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A self-adjoint linear operator equal to its square is called a projector (projection operator); such a linear operator can be realized as the operator of orthogonal projection onto a closed subspace of  $V$ . A linear operator is called a unitary operator (in the case of the field  $\mathbb{C}$ , an orthogonal

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operator) if, or, equivalently, if, and. A linear operator is unitary if and only if it is an isomorphism that preserves norms.

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In mathematics, a linear map (also

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called a linear mapping, linear transformation or, in some contexts, linear function) is a mapping  $V \rightarrow W$  between two modules (for example, two vector spaces) that preserves (in the sense defined below) the operations of addition and scalar multiplication. If a linear map is a

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bijection then it is called a linear isomorphism.

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$\hat{A}f(x) = g(x)$  The most common kind



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of operator encountered are linear operators which satisfies the following two conditions:  $\hat{O}(f(x) + g(x)) = \hat{O}f(x) + \hat{O}g(x)$  Condition A. and.  $\hat{O}cf(x) = c\hat{O}f(x)$  Condition B. where.  $\hat{O}$  is a linear operator,  $c$  is a constant that can be a complex number ( $c = a + ib$ ), and.

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Newton-Raphson Method • When the iterate is sufficiently close to the root, convergence is guaranteed (local convergence)! • Extending this idea to systems nonlinear equations is easy: •

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Approximate the function as linear:  $f(x_{i+1}) \approx f(x_i) + J(x_i)(x_{i+1} - x_i)$   
 $f(x_{i+1}) \approx f(x_i) + J(x_i) \Delta x_i$  • Solve for the displacement:  $J(x_i) \Delta x_i = f(x_i) - 1$  •  $\Delta x_i = [J(x_i)]^{-1} (f(x_i) - 1)$

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$L(q, \dot{q}, t)$  or equivalently the Hamiltonian.  $H(q, p, t)$ , a function of the generalized coordinates  $q$ , generalized velocities.  $\dot{q} = \frac{d q}{d t}$  and its conjugate momenta :  $p = \frac{\partial L}{\partial \dot{q}}$ .

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The operator  $(L(D))$  is linear:  $[C_1 y_1(D)(x) + C_2 y_2(D)(x)] = C_1 L(D)y_1(x) + C_2 L(D)y_2(x)$

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The most commonly used root-finding method is perhaps the Newton-Raphson method, commonly called the Newton method. This method is based on linearizing the given

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nonlinear function. This is based on the idea that if we zoom in a very small interval, the function appears to be a straight line.

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and Science Matrices and Linear Transformations 22, Matrices Geometry and Algebra Linear Transformations Matrix Terminology Geometry and Algebra Operating on point  $x$  in  $R^3$ , matrix  $A$  transforms it to  $y$  in  $R^2$ . Point  $y$  is the image of point  $x$  under the mapping de?ned by matrix



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