

Section 3.2

One-to-one and Onto Transformations

Matrix Transformations

Reminder

Recall: Let A be an $m \times n$ matrix. The matrix transformation associated to A is the transformation

$$T: \mathbb{R}^n \rightarrow \mathbb{R}^m \text{ defined by } T(x) = Ax.$$

- The domain of T is $\mathbb{R}^n$, which is the number of columns of A .
- The codomain of T is $\mathbb{R}^m$, which is the number of rows of A .
- The range of T is the set of all images of T .

$$T(x) = Ax = \begin{pmatrix} v_1 & v_2 & \dots & v_n \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{pmatrix} = x_1 v_1 + x_2 v_2 + \dots + x_n v_n.$$

This is the column space of A . It is a span of vectors in the codomain.

Matrix Transformations

Example

$$\text{Let } A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix} \text{ and let } T(x) = Ax, \text{ so } T: \mathbb{R}^2 \rightarrow \mathbb{R}^3.$$

(1) find $T(u)$ where $u = [3; 4]$

(2) let $b = [7; 5; 7]$, find v in $\mathbb{R}^2$ such that $T(v) = b$.

(3) is there any other vector w (other than v) that also gets sent to b ?

(1) $u = \begin{bmatrix} 3 \\ 4 \end{bmatrix}$ what is the image of u under T ?

$$T\left(\begin{bmatrix} 3 \\ 4 \end{bmatrix}\right) = A\begin{bmatrix} 3 \\ 4 \end{bmatrix} = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix} \begin{bmatrix} 3 \\ 4 \end{bmatrix} = \begin{pmatrix} 1 \\ 0 \\ 1 \end{pmatrix} + 4 \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix} = \begin{bmatrix} 7 \\ 4 \\ 7 \end{bmatrix}.$$

(2) is there an input $v = \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$ s.t. $T\left(\begin{bmatrix} x_1 \\ x_2 \end{bmatrix}\right) = \begin{bmatrix} 7 \\ 5 \\ 7 \end{bmatrix}$?

guess & check $v = \begin{bmatrix} 2 \\ 5 \end{bmatrix}$: $T\left(\begin{bmatrix} 2 \\ 5 \end{bmatrix}\right) = 2 \begin{pmatrix} 1 \\ 0 \\ 1 \end{pmatrix} + 5 \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix} = \begin{bmatrix} 7 \\ 5 \\ 7 \end{bmatrix}$ ✓

More systematic approach solve

$$Ax = \begin{bmatrix} 7 \\ 5 \\ 7 \end{bmatrix} \Rightarrow \left[\begin{array}{cc|c} 1 & 1 & 7 \\ 0 & 1 & 5 \\ 1 & 1 & 7 \end{array} \right] \sim \left[\begin{array}{cc|c} 1 & 1 & 7 \\ 0 & 1 & 5 \\ 0 & 0 & 0 \end{array} \right] \sim \left[\begin{array}{cc|c} 1 & 0 & 2 \\ 0 & 1 & 5 \\ 0 & 0 & 0 \end{array} \right]$$

$$x = \begin{pmatrix} 2 \\ 5 \end{pmatrix}.$$

(3) There is no other w in $\mathbb{R}^2$ which maps to b since $Ax = \begin{bmatrix} 7 \\ 5 \\ 7 \end{bmatrix}$ has a unique soln (The image is b)
(b is not in every col of A).

$$A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix} \text{ size } 3 \times 2$$

domain $\mathbb{R}^2$ $2 = \# \text{ cols}$

codomain $\mathbb{R}^3$ $3 = \# \text{ rows}$

range is set of vector

$$b = A \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = T\left(\begin{bmatrix} x_1 \\ x_2 \end{bmatrix}\right)$$

$$= \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix}$$

$$b = x_1 \begin{pmatrix} 1 \\ 0 \\ 1 \end{pmatrix} + x_2 \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix}$$

b in the range of T

if and only if

$$b \in \text{span}\left\{\begin{pmatrix} 1 \\ 0 \\ 1 \end{pmatrix}, \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix}\right\}$$

The range of T is Col A

Let $A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$ and let $T(x) = Ax$, so $T: \mathbb{R}^2 \rightarrow \mathbb{R}^3$.

Same A as previous example.

(4) is there any vector c in $\mathbb{R}^3$ which is not in the range of T ? In other words, can you find a vector c for which NO vector v in $\mathbb{R}^2$ maps to c ?

Translation: Find c such that $Ax = c$ is inconsistent.

guess & check

$$\begin{bmatrix} 0 \\ 1 \\ 0 \end{bmatrix} = -\begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix} + \begin{bmatrix} 1 \\ 1 \\ 1 \end{bmatrix} \quad \begin{bmatrix} 0 \\ 1 \\ 0 \end{bmatrix} \text{ in col } A \text{ (in the range!)}$$

try

$$\begin{bmatrix} 1 \\ 0 \\ 0 \end{bmatrix} = x_1 \begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix} + x_2 \begin{bmatrix} 1 \\ 1 \\ 1 \end{bmatrix} ? \quad \text{inconsistent?}$$

$$\left(\begin{array}{cc|c} 1 & 1 & 1 \\ 0 & 1 & 0 \\ 1 & 1 & 0 \end{array} \right) \sim \left(\begin{array}{cc|c} 1 & 1 & 1 \\ 0 & 1 & 0 \\ 0 & 0 & -1 \end{array} \right) \quad \text{system is inconsistent so no solutions}$$

abstractly $b = \begin{pmatrix} b_1 \\ b_2 \\ b_3 \end{pmatrix}$

$$\left(\begin{array}{cc|c} 1 & 1 & b_1 \\ 0 & 1 & b_2 \\ 1 & 1 & b_3 \end{array} \right) \sim \left(\begin{array}{cc|c} 1 & 1 & b_1 \\ 0 & 1 & b_2 \\ 0 & 0 & b_3 - b_1 \end{array} \right) \quad \text{inconsistent if } b_3 \neq b_1$$

Matrix Transformations

Note: All of these questions are questions about the transformation T ; it still makes sense to ask them in the absence of the matrix A .

The fact that T comes from a matrix means that these questions translate into questions about a matrix, which we know how to do.

Non-example: $T: \mathbb{R}^2 \rightarrow \mathbb{R}^3$ $T\begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} \sin x \\ xy \\ \cos y \end{pmatrix}$

We will restrict our focus to matrix transformations in this class, but it is good to know that you can still ask similar questions about arbitrary transformations from $\mathbb{R}^n$ to $\mathbb{R}^m$.

Questions About Transformations

Today we will focus on two important questions one can ask about a transformation $T: \mathbb{R}^n \rightarrow \mathbb{R}^m$:

- Do there exist distinct vectors x, y in $\mathbb{R}^n$ such that $T(x) = T(y)$?
- For every vector v in $\mathbb{R}^m$, does there exist a vector x in $\mathbb{R}^n$ such that $T(x) = v$?

These are subtle because of the multiple quantifiers involved ("for every", "there exists").

One-to-one Transformations

Definition

A transformation $T: \mathbb{R}^n \rightarrow \mathbb{R}^m$ is one-to-one (or *injective*) if different vectors in $\mathbb{R}^n$ map to different vectors in $\mathbb{R}^m$. In other words, for every b in $\mathbb{R}^m$, the equation $T(x) = b$ has at most one solution x . Or, different inputs have different outputs. Note that not one-to-one means at least two different vectors in $\mathbb{R}^n$ have the same image.

Opposite of 1-to-1 is many-to-1.

Matrix Transformations

Example

Let $A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix}$ and let $T(x) = Ax$, so $T: \mathbb{R}^2 \rightarrow \mathbb{R}^3$.

Same example as before: Is the transformation $T(x) = Ax$ one-to-one?

Ans: yes. If $bAx = Ay$ then $x = y$.

Characterization of One-to-One Matrix Transformations

Theorem

Let $T: \mathbb{R}^n \rightarrow \mathbb{R}^m$ be a matrix transformation with matrix A . Then the following are equivalent:

- T is one-to-one.
- For each b in $\mathbb{R}^m$, the equation $T(x) = b$ has at most one solution.
- For each b in $\mathbb{R}^m$, the equation $Ax = b$ has a unique solution or is inconsistent.
- $Ax = 0$ has a unique solution.
- The columns of A are linearly independent.
- A has a pivot in every column.

Question

If $T: \mathbb{R}^n \rightarrow \mathbb{R}^m$ is one-to-one, what can we say about the relative sizes of n and m ?

What can you say about A ? $n \leq m$ (#cols $\leq$ #rows)

What sizes can A be? can be TALL

What sizes can A NOT be? can NOT be WIDE

$$B = \begin{bmatrix} 1 & 0 & 1 \\ 1 & 1 & 1 \end{bmatrix}$$

then $T(x) = Bx$ can't be 1-to-1
 $T: \mathbb{R}^3 \rightarrow \mathbb{R}^2$

New example:

One-to-One Transformations

Define

$$A = \begin{pmatrix} 1 & 0 \\ 0 & 1 \\ 1 & 0 \end{pmatrix} \quad T(x) = Ax,$$

so $T: \mathbb{R}^2 \rightarrow \mathbb{R}^3$. Is T one-to-one?

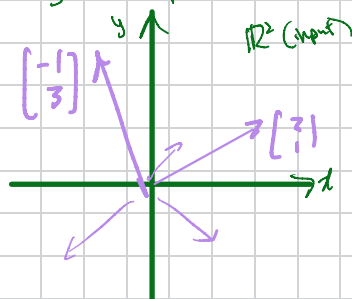
- (1) domain of T is $\mathbb{R}^2$
- (2) codomain of T is $\mathbb{R}^3$
- (3) range of T is a plane in $\frac{\mathbb{R}^3}{2}$
- (4) is T one-to-one? yes b/c every col has a pivot

Ex. $A = \begin{pmatrix} 1 & 0 \\ 0 & 1 \\ 0 & 0 \end{pmatrix}$

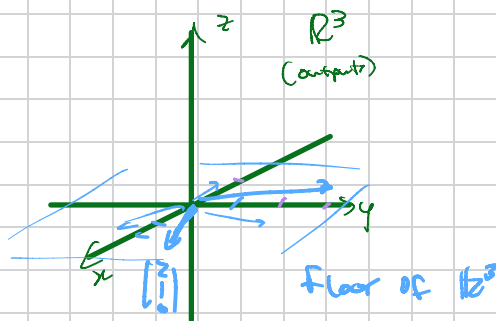
domain $\mathbb{R}^2$

codomain $\mathbb{R}^3$

range is a plane in $\mathbb{R}^3$



$$\begin{bmatrix} 1 & 0 \\ 0 & 1 \\ 0 & 0 \end{bmatrix} \begin{pmatrix} 2 \\ 1 \end{pmatrix} = \begin{pmatrix} 2 \\ 1 \\ 0 \end{pmatrix}, \quad \begin{bmatrix} 1 & 0 \\ 0 & 1 \\ 0 & 0 \end{bmatrix} \begin{pmatrix} 1 \\ 3 \end{pmatrix} = \begin{pmatrix} 1 \\ 3 \\ 0 \end{pmatrix}$$



Non-example:

One-to-One Transformations

Define

$$A = \begin{pmatrix} 1 & 1 & 0 \\ 0 & 1 & 1 \end{pmatrix} \quad T(x) = Ax,$$

- (1) Is the transformation $T(x) = Ax$ one-to-one?

No, b/c A doesn't have a pivot in every col.

- (2) If not, find two different vectors v and w that map to the same output b

- (3) Also, is every vector b in $\mathbb{R}^2$ the output for some input vector v ?

yes $Ax = b$ always consistent b/c pivot in every row of A .

$$T\left(\begin{bmatrix} 1 \\ 1 \\ 0 \end{bmatrix}\right) = \begin{bmatrix} 1 & 1 & 0 \\ 0 & 1 & 1 \end{bmatrix} \begin{pmatrix} 1 \\ 1 \\ 0 \end{pmatrix} = \begin{pmatrix} 2 \\ 1 \end{pmatrix}$$

$$T\left(\begin{bmatrix} 2 \\ 0 \\ 1 \end{bmatrix}\right) = \begin{bmatrix} 1 & 1 & 0 \\ 0 & 1 & 1 \end{bmatrix} \begin{pmatrix} 2 \\ 0 \\ 1 \end{pmatrix} = \begin{pmatrix} 2 \\ 1 \end{pmatrix}$$

$$v = \begin{bmatrix} 1 \\ 1 \\ 0 \end{bmatrix}, w = \begin{bmatrix} 2 \\ 0 \\ 1 \end{bmatrix} \quad \text{then } T(v) = T(w)$$

$$\text{but } v \neq w$$

so T is NOT 1-to-1.

One-to-one Transformations

Definition

A transformation $T: \mathbb{R}^n \rightarrow \mathbb{R}^m$ is one-to-one (or into, or injective) if different vectors in $\mathbb{R}^n$ map to different vectors in $\mathbb{R}^m$. In other words, for every b in $\mathbb{R}^m$, the equation $T(x) = b$ has at most one solution x . Or, different inputs have different outputs. Note that not one-to-one means at least two different vectors in $\mathbb{R}^n$ have the same image.

Onto Transformations

Definition

A transformation $T: \mathbb{R}^n \rightarrow \mathbb{R}^m$ is onto (or surjective) if the range of T is equal to $\mathbb{R}^m$ (its codomain). In other words, for every b in $\mathbb{R}^m$, the equation $T(x) = b$ has at least one solution. Or, every possible output has an input. Note that not onto means there is some b in $\mathbb{R}^m$ which is not the image of any x in $\mathbb{R}^n$.

$$f(x) = 3x \quad f: \mathbb{R} \rightarrow \mathbb{R}$$

f is $b \rightarrow 1$ ✓
 f is onto ✓

Same example as before:

One-to-One Transformations

Non-Example

Define

$$A = \begin{pmatrix} 1 & 1 & 0 \\ 0 & 1 & 1 \end{pmatrix} \quad T(x) = Ax$$

(1) is $T(x) = Ax$ onto?

yes b/c A has a pivot every row
 so T is onto.

Characterization of Onto Matrix Transformations

Theorem

Let $T: \mathbb{R}^n \rightarrow \mathbb{R}^m$ be a matrix transformation with matrix A . Then the following are equivalent:

- ▶ T is onto
- ▶ $T(x) = b$ has a solution for every b in $\mathbb{R}^m$
- ▶ $Ax = b$ is consistent for every b in $\mathbb{R}^m$
- ▶ The columns of A span $\mathbb{R}^m$
- ▶ A has a pivot in every row

Same example as before:

Matrix Transformations

Example

$$\text{Let } A = \begin{pmatrix} 1 & 1 \\ 0 & 1 \\ 1 & 1 \end{pmatrix} \text{ and let } T(x) = Ax, \text{ so } T: \mathbb{R}^2 \rightarrow \mathbb{R}^3.$$

(1) is $T(x) = Ax$ onto?

T is NOT onto
 b/c A does not have a pivot in every row:

recall $\begin{bmatrix} 1 \\ 0 \\ 0 \end{bmatrix}$ was not in the range of T b/c

$$\begin{bmatrix} 1 & 1 & 0 \\ 0 & 1 & 0 \\ 1 & 1 & 0 \end{bmatrix} \sim \begin{bmatrix} 1 & 1 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{bmatrix}$$

$$T(x) = Ax = \begin{pmatrix} 1 \\ 0 \\ 0 \end{pmatrix} \text{ inconsistent}$$

Question

If $T: \mathbb{R}^n \rightarrow \mathbb{R}^m$ is onto, what can we say about the relative sizes of n and m ?

* IF A is $m \times n$ then $m \leq n$ (# rows $\leq$ # cols)

* A can be WIDE for T to be onto

* A can NOT be tall for T to be onto.

Last example:

One-to-One and Onto Transformations

Non-Example

Define

$$A = \begin{pmatrix} 1 & -1 & 2 \\ -2 & 2 & -4 \end{pmatrix} \quad T(x) = Ax,$$

so $T: \mathbb{R}^3 \rightarrow \mathbb{R}^2$. Is T one-to-one? Is it onto?

(input) domain $\mathbb{R}^3$, (output) codomain $\mathbb{R}^2$

✓ (1) find the domain and codomain of T

✓ (2) is T one-to-one? NO, b/c A is wide #cols > #rows

So can not have pivot in every column

? (3) is T onto? Maybe? row reduce
& find pivots.

Q: Is there a pivot in every row? NO

$$A = \begin{pmatrix} 1 & -1 & 2 \\ -2 & 2 & -4 \end{pmatrix} \sim \begin{pmatrix} 1 & -1 & 2 \\ 0 & 0 & 0 \end{pmatrix}$$

NO, T is NOT onto.

Q: the range of T is a line in $\mathbb{R}^2$

Summary

- A transformation T is **one-to-one** if $T(x) = b$ has at most one solution, for every b in $\mathbb{R}^n$.
- A transformation T is **onto** if $T(x) = b$ has at least one solution, for every b in $\mathbb{R}^n$.
- A matrix transformation with matrix A is one-to-one if and only if the columns of A are linearly independent, if and only if A has a pivot in every column.
- A matrix transformation with matrix A is onto if and only if the columns of A span $\mathbb{R}^n$, if and only if A has a pivot in every row.
- Two of the most basic questions one can ask about a transformation is whether it is one-to-one or onto.

Section 3.3

Linear Transformations

Linear Transformations

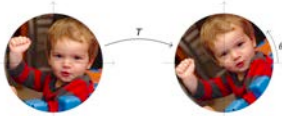
Motivation

In the last two lectures we have been asking questions about transformations, and answering them in the case of matrix transformations.

However, sometimes it is not clear if a transformation is a matrix transformation or not.

Example

For a vector x in $\mathbb{R}^2$, let $T(x)$ be the counterclockwise rotation of x by an angle θ . Is $T(x) = Ax$ for some matrix A ?



Linear Transformations

Definition

A transformation $T: \mathbb{R}^n \rightarrow \mathbb{R}^m$ is **linear** if it satisfies the equations for all vectors u, v in $\mathbb{R}^n$ and all scalars c .

(1) $T(u+v) = T(u) + T(v)$ "T respects addition"

(2) $T(cv) = c T(v)$ "T respects scalar multiplication"

Some immediate consequences:

Check: if T is linear, then

$$T(0) = 0 \quad T(cu + dv) = cT(u) + dT(v)$$

for all vectors u, v and scalars c, d . More generally,

$$T(c_1 v_1 + c_2 v_2 + \dots + c_n v_n) = c_1 T(v_1) + c_2 T(v_2) + \dots + c_n T(v_n).$$

In engineering this is called **superposition**.

Linear Transformations

Distion

Define $T: \mathbb{R}^2 \rightarrow \mathbb{R}^2$ by $T(x) = 1.5x$. Is T linear? Check:



Key observation:

Recall: If A is a matrix, u, v are vectors, and c is a scalar, then

$$A(u + v) = Au + Av \quad A(cv) = cAv.$$

So if $T(x) = Ax$ is a matrix transformation then,

$$T(u + v) = T(u) + T(v) \quad \text{and} \quad T(cv) = cT(v).$$

Note: T is a matrix transformation!

$$T(x) = \begin{pmatrix} 1.5 & 0 \\ 0 & 1.5 \end{pmatrix} x,$$

as we checked before.

Linear Transformations

Rotation

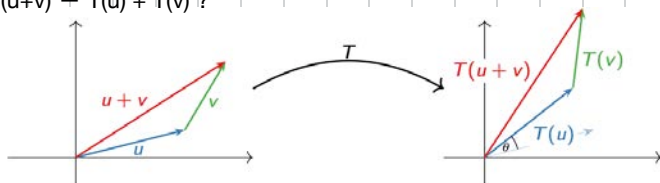
Define $T: \mathbb{R}^2 \rightarrow \mathbb{R}^2$ by

$T(x)$ = the vector x rotated counterclockwise by an angle of θ .

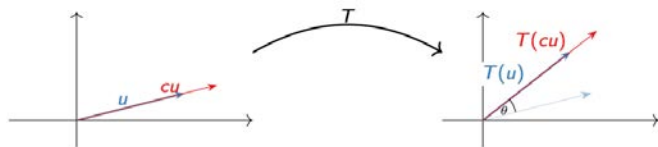
Is T linear? Check:

Proof by picture:

(1) $T(u+v) \stackrel{?}{=} T(u) + T(v)$?



(2) $T(cu) \stackrel{?}{=} c T(u)$?



Linear Transformations

Non-example

Is every transformation a linear transformation?

No! For instance, $T \begin{pmatrix} x \\ y \end{pmatrix} = \begin{pmatrix} \sin x \\ xy \\ \cos y \end{pmatrix}$ is not linear.

Hint: check what happens to $T(v)$ if $v=0$ the zero vector.

You Try It!

Poll

Which of the following transformations are linear?

A. $T \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} |x_1| \\ x_2 \end{pmatrix}$ B. $T \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} 2x_1 + x_2 \\ x_1 - 2x_2 \end{pmatrix}$

C. $T \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} x_1 x_2 \\ x_2 \end{pmatrix}$ D. $T \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} 2x_1 + 1 \\ x_1 - 2x_2 \end{pmatrix}$

The Matrix of a Linear Transformation

We will see that a linear transformation T is a matrix transformation:
 $T(x) = Ax$.

But what matrix does T come from? What is A ?

Here's how to compute it.

The Matrix of a Linear Transformation

We will see that a linear transformation T is a matrix transformation:
 $T(x) = Ax$.

But what matrix does T come from? What is A ?

Here's how to compute it.

First: recall the definitions of $e_1, e_2, \dots, e_n$

Unit Coordinate Vectors

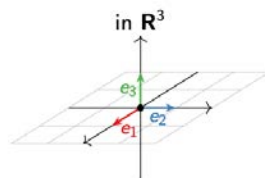
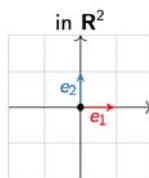
Definition

The unit coordinate vectors in $\mathbb{R}^n$ are

This is what $e_1, e_2, \dots, e_n$ mean, for the rest of the class.

$$e_1 = \begin{pmatrix} 1 \\ 0 \\ \vdots \\ 0 \\ 0 \end{pmatrix}, \quad e_2 = \begin{pmatrix} 0 \\ 1 \\ \vdots \\ 0 \\ 0 \end{pmatrix}, \quad \dots, \quad e_{n-1} = \begin{pmatrix} 0 \\ 0 \\ \vdots \\ 1 \\ 0 \end{pmatrix}, \quad e_n = \begin{pmatrix} 0 \\ 0 \\ \vdots \\ 0 \\ 1 \end{pmatrix}.$$

aka standard basis vectors in $\mathbb{R}^n$.



For the matrix $A = \begin{bmatrix} 1 & 2 & 3 \\ 4 & 5 & 6 \\ 7 & 8 & 9 \end{bmatrix}$ compute Ae_1 , Ae_2 , and Ae_3 .

$$Ae_1 = \begin{pmatrix} 1 & 2 & 3 \\ 4 & 5 & 6 \\ 7 & 8 & 9 \end{pmatrix} \begin{pmatrix} 1 \\ 0 \\ 0 \end{pmatrix}$$

$$Ae_2 = \begin{pmatrix} 1 & 2 & 3 \\ 4 & 5 & 6 \\ 7 & 8 & 9 \end{pmatrix} \begin{pmatrix} 0 \\ 1 \\ 0 \end{pmatrix}$$

$$Ae_3 = \begin{pmatrix} 1 & 2 & 3 \\ 4 & 5 & 6 \\ 7 & 8 & 9 \end{pmatrix} \begin{pmatrix} 0 \\ 0 \\ 1 \end{pmatrix}$$

Note: if A is an $m \times n$ matrix with columns $v_1, v_2, \dots, v_n$, then $Ae_i = v_i$ for $i = 1, 2, \dots, n$: multiplying a matrix by e_i gives you the i th column.

Linear Transformations are Matrix Transformations

Theorem

Let $T: \mathbb{R}^1 \rightarrow \mathbb{R}^n$ be a linear transformation. Let

$$A = \begin{pmatrix} | & | & | & | \\ T(e_1) & T(e_2) & \dots & T(e_n) \\ | & | & | & | \end{pmatrix}.$$

This is an $m \times n$ matrix, and T is the matrix transformation for A : $T(x) = Ax$.
 The matrix A is called the **standard matrix** for T .

Take-Away

Linear transformations are the same as matrix transformations.

Linear Transformations are Matrix Transformations

Example

Before, we defined a **dilation** transformation $T: \mathbb{R}^2 \rightarrow \mathbb{R}^2$ by $T(x) = 1.5x$.
What is its standard matrix?

How to get A?

Linear Transformations are Matrix Transformations

Example

Question

What is the matrix for the linear transformation $T: \mathbb{R}^2 \rightarrow \mathbb{R}^2$ defined by

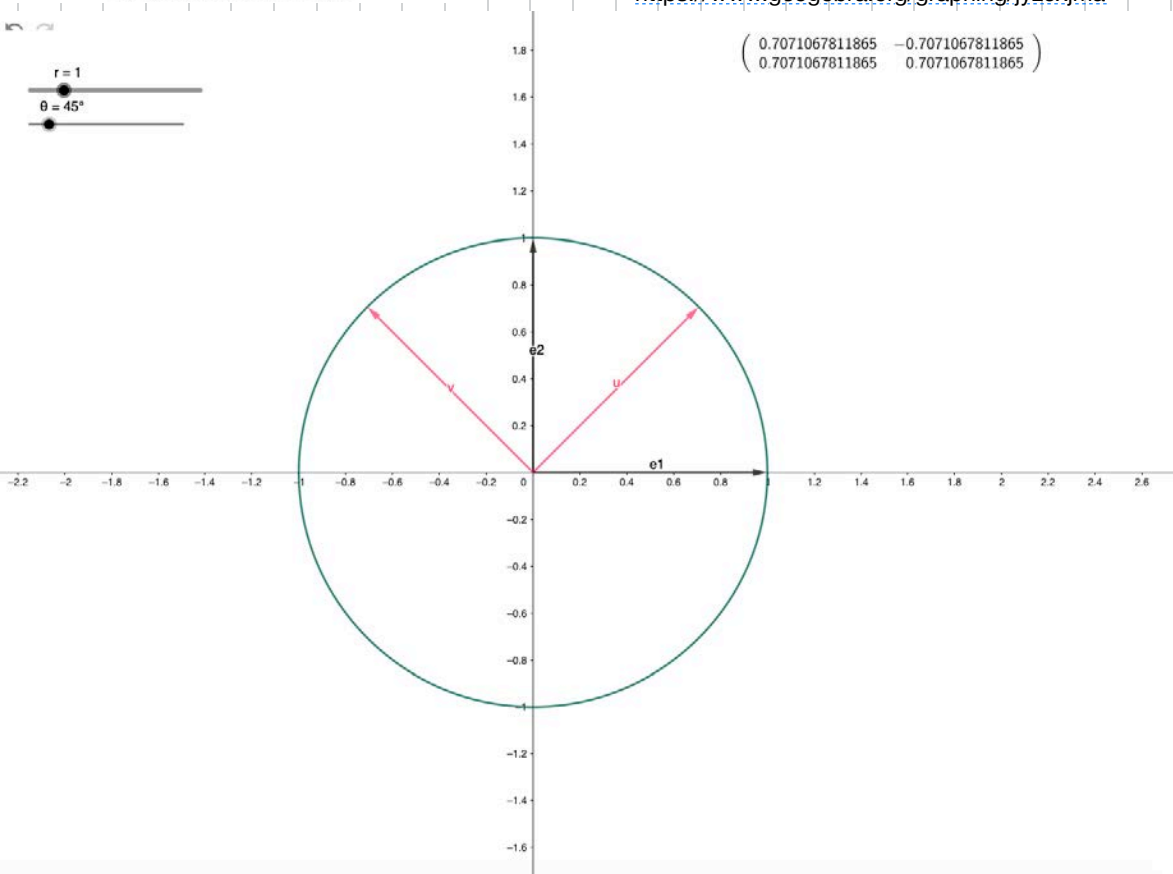
$T(x) = x$ rotated counterclockwise by an angle θ ?

<https://www.geogebra.org/graphing/jyzexjma>

$r = 1$

$\theta = 45^\circ$

$$\begin{pmatrix} 0.7071067811865 & -0.7071067811865 \\ 0.7071067811865 & 0.7071067811865 \end{pmatrix}$$



Ex. Find A for reflect across y -axis

$$A = [T(e_1) \ T(e_2)]$$

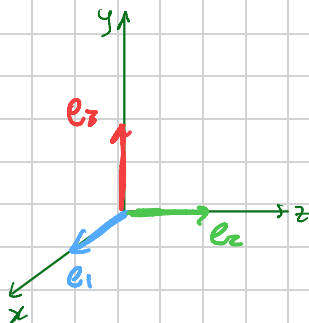
Linear Transformations are Matrix Transformations

Example, continued

Question

What is the matrix for the linear transformation $T: \mathbb{R}^3 \rightarrow \mathbb{R}^3$ that reflects through the xy -plane and then projects onto the yz -plane?

- (1) Find the standard matrix A of T
- (2) is T one-to-one?
- (3) is T onto?



Linear Transformations are Matrix Transformations

Example

Question

Define a linear transformation $T: \mathbb{R}^3 \rightarrow \mathbb{R}^3$ by

$$T \begin{pmatrix} x \\ y \\ z \end{pmatrix} = \begin{pmatrix} x + 2y + 3z \\ -y - 5z \end{pmatrix}.$$

What is the standard matrix A for T ?

- (1) Find the standard matrix A of T

→ (2) is T one-to-one?

→ (3) is T onto?

Summary

- Linear transformations are the transformations that come from matrices.
- The **unit coordinate vectors** $e_1, e_2, \dots$ are the unit vectors in the positive direction along the coordinate axes.
- You compute the columns of the matrix for a linear transformation by plugging in the unit coordinate vectors.
- This is useful when the transformation is specified geometrically, in terms of a formula, or any other way that isn't as a matrix transformation.

$$\begin{bmatrix} * & * \\ * & * \\ * & * \end{bmatrix} \quad n < m \quad (\text{tall})$$

$$\begin{bmatrix} * & * \\ * & * \end{bmatrix} \quad n = m \quad (\text{square})$$

$$\begin{bmatrix} * & * & * \\ * & * & * \end{bmatrix} \quad n > m \quad (\text{wide})$$