2018

Section 1.8: Intro to Linear Transformations

Recall that the product $A\mathbf{x}$ is a linear combination of the columns of A—turns out to be a vector. If the columns of A are vectors in $\mathbb{R}^m$, and there are n of them, then

- A is an $m \times n$ matrix,
- the product $A\mathbf{x}$ is defined for $\mathbf{x}$ in $\mathbb{R}^n$, and
- the vector $\mathbf{b} = A\mathbf{x}$ is a vector in $\mathbb{R}^m$.

So we can think of A as an **object that acts** on vectors $\mathbf{x}$ in $\mathbb{R}^n$ (via the product $A\mathbf{x}$) to produce vectors $\mathbf{b}$ in $\mathbb{R}^m$.

Transformation from $\mathbb{R}^n$ to $\mathbb{R}^m$

Definition: A transformation T (a.k.a. **function** or **mapping**) from $\mathbb{R}^n$ to $\mathbb{R}^m$ is a rule that assigns to each vector $\mathbf{x}$ in $\mathbb{R}^n$ a vector $T(\mathbf{x})$ in $\mathbb{R}^m$.

" T of $\vec{x}$ "

Some relevant terms and notation include

- $\mathbb{R}^n$ is the **domain** and $\mathbb{R}^m$ is called the **codomain.**
- For $\mathbf{x}$ in the domain, $T(\mathbf{x})$ is called the **image** of $\mathbf{x}$ under T.
- The collection of all images is called the **range.**
- The notation $T : \mathbb{R}^n \longrightarrow \mathbb{R}^m$ may be used to indicate that $\mathbb{R}^n$ is the domain and $\mathbb{R}^m$ is the codomain.
- If $T(\mathbf{x})$ is defined by multiplication by the $m \times n$ matrix A, we may denote this by $\mathbf{x} \mapsto A\mathbf{x}$.

" $\vec{x}$ maps to $A\vec{x}$ "

Matrix Transformation Example

Let $A = \begin{bmatrix} 1 & 3 \\ 2 & 4 \\ 0 & -2 \end{bmatrix}$. Define the transformation $T : \mathbb{R}^2 \longrightarrow \mathbb{R}^3$ by the mapping $T(\mathbf{x}) = A\mathbf{x}$.

(a) Find the image of the vector $\mathbf{u} = \begin{bmatrix} 1 \\ -3 \end{bmatrix}$ under T.

$T(\vec{u}) = A\vec{u}$.

$= \begin{bmatrix} 1 & 3 \\ 2 & 4 \\ 0 & -2 \end{bmatrix} \begin{bmatrix} 1 \\ -3 \end{bmatrix} = \begin{bmatrix} -8 \\ -10 \\ 6 \end{bmatrix}$

$\vec{u} = \begin{bmatrix} 1 \\ -3 \end{bmatrix}$ is in $\mathbb{R}^2$

$T(\vec{u}) = \begin{bmatrix} -8 \\ -10 \\ 6 \end{bmatrix}$ is in $\mathbb{R}^3$

$$A = \begin{bmatrix} 1 & 3 \\ 2 & 4 \\ 0 & -2 \end{bmatrix}$$

(b) Determine a vector $\mathbf{x}$ in $\mathbb{R}^2$ whose image under T is $\begin{bmatrix} -4 \\ -4 \\ 4 \end{bmatrix}$.

Find $\vec{x}$ such that $T(\vec{x}) = \begin{bmatrix} -4 \\ -4 \\ 4 \end{bmatrix}$.

Since $T(\vec{x}) = A\vec{x}$, this equation is

$$\begin{bmatrix} 1 & 3 \\ 2 & 4 \\ 0 & -2 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} -4 \\ -4 \\ 4 \end{bmatrix}$$

We can use an augmented matrix

$$\begin{bmatrix} 1 & 3 & -4 \\ 2 & 4 & -4 \\ 0 & -2 & 4 \end{bmatrix} \xrightarrow{\text{rref}} \begin{bmatrix} 1 & 0 & 2 \\ 0 & 1 & -2 \\ 0 & 0 & 0 \end{bmatrix}$$

$x_1 = 2$

$x_2 = -2$

A vector $\vec{x}$ whose image is $\begin{bmatrix} -4 \\ -4 \\ 4 \end{bmatrix}$ is

$$\vec{x} = \begin{bmatrix} 2 \\ -2 \end{bmatrix}.$$

$$A = \begin{bmatrix} 1 & 3 \\ 2 & 4 \\ 0 & -2 \end{bmatrix}$$

(c) Determine if $\begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix}$ is in the range of T.

i.e. is $\begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix}$ the image of some $\vec{x}$ in $\mathbb{R}^2$.

This can be stated as an equation:

is $T(\vec{x}) = \begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix}$ solvable, i.e.

is $A\vec{x} = \begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix}$ consistent?

Using an augmented matrix

$$\begin{bmatrix} 1 & 3 & 1 \\ 2 & 4 & 0 \\ 0 & -2 & 1 \end{bmatrix} \xrightarrow{\text{rref}} \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

pivot column!

$A\vec{x} = \begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix}$ is inconsistent.

$\begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix}$ is not in the range of T.

Linear Transformations

Definition: A transformation T is **linear** provided

(i) $T(\mathbf{u}+\mathbf{v}) = T(\mathbf{u}) + T(\mathbf{v})$ for every $\mathbf{u}$,$\mathbf{v}$ in the domain of T, and

(ii) $T(c\mathbf{u}) = cT(\mathbf{u})$ for every scalar c and vector $\mathbf{u}$ in the domain of T.

Every matrix transformation (e.g. $\mathbf{x} \mapsto A\mathbf{x}$) is a linear transformation. And it turns out that every linear transformation from $\mathbb{R}^n$ to $\mathbb{R}^m$ can be expressed in terms of matrix multiplication.

A Theorem About Linear Transformations:

If T is a linear transformation, then

$$T(\mathbf{0}) = \mathbf{0},$$

$$T(c\mathbf{u} + d\mathbf{v}) = cT(\mathbf{u}) + dT(\mathbf{v})$$

for scalars c, d and vectors $\mathbf{u}, \mathbf{v}$.

And in fact

$$T(c_1\mathbf{u}_1 + c_2\mathbf{u}_2 + \cdots + c_k\mathbf{u}_k) = c_1 T(\mathbf{u}_1) + c_2 T(\mathbf{u}_2) + \cdots + c_k T(\mathbf{u}_k).$$

Example

Let r be a nonzero scalar. The transformation $T : \mathbb{R}^2 \longrightarrow \mathbb{R}^2$ defined by

$$T(\mathbf{x}) = r\mathbf{x}$$

is a linear transformation[1].
Show that T is a linear transformation.

We have to show that for any $\vec{u}, \vec{v}$ in $\mathbb{R}^2$ and scalar c

$$T(\vec{u}+\vec{v}) = T(\vec{u}) + T(\vec{v}) \quad \text{, and}$$

$$T(c\vec{u}) = cT(\vec{u}).$$

$$T(\vec{u}+\vec{v}) = r(\vec{u}+\vec{v}) = r\vec{u} + r\vec{v} = T(\vec{u}) + T(\vec{v})$$

[1] It's called a **contraction** if $0 < r < 1$ and a **dilation** when $r > 1$

The 1^{st} property holds.

$$T(c\vec{u}) = r(c\vec{u}) = rc\vec{u} = cr\vec{u} = c(r\vec{u})$$

$$= cT(\vec{u}).$$

Both properties hold, so T is a

liner transformation.

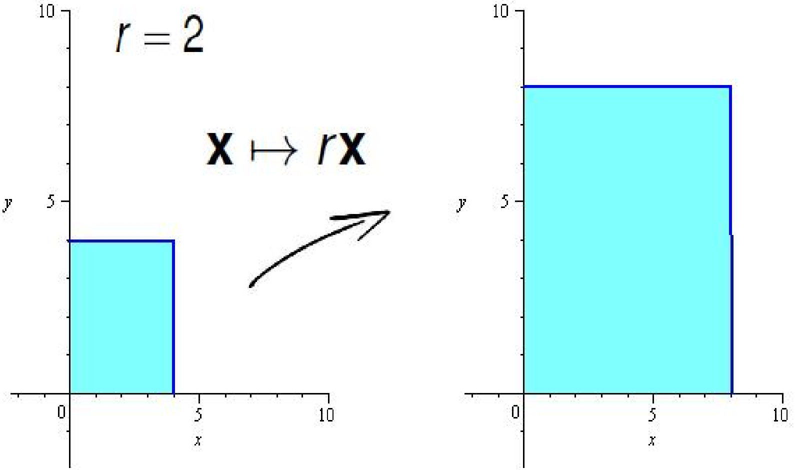


Figure: Geometry of dilation $\mathbf{x} \mapsto 2\mathbf{x}$. The 4 by 4 square maps to an 8 by 8 square.

Section 1.9: The Matrix for a Linear Transformation

Elementary Vectors: We'll use the notation $\mathbf{e}_i$ to denote the vector in $\mathbb{R}^n$ having a 1 in the i^{th} position and zero everywhere else.

e.g. in $\mathbb{R}^2$ the elementary vectors are

$$\mathbf{e}_1 = \begin{bmatrix} 1 \\ 0 \end{bmatrix}, \quad \text{and} \quad \mathbf{e}_2 = \begin{bmatrix} 0 \\ 1 \end{bmatrix},$$

in $\mathbb{R}^3$ they would be

$$\mathbf{e}_1 = \begin{bmatrix} 1 \\ 0 \\ 0 \end{bmatrix}, \quad \mathbf{e}_2 = \begin{bmatrix} 0 \\ 1 \\ 0 \end{bmatrix}, \quad \text{and} \quad \mathbf{e}_3 = \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}$$

and so forth.

Note that in $\mathbb{R}^n$, the elementary vectors are the columns of the identity I_n.

Matrix of Linear Transformation

Let $T : \mathbb{R}^2 \longrightarrow \mathbb{R}^4$ be a linear transformation, and suppose

$$T(\mathbf{e}_1) = \begin{bmatrix} 0 \\ 1 \\ -2 \\ 4 \end{bmatrix}, \quad \text{and} \quad T(\mathbf{e}_2) = \begin{bmatrix} 1 \\ 1 \\ -1 \\ 6 \end{bmatrix}.$$

Use the fact that T is linear, and the fact that for each $\mathbf{x}$ in $\mathbb{R}^2$ we have

$$\mathbf{x} = \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = x_1 \begin{bmatrix} 1 \\ 0 \end{bmatrix} + x_2 \begin{bmatrix} 0 \\ 1 \end{bmatrix} = x_1\mathbf{e}_1 + x_2\mathbf{e}_2$$

to find a matrix A such that

$$T(\mathbf{x}) = A\mathbf{x} \quad \text{for every} \quad \mathbf{x} \in \mathbb{R}^2.$$

$$T(\mathbf{e}_1) = \begin{bmatrix} 0 \\ 1 \\ -2 \\ 4 \end{bmatrix}, \quad \text{and} \quad T(\mathbf{e}_2) = \begin{bmatrix} 1 \\ 1 \\ -1 \\ 6 \end{bmatrix}$$

$$\vec{x} = \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = x_1\vec{e}_1 + x_2\vec{e}_2$$

$$T(\vec{x}) = T(x_1\vec{e}_1 + x_2\vec{e}_2)$$

$$= x_1 T(\vec{e}_1) + x_2 T(e_2)$$ as T is linear

$$= x_1 \begin{bmatrix} 0 \\ 1 \\ -2 \\ 4 \end{bmatrix} + x_2 \begin{bmatrix} 1 \\ 1 \\ -1 \\ 6 \end{bmatrix}$$ givens

$$= \begin{bmatrix} 0 & 1 \\ 1 & 1 \\ -2 & -1 \\ 4 & 6 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$$

By definition of the product "$A\vec{x}$"

This holds for any vector $\vec{x}$ in $\mathbb{R}^2$,

so $T(\vec{x}) = A\vec{x}$ where

$$A = \begin{bmatrix} 0 & 1 \\ 1 & 1 \\ -2 & -1 \\ 4 & 6 \end{bmatrix}.$$

Note $A = \left[T(\vec{e}_1) \quad T(\vec{e}_2) \right]$

Theorem

Let $T : \mathbb{R}^n \longrightarrow \mathbb{R}^m$ be a linear transformation. There exists a unique $m \times n$ matrix A such that

$\swarrow \vec{x}$ in $\mathbb{R}^n$

$$T(\mathbf{x}) = A\mathbf{x} \quad \text{for every} \quad \mathbf{x} \in \mathbb{R}^n.$$

Moreover, the j^{th} column of the matrix A is the vector $T(\mathbf{e}_j)$, where $\mathbf{e}_j$ is the j^{th} column of the $n \times n$ identity matrix I_n. That is,

$$A = [T(\mathbf{e}_1) \quad T(\mathbf{e}_2) \quad \cdots \quad T(\mathbf{e}_n)] \,.$$

The matrix A is called the **standard matrix** for the linear transformation T.

Example

Let $T : \mathbb{R}^2 \longrightarrow \mathbb{R}^2$ be the scaling trasformation (contraction or dilation for $r > 0$) defined by

$$T(\mathbf{x}) = r\mathbf{x}, \quad \text{for positive scalar } r.$$

Find the standard matrix for T.

in $\mathbb{R}^2$ $\quad \vec{e}_1 = \begin{bmatrix} 1 \\ 0 \end{bmatrix}$, $\quad T(\vec{e}_1) = r\vec{e}_1 = r\begin{bmatrix} 1 \\ 0 \end{bmatrix} = \begin{bmatrix} r \\ 0 \end{bmatrix}$

$\vec{e}_2 = \begin{bmatrix} 0 \\ 1 \end{bmatrix}$, $\quad T(\vec{e}_2) = r\vec{e}_2 = r\begin{bmatrix} 0 \\ 1 \end{bmatrix} = \begin{bmatrix} 0 \\ r \end{bmatrix}$

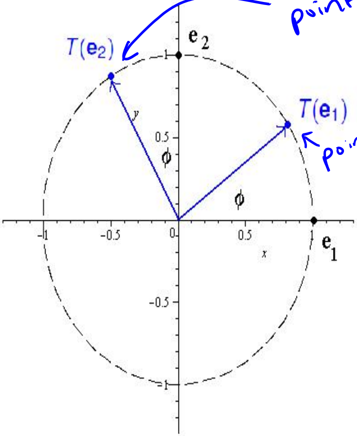
so the standard matrix

$$A = \left[T(e_1) \; T(e_2) \right] = \begin{bmatrix} r & 0 \\ 0 & r \end{bmatrix}.$$

Example

Let $T : \mathbb{R}^2 \longrightarrow \mathbb{R}^2$ be the rotation transformation that rotates each point in $\mathbb{R}^2$ counter clockwise about the origin through an angle ϕ. Find the standard matrix for T.

point $\left(\cos\left(\frac{\pi}{2}+\varphi\right), \sin\left(\frac{\pi}{2}+\varphi\right)\right)$



point $(\cos\varphi, \sin\varphi)$

$$T(\vec{e}_1) = \begin{bmatrix} \cos\varphi \\ \sin\varphi \end{bmatrix}$$

$$T(\vec{e}_2) = \begin{bmatrix} \cos\left(\frac{\pi}{2}+\varphi\right) \\ \sin\left(\frac{\pi}{2}+\varphi\right) \end{bmatrix}$$

$$\cos\left(\frac{\pi}{2}+\varphi\right) = \cos\frac{\pi}{2}\cos\varphi - \sin\frac{\pi}{2}\sin\varphi = -\sin\varphi$$

$$\sin\left(\frac{\pi}{2}+\varphi\right) = \sin\frac{\pi}{2}\cos\varphi + \sin\varphi\cos\frac{\pi}{2} = \cos\varphi$$

$$\Rightarrow \quad T(\vec{e}_2) = \begin{bmatrix} -\sin\varphi \\ \cos\varphi \end{bmatrix}$$

The standard matrix

$$A = [T(\vec{e}_1) \ T(\vec{e}_2)] = \begin{bmatrix} \cos\varphi & -\sin\varphi \\ \sin\varphi & \cos\varphi \end{bmatrix}$$

Example[2]

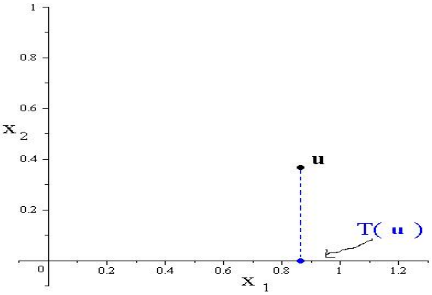
Let $T : \mathbb{R}^2 \longrightarrow \mathbb{R}^2$ be the projection transformation that projects each point onto the x_1 axis

$$T\left(\begin{bmatrix} x_1 \\ x_2 \end{bmatrix}\right) = \begin{bmatrix} x_1 \\ 0 \end{bmatrix}.$$

Find the standard matrix for T.

$$T(\vec{e}_1) = T\left(\begin{bmatrix} 1 \\ 0 \end{bmatrix}\right) = \begin{bmatrix} 1 \\ 0 \end{bmatrix}$$

$$T(\vec{e}_2) = T\left(\begin{bmatrix} 0 \\ 1 \end{bmatrix}\right) = \begin{bmatrix} 0 \\ 0 \end{bmatrix}$$



[2]See pages 73–75 in Lay for matrices associated with other geometric tranformation on $\mathbb{R}^2$

The standard matrix

$$A = \left[T(\vec{e}_1) \quad T(\vec{e}_2) \right] = \begin{bmatrix} 1 & 0 \\ 0 & 0 \end{bmatrix}$$

One to One, Onto

Definition: A mapping $T : \mathbb{R}^n \longrightarrow \mathbb{R}^m$ is said to be **onto** $\mathbb{R}^m$ if each **b** in $\mathbb{R}^m$ is the image of at least one **x** in $\mathbb{R}^n$—i.e. if the range of T is all of the codomain.

If T is onto, then an equation $T(\vec{x}) = \vec{b}$ is consistent for every $\vec{b}$ in $\mathbb{R}^m$.

Definition: A mapping $T : \mathbb{R}^n \longrightarrow \mathbb{R}^m$ is said to be **one to one** if each **b** in $\mathbb{R}^m$ is the image of **at most one x** in $\mathbb{R}^n$.

i.e. T is one to one if

$T(\vec{x}) = T(\vec{y})$ if and only if $\vec{x} = \vec{y}$.

Determine if the transformation is one to one, onto, neither or both.

$$T(\mathbf{x}) = \begin{bmatrix} 1 & 0 & 2 \\ 0 & 1 & 3 \end{bmatrix} \mathbf{x}.$$

$T: \mathbb{R}^3 \to \mathbb{R}^2$

Let's see if T is onto.

Is every vector $\vec{b} = \begin{bmatrix} b_1 \\ b_2 \end{bmatrix}$ the output

$\vec{b} = T(\vec{x})$ for some $\vec{x}$ in $\mathbb{R}^3$?

Is $T(\vec{x}) = \begin{bmatrix} 1 & 0 & 2 \\ 0 & 1 & 3 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} b_1 \\ b_2 \end{bmatrix}$ consistent?

Using an augmented matrix

$$\begin{bmatrix} 1 & 0 & 2 & b_1 \\ 0 & 1 & 3 & b_2 \end{bmatrix} \xrightarrow{\text{rref}} \begin{bmatrix} 1 & 0 & 2 & b_1 \\ 0 & 1 & 3 & b_2 \end{bmatrix}$$

never a pivot column

The system is always consistent, that is $\vec{b}$ is in range T for every $\vec{b}$ in $\mathbb{R}^2$. T is onto.

From the rref, we see that

$$x_1 = b_1 - 2x_3$$

$$x_2 = b_2 - 3x_3$$

$$x_3 - \text{free}$$

So $T(\vec{x}) = \vec{b}$ has infinitely many solutions

So T is not one to one.