Module I: Introduction

Module I Part 1

Remark I.1.1 What is Linear Algebra?
Linear algebra is the study of **linear maps**.

- In Calculus, you learn how to approximate any function by a linear function.
- In Linear Algebra, we learn about how linear maps behave.
- Combining the two, we can approximate how any function behaves.

Remark I.1.2 What is Linear Algebra good for?

- Linear algebra is used throughout several fields in higher mathematics.
- In computer graphics, linear algebra is used to help represent 3D objects in a 2D grid of pixels.
- Linear algebra is used to approximate differential equation solutions in a vast number of engineering applications (e.g. fluid flows, vibrations, heat transfer) whose solutions are very difficult (or impossible) to find precisely.
- Google's search engine is based on its Page Rank algorithm, which ranks websites by computing an eigenvector of a matrix.

Remark I.1.3 What will I learn in this class?
By the end of this class, you will be able to:

- Solve systems of linear equations. (Module E)
- Identify vector spaces and their properties. (Module V)
- Analyze the structure of vector spaces and sets of vectors. (Module S)
- Use and apply the algebraic properties of linear transformations. (Module A)
- Perform fundamental operations in the algebra of matrices. (Module M)
- Use and apply the geometric properties of linear transformations. (Module G)

Module E: Solving Systems of Linear Equations

Standards for this Module

How can we solve systems of linear equations? At the end of this module, students will be able to...

E1. Systems as matrices. ... translate back and forth between a system of linear equations and the corresponding augmented matrix.

E2. Row reduction. ... put a matrix in reduced row echelon form.

E3. Systems of linear equations. ... compute the solution set for a system of linear equations.

Module E Part 1

Definition E.1.1 A **linear equation** is an equation of the variables x_i of the form

$$a_1x_1 + a_2x_2 + \cdots + a_nx_n = b.$$

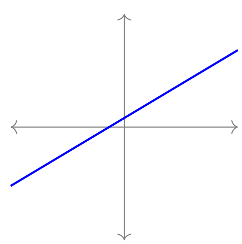
A **solution** for a linear equation is expressed in terms of the Euclidean vectors

$$\begin{bmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{bmatrix} = \begin{bmatrix} s_1 \\ s_2 \\ \vdots \\ s_n \end{bmatrix}$$

and must satisfy

$$a_1s_1 + a_2s_2 + \cdots + a_ns_n = b.$$

Observation E.1.2 The linear equation $3x - 5y = -2$ may be graphed as a line in the xy plane.



The linear equation $x + 2y - z = 4$ may be graphed as a plane in xyz space.

Remark E.1.3 In previous classes you likely assumed $x = x_1$, $y = x_2$, and $z = x_3$. However, since this course often deals with equations of four or more variables, we will almost always write our variables as x_i.

Definition E.1.4 A **system of linear equations** (or a **linear system** for short) is a collection of one or more linear equations.

$$
\begin{aligned}
a_{11}x_1 + \; a_{12}x_2 + \ldots + \; a_{1n}x_n \; &= \; b_1 \\
a_{21}x_1 + \; a_{22}x_2 + \ldots + \; a_{2n}x_n \; &= \; b_2 \\
\vdots \qquad\quad \vdots \qquad\qquad\quad \vdots \quad &\;\; \vdots \\
a_{m1}x_1 + a_{m2}x_2 + \ldots + a_{mn}x_n \; &= b_m
\end{aligned}
$$

A **solution**

$$
\begin{bmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{bmatrix} = \begin{bmatrix} s_1 \\ s_2 \\ \vdots \\ s_n \end{bmatrix}
$$

for a linear system satisfies

$$a_{i1}s_1 + a_{i2}s_2 + \cdots + a_{in}s_n = b_i$$

for $1 \leq i \leq m$ (that is, the solution satisfies all equations in the system).

Remark E.1.5 When variables in a large linear system are missing, we prefer to write the system in one of the following standard forms:

Original linear system:

$$
\begin{aligned}
x_1 + 3x_3 \; &= \;\; 3 \\
3x_1 - 2x_2 + 4x_3 \; &= \;\; 0 \\
-x_2 + x_3 \; &= -2
\end{aligned}
$$

Verbose standard form:

$$
\begin{aligned}
1x_1 + 0x_2 + 3x_3 \; &= \;\; 3 \\
3x_1 - 2x_2 + 4x_3 \; &= \;\; 0 \\
0x_1 - 1x_2 + 1x_3 \; &= -2
\end{aligned}
$$

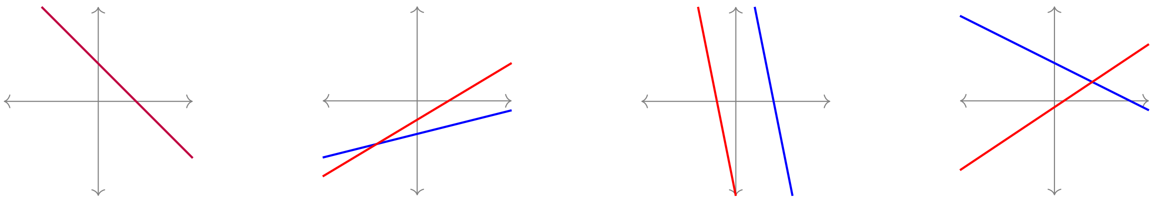
Concise standard form:

$$
\begin{alignedat}{4}
x_1 & & &+ 3x_3 &&= && \;\; 3 \\
3x_1 &- 2x_2 & &+ 4x_3 &&= && \;\; 0 \\
&- \;\; x_2 & &+ \;\; x_3 &&= && -2
\end{alignedat}
$$

Definition E.1.6 A linear system is **consistent** if there exists a solution for the system. Otherwise it is **inconsistent**.

Fact E.1.7 All linear systems are either **consistent with one solution**, **consistent with infinitely-many solutions**, or **inconsistent**.

Activity E.1.8 *(5 min)* Consider the following graphs representing linear systems of two variables. Label each graph with **consistent with one solution**, **consistent with infinitely-many solutions**, or **inconsistent**.



Activity E.1.9 *(10 min)* All inconsistent linear systems contain a logical **contradiction**. Find a contradiction in this system.

$$\begin{aligned} -x_1 + 2x_2 &= 5 \\ 2x_1 - 4x_2 &= 6 \end{aligned}$$

Activity E.1.10 *(10 min)* Consider the following consistent linear system.

$$\begin{aligned} -x_1 + 2x_2 &= -3 \\ 2x_1 - 4x_2 &= 6 \end{aligned}$$

Part 1: Find three different solutions $\begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} r_1 \\ r_2 \end{bmatrix}, \begin{bmatrix} s_1 \\ s_2 \end{bmatrix}, \begin{bmatrix} t_1 \\ t_2 \end{bmatrix}$ for this system.

Part 2: Let $x_2 = a$ where a is an arbitrary real number, then find an expression for x_1 in terms of a. Use this to describe *all* solutions (the **solution set**) $\begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} ? \\ a \end{bmatrix}$ for the linear system in terms of a.

Activity E.1.11 *(10 min)* Consider the following linear system.

$$\begin{aligned} x_1 + 2x_2 \quad - \;\; x_4 &= \;\; 3 \\ x_3 + 4x_4 &= -2 \end{aligned}$$

Describe the solution set

$$\begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ x_4 \end{bmatrix} = \begin{bmatrix} ? \\ a \\ ? \\ b \end{bmatrix} = \begin{bmatrix} t_1 \\ 0 \\ t_3 \\ 0 \end{bmatrix} + a \begin{bmatrix} ? \\ 1 \\ ? \\ 0 \end{bmatrix} + b \begin{bmatrix} ? \\ 0 \\ ? \\ 1 \end{bmatrix}$$

to the linear system by setting $x_2 = a$ and $x_4 = b$, and then solving for x_1 and x_3.

Observation E.1.12 Solving linear systems of two variables by graphing or substitution is reasonable for two-variable systems, but these simple techniques won't cut it for equations with more than two variables or more than two equations.

Remark E.1.13 The only important information in a linear system are its coefficients and constants.

Original linear system:

$$\begin{aligned} x_1 + 3x_3 &= 3 \\ 3x_1 - 2x_2 + 4x_3 &= 0 \\ -x_2 + x_3 &= -2 \end{aligned}$$

Verbose standard form:

$$\begin{aligned} 1x_1 + 0x_2 + 3x_3 &= 3 \\ 3x_1 - 2x_2 + 4x_3 &= 0 \\ 0x_1 - 1x_2 + 1x_3 &= -2 \end{aligned}$$

Coefficients/constants:

$$\begin{array}{rrr|r} 1 & 0 & 3 & 3 \\ 3 & -2 & 4 & 0 \\ 0 & -1 & 1 & -2 \end{array}$$

Definition E.1.14 A system of m linear equations with n variables is often represented by writing its coefficients and constants in an **augmented matrix**.

$$\begin{aligned} a_{11}x_1 + a_{12}x_2 + \ldots + a_{1n}x_n &= b_1 \\ a_{21}x_1 + a_{22}x_2 + \ldots + a_{2n}x_n &= b_2 \\ \vdots \qquad \vdots \qquad\qquad \vdots \quad &\;\;\vdots \\ a_{m1}x_1 + a_{m2}x_2 + \ldots + a_{mn}x_n &= b_m \end{aligned}$$

$$\left[\begin{array}{cccc|c} a_{11} & a_{12} & \cdots & a_{1n} & b_1 \\ a_{21} & a_{22} & \cdots & a_{2n} & b_2 \\ \vdots & \vdots & \ddots & \vdots & \vdots \\ a_{m1} & a_{m2} & \cdots & a_{mn} & b_m \end{array}\right]$$

Definition E.1.15 Two systems of linear equations (and their corresponding augmented matrices) are said to be **equivalent** if they have the same solution set.
For example, both of these systems have a single solution: $(x_1, x_2) = (1, 1)$.

$$\begin{aligned} 3x_1 - 2x_2 &= 1 \\ x_1 + 4x_2 &= 5 \end{aligned}$$

$$\begin{aligned} 3x_1 - 2x_2 &= 1 \\ 4x_1 + 2x_2 &= 6 \end{aligned}$$

Therefore these augmented matrices are equivalent:

$$\left[\begin{array}{cc|c} 3 & -2 & 1 \\ 1 & 4 & 5 \end{array}\right]$$

$$\left[\begin{array}{cc|c} 3 & -2 & 1 \\ 4 & 2 & 6 \end{array}\right]$$

Activity E.1.16 *(10 min)* Following are six procedures used to manipulate an augmented matrix. Label the procedures that would result in an equivalent augmented matrix as **valid**, and label the procedures that would change the solution set of the corresponding linear system as **invalid**.

a) Swap two rows.

b) Swap two columns.

c) Add a constant to every term in a row.

d) Multiply a row by a nonzero constant.

e) Add a constant multiple of one row to another row.

f) Replace a column with zeros.

(Instructor Note:) This activity could be ran as a card sort.

Module E Part 2

Definition E.2.1 The following **row operations** produce equivalent augmented matrices:

1. Swap two rows.
2. Multiply a row by a nonzero constant.
3. Add a constant multiple of one row to another row.

Whenever two matrices A, B are equivalent (so whenever we do any of these operations), we write $A \sim B$.

Activity E.2.2 *(10 min)* Consider the following two linear systems.

$$\begin{aligned} 3x_1 - 2x_2 + 13x_3 &= 6 \\ 2x_1 - 2x_2 + 10x_3 &= 2 \\ -1x_1 + 3x_2 - 6x_3 &= 11 \end{aligned} \qquad \begin{aligned} x_1 - x_2 + 5x_3 &= 1 \\ x_2 - 2x_3 &= 3 \\ x_3 &= 2 \end{aligned}$$

Part 1: Show these are equivalent by converting the first system to an augmented matrix, and then performing the following row operations to obtain an augmented matrix equivalent to the second system.

1. Swap R_1 (first row) and R_2 (second row).
2. Multiply R_2 by $\frac{1}{2}$.
3. Add R_1 to R_3.
4. Add $-3R_1$ to R_2.
5. Add $-2R_2$ to R_3.
6. Multiply R_3 by $\frac{1}{3}$.

Part 2: Which linear system would you rather solve?

Definition E.2.3 The **leading term** of a matrix row is its first nonzero term. A matrix is in **row echelon form** if all leading terms are 1, the leading term of every row is farther right than every leading term on a higher row, and all zero rows are at the bottom of the matrix. Examples:

$$\left[\begin{array}{ccc|c} 1 & -1 & 5 & 1 \\ 0 & 1 & -2 & 3 \\ 0 & 0 & 1 & 2 \end{array}\right] \qquad \left[\begin{array}{ccc|c} 1 & -1 & 5 & 1 \\ 0 & 0 & 1 & 3 \\ 0 & 0 & 0 & 1 \end{array}\right] \qquad \left[\begin{array}{ccc|c} 1 & -1 & 5 & 1 \\ 0 & 0 & 1 & 3 \\ 0 & 0 & 0 & 0 \end{array}\right]$$

Activity E.2.4 *(10 min)* Find your own sequence of row operations to manipulate the matrix

$$\left[\begin{array}{ccc|c} 3 & -2 & 13 & 6 \\ 2 & -2 & 10 & 2 \\ -1 & 3 & -6 & 11 \end{array}\right]$$

into row echelon form. (Note that row echelon form is not unique.)
The most efficient way to do this is by circling **pivot positions** in your matrix:

1. Circle the top-left-most cell that (a) is below any existing pivot positions and (b) has a nonzero term either in that position or below it.
2. Ignoring any rows above this pivot position, use row operations to change the value of your pivot position to 1, and the terms below it to 0.
3. Repeat these two steps as often as possible.

Activity E.2.5 *(10 min)* Solve this simplifed linear system:

$$\begin{aligned} x_1 - x_2 + 5x_3 &= 1 \\ x_2 - 2x_3 &= 3 \\ x_3 &= 2 \end{aligned}$$

Observation E.2.6 The consise standard form of the solution to this linear system corresponds to a simplified row echelon form matrix:

$$\begin{aligned} x_1 \quad\quad\quad &= -2 \\ x_2 \quad\; &= 7 \\ x_3 &= 2 \end{aligned} \qquad\qquad \left[\begin{array}{ccc|c} 1 & 0 & 0 & -2 \\ 0 & 1 & 0 & 7 \\ 0 & 0 & 1 & 2 \end{array}\right]$$

Definition E.2.7 A matrix is in **reduced row echelon form** if it is in row echelon form and all terms above leading terms are 0. Examples:

$$\left[\begin{array}{ccc|c} 1 & 0 & 0 & -2 \\ 0 & 1 & 0 & 7 \\ 0 & 0 & 1 & 2 \end{array}\right] \qquad \left[\begin{array}{ccc|c} 1 & 0 & -2 & 0 \\ 0 & 1 & 3 & 0 \\ 0 & 0 & 0 & 1 \end{array}\right] \qquad \left[\begin{array}{ccc|c} 1 & 3 & 0 & -2 \\ 0 & 0 & 1 & 7 \\ 0 & 0 & 0 & 0 \end{array}\right]$$

Activity E.2.8 *(10 min)* Show that the following two linear systems:

$$\begin{aligned} x_1 - x_2 + 5x_3 &= 1 \\ x_2 - 2x_3 &= 3 \\ x_3 &= 2 \end{aligned} \qquad\qquad \begin{aligned} x_1 &= -2 \\ x_2 &= 7 \\ x_3 &= 2 \end{aligned}$$

are equivalent by converting the first system to an augmented matrix, and then zeroing out all terms above pivot positions (the leading terms).

Remark E.2.9 We may verify that $\begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} -2 \\ 7 \\ 2 \end{bmatrix}$ is a solution to the original linear system

$$\begin{aligned} 3x_1 - 2x_2 + 13x_3 &= 6 \\ 2x_1 - 2x_2 + 10x_3 &= 2 \\ -1x_1 + 3x_2 - 6x_3 &= 11 \end{aligned}$$

by plugging the solution into each equation.

Fact E.2.10 Every augmented matrix A reduces to a unique reduced row echelon form matrix. This matrix is denoted as $\mathrm{RREF}(A)$.

Activity E.2.11 *(10 min)* Consider the following matrix.

$$A = \left[\begin{array}{ccc|c} 1 & 2 & 3 & 1 \\ 2 & 4 & 8 & 0 \end{array}\right]$$

Part 1: Find $\mathrm{RREF}(A)$.
Part 2: How many solutions does the corresponding linear system have?

Module E Part 3

Definition E.3.1 An algorithm that reduces A to RREF(A) is called **Gauss-Jordan elimination**. For example:

1. Circle the cell that (a) is in the top-most row without a pivot position and (b) is in the left-most column with a nonzero term either in that position or below it. This position (not the number inside) is called a **pivot**.
2. Change the pivot's value to 1 by using row operations involving only the pivot row and rows below it.
3. Add or subtract multiples of the pivot row to zero out above and below the pivot.
4. Return to Step 1 and repeat as needed until the matrix is in row reduced echelon form.

Observation E.3.2 Here is an example of applying Gauss-Jordan elimination to a matrix:

$$\left[\begin{array}{cccc|c} 2 & -2 & -6 & 1 & 3 \\ -1 & 1 & 3 & -1 & -3 \\ 1 & -2 & -1 & 1 & 2 \end{array}\right] \sim \left[\begin{array}{cccc|c} 1 & -2 & -1 & 1 & 2 \\ -1 & 1 & 3 & -1 & -3 \\ 2 & -2 & -6 & 1 & 3 \end{array}\right] \sim \left[\begin{array}{cccc|c} 1 & -2 & -1 & 1 & 2 \\ 0 & -1 & 2 & 0 & -1 \\ 0 & 2 & -4 & -1 & -1 \end{array}\right]$$

$$\sim \left[\begin{array}{cccc|c} 1 & -2 & -1 & 1 & 2 \\ 0 & 1 & -2 & 0 & 1 \\ 0 & 2 & -4 & -1 & -1 \end{array}\right] \sim \left[\begin{array}{cccc|c} 1 & 0 & -5 & 1 & 4 \\ 0 & 1 & -2 & 0 & 1 \\ 0 & 0 & 0 & -1 & -3 \end{array}\right]$$

$$\sim \left[\begin{array}{cccc|c} 1 & 0 & -5 & 1 & 4 \\ 0 & 1 & -2 & 0 & 1 \\ 0 & 0 & 0 & 1 & 3 \end{array}\right] \sim \left[\begin{array}{cccc|c} 1 & 0 & -5 & 0 & 1 \\ 0 & 1 & -2 & 0 & 1 \\ 0 & 0 & 0 & 1 & 3 \end{array}\right]$$

Definition E.3.3 The columns of RREF(A) without a leading term represent **free variables** of the linear system modeled by A that may be set equal to arbitrary parameters. The other **bounded variables** can then be expressed in terms of those parameters to describe the solution set to the linear system modeled by A.

Example E.3.4 Here, x_3 is the free variable set equal to a since its column lacks a pivot, and the other bounded variables are put in terms of a.

$$\begin{array}{ccccc}
\begin{aligned} 2x_1 - 2x_2 - 6x_3 + x_4 &= 3 \\ -x_1 + x_2 + 3x_3 - x_4 &= -3 \\ x_1 - 2x_2 - x_3 + x_4 &= 1 \end{aligned} & & \begin{aligned} x_1 - 5x_3 &= 1 \\ x_2 - 2x_3 &= 1 \\ x_4 &= 3 \end{aligned} & \Rightarrow & \begin{aligned} x_1 &= 1 + 5a \\ x_2 &= 1 + 2a \\ x_3 &= a \\ x_4 &= 3 \end{aligned} \\
\Downarrow & & \Uparrow & & \\
\left[\begin{array}{cccc|c} 2 & -2 & -6 & 1 & 3 \\ -1 & 1 & 3 & -1 & -3 \\ 1 & -2 & -1 & 1 & 2 \end{array}\right] & \sim & \left[\begin{array}{cccc|c} 1 & 0 & -5 & 0 & 1 \\ 0 & 1 & -2 & 0 & 1 \\ 0 & 0 & 0 & 1 & 3 \end{array}\right] & &
\end{array}$$

So the solution set is $\left\{ \begin{bmatrix} 1+5a \\ 1+2a \\ a \\ 3 \end{bmatrix} \,\middle|\, a \in \mathbb{R} \right\}$.

Activity E.3.5 *(20 min)* Solve the system of linear equations, circling the pivot positions in your augmented matrices as you work.

$$\begin{aligned}
-x_1 + x_2 - 3x_3 + 2x_4 &= 0 \\
2x_1 - x_2 + 5x_3 + 3x_4 &= -11 \\
3x_1 + 2x_2 + 4x_3 + x_4 &= 1 \\
x_2 - x_3 + x_4 &= 1
\end{aligned}$$

Remember to find the solution set of the system by setting the free variable (the column without a pivot position) equal to a, and then express each of the other bounded variables equal to an expression in terms of a.

(Instructor Note:) The resulting RREF matrix is

$$\left[\begin{array}{cccc|c} 1 & 0 & 2 & 0 & -1 \\ 0 & 1 & -1 & 0 & 3 \\ 0 & 0 & 0 & 1 & -2 \\ 0 & 0 & 0 & 0 & 0 \end{array}\right]$$

Remark E.3.6 From now on, unless specified, there's no need to show your work in finding RREF(A), so you may use a calculator to speed up your work.

Activity E.3.7 *(10 min)* Solve the linear system

$$\begin{aligned} 2x_1 - 3x_2 &= 17 \\ x_1 + 2x_2 &= -2 \\ -x_1 - x_2 &= 1 \end{aligned}$$

(Instructor Note:) This is an inconsistent solution. Point out to the students that one need not go all the way to RREF to discover a system is inconsistent.

Activity E.3.8 *(5 min)* Show that all linear systems of the form

$$\begin{array}{ccccccc} a_{11}x_1 + & a_{12}x_2 & + \ldots + & a_{1n}x_n & = 0 \\ a_{21}x_1 + & a_{22}x_2 & + \ldots + & a_{2n}x_n & = 0 \\ \vdots & \vdots & & \vdots & \vdots \\ a_{m1}x_1 + & a_{m2}x_2 & + \ldots + & a_{mn}x_n & = 0 \end{array}$$

are consistent by finding a quickly verifiable solution.

Definition E.3.9 A **homogeneous system** is a linear system satisfying $b_i = 0$, that is, it is a linear system of the form

$$\begin{array}{ccccccc} a_{11}x_1 + & a_{12}x_2 & + \ldots + & a_{1n}x_n & = 0 \\ a_{21}x_1 + & a_{22}x_2 & + \ldots + & a_{2n}x_n & = 0 \\ \vdots & \vdots & & \vdots & \vdots \\ a_{m1}x_1 + & a_{m2}x_2 & + \ldots + & a_{mn}x_n & = 0 \end{array}$$

Fact E.3.10 Because the zero vector is always a solution, the solution set to any homogeneous system with infinitely-many solutions may be generated by multiplying the parameters representing the free variables by a minimal set of Euclidean vectors, and adding these up. For example:

$$\begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ x_4 \end{bmatrix} = a \begin{bmatrix} 3 \\ 1 \\ -1 \\ 0 \end{bmatrix} + b \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix}$$

Definition E.3.11 A minimal set of Euclidean vectors generating the solution set to a homogeneous system is called a **basis** for the solution set of the homogeneous system. For example:

$$\begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ x_4 \end{bmatrix} = a \begin{bmatrix} 3 \\ 1 \\ -1 \\ 0 \end{bmatrix} + b \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix} \qquad \text{Basis} = \left\{ \begin{bmatrix} 3 \\ 1 \\ -1 \\ 0 \end{bmatrix}, \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix} \right\}$$

Activity E.3.12 *(10 min)* Find a basis for the solution set of the following homogeneous linear system.

$$\begin{aligned} x_1 + 2x_2 \phantom{{}+x_3} - x_4 &= 0 \\ x_3 + 4x_4 &= 0 \\ 2x_1 + 4x_2 + x_3 + 2x_4 &= 0 \end{aligned}$$

Module V: Vector Spaces

Standards for this Module

What is a vector space? At the end of this module, students will be able to...

V1. Vector property verification. ... show why an example satisfies a given vector space property, but does not satisfy another given property.

V2. Vector space identification. ... list the eight defining properties of a vector space, infer which of these properties a given example satisfies, and thus determine if the example is a vector space.

V3. Linear combinations. ... determine if a Euclidean vector can be written as a linear combination of a given set of Euclidean vectors.

V4. Spanning sets. ... determine if a set of Euclidean vectors spans $\mathbb{R}^n$.

V5. Subspaces. ... determine if a subset of $\mathbb{R}^n$ is a subspace or not.

Module V Part 1

Activity V.1.1 *(20 min)* Consider each of the following vector properties. Label each property with $\mathbb{R}^1$, $\mathbb{R}^2$, and/or $\mathbb{R}^3$ if that property holds for Euclidean vectors/scalars $\mathbf{u}, \mathbf{v}, \mathbf{w}$ of that dimension.

1. **Addition associativity.**

   $\mathbf{u} + (\mathbf{v} + \mathbf{w}) = (\mathbf{u} + \mathbf{v}) + \mathbf{w}$.

2. **Addition commutivity.**

   $\mathbf{u} + \mathbf{v} = \mathbf{v} + \mathbf{u}$.

3. **Addition identity.**

   There exists some $\mathbf{0}$ where $\mathbf{v} + \mathbf{0} = \mathbf{v}$.

4. **Addition inverse.**

   There exists some $-\mathbf{v}$ where $\mathbf{v} + (-\mathbf{v}) = \mathbf{0}$.

5. **Addition midpoint uniqueness.**

   There exists a unique $\mathbf{m}$ where the distance from $\mathbf{u}$ to $\mathbf{m}$ equals the distance from $\mathbf{m}$ to $\mathbf{v}$.

6. **Scalar multiplication associativity.**

   $a(b\mathbf{v}) = (ab)\mathbf{v}$.

7. **Scalar multiplication identity.**

   $1\mathbf{v} = \mathbf{v}$.

8. **Scalar multiplication relativity.**

   There exists some scalar c where either $c\mathbf{v} = \mathbf{w}$ or $c\mathbf{w} = \mathbf{v}$.

9. **Scalar distribution.**

   $a(\mathbf{u} + \mathbf{v}) = a\mathbf{u} + a\mathbf{v}$.

10. **Vector distribution.**

    $(a + b)\mathbf{v} = a\mathbf{v} + b\mathbf{v}$.

11. **Orthogonality.**

    There exists a non-zero vector $\mathbf{n}$ such that $\mathbf{n}$ is orthogonal to both $\mathbf{u}$ and $\mathbf{v}$.

12. **Bidimensionality.**

    $\mathbf{v} = a\mathbf{i} + b\mathbf{j}$ for some value of a, b.

Definition V.1.2 A **vector space** V is any collection of mathematical objects with associated addition and scalar multiplication operations that satisfy the following properties. Let $\mathbf{u}, \mathbf{v}, \mathbf{w}$ belong to V, and let a, b be scalar numbers.

- **Addition associativity.**
  $\mathbf{u} + (\mathbf{v} + \mathbf{w}) = (\mathbf{u} + \mathbf{v}) + \mathbf{w}$.
- **Addition commutivity.**
  $\mathbf{u} + \mathbf{v} = \mathbf{v} + \mathbf{u}$.
- **Addition identity.**
  There exists some $\mathbf{0}$ where $\mathbf{v} + \mathbf{0} = \mathbf{v}$.
- **Addition inverse.**
  There exists some $-\mathbf{v}$ where $\mathbf{v} + (-\mathbf{v}) = \mathbf{0}$.
- **Scalar multiplication associativity.**
  $a(b\mathbf{v}) = (ab)\mathbf{v}$.
- **Scalar multiplication identity.**
  $1\mathbf{v} = \mathbf{v}$.
- **Scalar distribution.**
  $a(\mathbf{u} + \mathbf{v}) = a\mathbf{u} + a\mathbf{v}$.
- **Vector distribution.**
  $(a + b)\mathbf{v} = a\mathbf{v} + b\mathbf{v}$.

Definition V.1.3 The most important examples of vector spaces are the **Euclidean vector spaces** $\mathbb{R}^n$, but there are other examples as well.

Activity V.1.4 *(25 min)* Consider the following set that models motion along the curve $y = e^x$. Let $V = \{(x, y) : y = e^x\}$. Let vector addition be defined by $(x_1, y_1) \oplus (x_2, y_2) = (x_1 + x_2, y_1 y_2)$, and let scalar multiplication be defined by $c \odot (x, y) = (cx, y^c)$.
Part 1: Which of the vector space properties are satisfied by V paired with these operations?

- **Addition associativity.**
  $\mathbf{u} \oplus (\mathbf{v} \oplus \mathbf{w}) = (\mathbf{u} \oplus \mathbf{v}) \oplus \mathbf{w}$.
- **Addition commutivity.**
  $\mathbf{u} \oplus \mathbf{v} = \mathbf{v} \oplus \mathbf{u}$.
- **Addition identity.**
  There exists some $\mathbf{0}$ where $\mathbf{v} \oplus \mathbf{0} = \mathbf{v}$.
- **Addition inverse.**
  There exists some $-\mathbf{v}$ where $\mathbf{v} \oplus (-\mathbf{v}) = \mathbf{0}$.
- **Scalar multiplication associativity.**
  $a \odot (b \odot \mathbf{v}) = (ab) \odot \mathbf{v}$.
- **Scalar multiplication identity.**
  $1 \odot \mathbf{v} = \mathbf{v}$.
- **Scalar distribution.**
  $a \odot (\mathbf{u} \oplus \mathbf{v}) = (a \odot \mathbf{u}) \oplus (a \odot \mathbf{v})$.
- **Vector distribution.**
  $(a + b) \odot \mathbf{v} = (a \odot \mathbf{v}) \oplus (b \odot \mathbf{v})$.

Part 2: Is V a vector space?

Module V Part 2

Remark V.2.1 The following sets are examples of vector spaces, with the usual/natural operations for addition and scalar multiplication.

- $\mathbb{R}^n$: Euclidean vectors with n components.
- $\mathbb{R}^\infty$: Sequences of real numbers $(v_1, v_2, \dots)$.
- $\mathbb{R}^{m\times n}$: Matrices of real numbers with m rows and n columns.
- $\mathbb{C}$: Complex numbers.
- $\mathcal{P}^n$: Polynomials of degree n or less.
- $\mathcal{P}$: Polynomials of any degree.
- $C(\mathbb{R})$: Real-valued continuous functions.

Activity V.2.2 *(10 min)* Let $V = \{(a, b) : a, b \text{ are real numbers}\}$, where $(a_1, b_1) \oplus (a_2, b_2) = (a_1 + b_1 + a_2 + b_2, b_1^2 + b_2^2)$ and $c \odot (a, b) = (a^c, b + c)$. Show that this is not a vector space by finding a counterexample that does not satisfy one of the vector space properties.

- **Addition associativity.**
  $\mathbf{u} \oplus (\mathbf{v} \oplus \mathbf{w}) = (\mathbf{u} \oplus \mathbf{v}) \oplus \mathbf{w}$.
- **Addition commutivity.**
  $\mathbf{u} \oplus \mathbf{v} = \mathbf{v} \oplus \mathbf{u}$.
- **Addition identity.**
  There exists some $\mathbf{0}$ where $\mathbf{v} \oplus \mathbf{0} = \mathbf{v}$.
- **Addition inverse.**
  There exists some $-\mathbf{v}$ where $\mathbf{v} \oplus (-\mathbf{v}) = \mathbf{0}$.
- **Scalar multiplication associativity.**
  $a \odot (b \odot \mathbf{v}) = (ab) \odot \mathbf{v}$.
- **Scalar multiplication identity.**
  $1 \odot \mathbf{v} = \mathbf{v}$.
- **Scalar distribution.**
  $a \odot (\mathbf{u} \oplus \mathbf{v}) = (a \odot \mathbf{u}) \oplus (a \odot \mathbf{v})$.
- **Vector distribution.**
  $(a + b) \odot \mathbf{v} = (a \odot \mathbf{v}) \oplus (b \odot \mathbf{v})$.

Definition V.2.3 A **linear combination** of a set of vectors $\{\mathbf{v}_1, \mathbf{v}_2, \dots, \mathbf{v}_m\}$ is given by $c_1\mathbf{v}_1 + c_2\mathbf{v}_2 + \cdots + c_m\mathbf{v}_m$ for any choice of scalar multiples $c_1, c_2, \dots, c_m$.

For example, we say $\begin{bmatrix}3\\0\\5\end{bmatrix}$ is a linear combination of the vectors $\begin{bmatrix}1\\-1\\2\end{bmatrix}$ and $\begin{bmatrix}1\\2\\1\end{bmatrix}$ since

$$\begin{bmatrix}3\\0\\5\end{bmatrix} = 2\begin{bmatrix}1\\-1\\2\end{bmatrix} + 1\begin{bmatrix}1\\2\\1\end{bmatrix}$$

Definition V.2.4 The **span** of a set of vectors is the collection of all linear combinations of that set:

$$\text{span}\{\mathbf{v}_1, \mathbf{v}_2, \ldots, \mathbf{v}_m\} = \{c_1\mathbf{v}_1 + c_2\mathbf{v}_2 + \cdots + c_m\mathbf{v}_m : c_i \text{ is a real number}\}$$

Activity V.2.5 *(10 min)* Consider $\text{span}\left\{\begin{bmatrix}1\\2\end{bmatrix}\right\}$.

Part 1: Sketch $c\begin{bmatrix}1\\2\end{bmatrix}$ in the xy plane for $c = 1, 3, 0, -2$.

Part 2: Sketch a representation of all the vectors given by $\text{span}\left\{\begin{bmatrix}1\\2\end{bmatrix}\right\}$ in the xy plane.

Activity V.2.6 *(10 min)* Consider $\text{span}\left\{\begin{bmatrix}1\\2\end{bmatrix}, \begin{bmatrix}-1\\1\end{bmatrix}\right\}$.

Part 1: Sketch the following linear combinations in the xy plane: $1\begin{bmatrix}1\\2\end{bmatrix} + 0\begin{bmatrix}-1\\1\end{bmatrix}$, $0\begin{bmatrix}1\\2\end{bmatrix} + 1\begin{bmatrix}-1\\1\end{bmatrix}$, $2\begin{bmatrix}1\\2\end{bmatrix} + 0\begin{bmatrix}-1\\1\end{bmatrix}$, $2\begin{bmatrix}1\\2\end{bmatrix} + 1\begin{bmatrix}-1\\1\end{bmatrix}$.

Part 2: Sketch a representation of all the vectors given by $\text{span}\left\{\begin{bmatrix}1\\2\end{bmatrix}, \begin{bmatrix}-1\\1\end{bmatrix}\right\}$ in the xy plane.

Activity V.2.7 *(5 min)* Sketch a representation of all the vectors given by $\text{span}\left\{\begin{bmatrix}6\\-4\end{bmatrix}, \begin{bmatrix}-2\\3\end{bmatrix}\right\}$ in the xy plane.

Activity V.2.8 *(15 min)* The vector $\begin{bmatrix}-1\\-6\\1\end{bmatrix}$ belongs to $\text{span}\left\{\begin{bmatrix}1\\0\\-3\end{bmatrix}, \begin{bmatrix}-1\\-3\\2\end{bmatrix}\right\}$ exactly when the vector equation $x_1\begin{bmatrix}1\\0\\-3\end{bmatrix} + x_2\begin{bmatrix}-1\\-3\\2\end{bmatrix} = \begin{bmatrix}-1\\-6\\1\end{bmatrix}$ holds for some scalars x_1, x_2.

Part 1: Reinterpret this vector equation as a system of linear equations.

Part 2: Solve this system. (Remember, you should use a calculator to help find RREF.)

Part 3: Given this solution, does $\begin{bmatrix}-1\\-6\\1\end{bmatrix}$ belong to $\text{span}\left\{\begin{bmatrix}1\\0\\-3\end{bmatrix}, \begin{bmatrix}-1\\-3\\2\end{bmatrix}\right\}$?

Module V Part 3

Fact V.3.1 A vector $\mathbf{b}$ belongs to $\text{span}\{\mathbf{v}_1, \ldots, \mathbf{v}_n\}$ if and only if the linear system corresponding to $[\mathbf{v}_1 \ \ldots \ \mathbf{v}_n \,|\, \mathbf{b}]$ is consistent.

Remark V.3.2 To determine if $\mathbf{b}$ belongs to $\text{span}\{\mathbf{v}_1, \ldots, \mathbf{v}_n\}$, find $\text{RREF}[\mathbf{v}_1 \ \ldots \ \mathbf{v}_n \,|\, \mathbf{b}]$.

Activity V.3.3 *(5 min)* Determine if $\begin{bmatrix} 3 \\ -2 \\ 1 \end{bmatrix}$ belongs to span $\left\{ \begin{bmatrix} 1 \\ 0 \\ -3 \end{bmatrix}, \begin{bmatrix} -1 \\ -3 \\ 2 \end{bmatrix} \right\}$ by row-reducing an appropriate matrix.

Activity V.3.4 *(5 min)* Determine if $\begin{bmatrix} -1 \\ -9 \\ 0 \end{bmatrix}$ belongs to span $\left\{ \begin{bmatrix} 1 \\ 0 \\ -3 \end{bmatrix}, \begin{bmatrix} -1 \\ -3 \\ 2 \end{bmatrix} \right\}$ by row-reducing an appropriate matrix.

Observation V.3.5 So far we've only discussed linear combinations of Euclidean vectors. Fortunately, many vector spaces of interest can be reinterpreted as an **isomorphic** Euclidean space $\mathbb{R}^n$; that is, a Euclidean space that mirrors the behavior of the vector space exactly.

Activity V.3.6 *(5 min)* We previously checked that $\begin{bmatrix} 3 \\ -2 \\ 1 \end{bmatrix}$ does not belong to span $\left\{ \begin{bmatrix} 1 \\ 0 \\ -3 \end{bmatrix}, \begin{bmatrix} -1 \\ -3 \\ 2 \end{bmatrix} \right\}$. Does $f(x) = 3x^2 - 2x + 1$ belong to $\operatorname{span}\{x^2 - 3, -x^2 - 3x + 2\}$?

Activity V.3.7 *(10 min)* Does the matrix $\begin{bmatrix} 6 & 3 \\ 2 & -1 \end{bmatrix}$ belong to span $\left\{ \begin{bmatrix} 1 & 0 \\ 0 & -1 \end{bmatrix}, \begin{bmatrix} 4 & 3 \\ 2 & 1 \end{bmatrix} \right\}$?

Activity V.3.8 *(10 min)* Does the complex number $2i$ belong to $\operatorname{span}\{-3 + i, 6 - 2i\}$?

Activity V.3.9 *(10 min)* How many vectors are required to span $\mathbb{R}^2$? Sketch a drawing in the xy plane to support your answer.

(a) 1

(b) 2

(c) 3

(d) 4

(e) Infinitely Many

Activity V.3.10 *(5 min)* How many vectors are required to span $\mathbb{R}^3$?

(a) 1

(b) 2

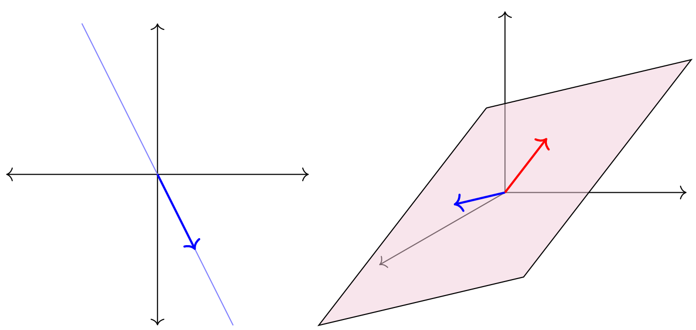
(c) 3

(d) 4

(e) Infinitely Many

Module V Part 4

Fact V.4.1 At least n vectors are required to span $\mathbb{R}^n$.



Activity V.4.2 *(10 min)* Choose a vector $\begin{bmatrix} a \\ b \\ c \end{bmatrix}$ in $\mathbb{R}^3$ that is not in span $\left\{ \begin{bmatrix} 1 \\ -1 \\ 0 \end{bmatrix}, \begin{bmatrix} -2 \\ 0 \\ 1 \end{bmatrix} \right\}$ by ensuring $\left[\begin{array}{cc|c} 1 & -2 & a \\ -1 & 0 & b \\ 0 & 1 & c \end{array}\right] \sim \left[\begin{array}{cc|c} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{array}\right]$. (Why does this work?)

Fact V.4.3 The set $\{\mathbf{v}_1, \dots, \mathbf{v}_m\}$ fails to span all of $\mathbb{R}^n$ exactly when RREF$[\mathbf{v}_1 \dots \mathbf{v}_m]$ has a row of zeros:

$$\begin{bmatrix} 1 & -2 \\ -1 & 0 \\ 0 & 1 \end{bmatrix} \sim \begin{bmatrix} 1 & 0 \\ 0 & 1 \\ 0 & 0 \end{bmatrix} \Rightarrow \left[\begin{array}{cc|c} 1 & -2 & a \\ -1 & 0 & b \\ 0 & 1 & c \end{array}\right] \sim \left[\begin{array}{cc|c} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{array}\right]$$

Activity V.4.4 *(5 min)* Consider the set of vectors $S = \left\{ \begin{bmatrix} 2 \\ 3 \\ 0 \\ -1 \end{bmatrix}, \begin{bmatrix} 1 \\ -4 \\ 3 \\ 0 \end{bmatrix}, \begin{bmatrix} 2 \\ 0 \\ 0 \\ 3 \end{bmatrix}, \begin{bmatrix} 0 \\ 3 \\ 5 \\ 7 \end{bmatrix}, \begin{bmatrix} 3 \\ 13 \\ 7 \\ 16 \end{bmatrix} \right\}$. Does $\mathbb{R}^4 = \operatorname{span} S$?

Activity V.4.5 *(10 min)* Consider the set of third-degree polynomials

$$S = \left\{2x^3 + 3x^2 - 1, 2x^3 + 3, 3x^3 + 13x^2 + 7x + 16, -x^3 + 10x^2 + 7x + 14, 4x^3 + 3x^2 + 2\right\}.$$

Does $\mathcal{P}^3 = \operatorname{span} S$?

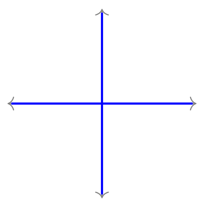
Definition V.4.6 A subset of a vector space is called a **subspace** if it is itself a vector space.

Fact V.4.7 If S is a subset of a vector space V, then $\operatorname{span} S$ is a subspace of V.

Remark V.4.8 To prove that a subset is a subspace, you need only verify that $c\mathbf{v} + d\mathbf{w}$ belongs to the subset for any choice of vectors $\mathbf{v}, \mathbf{w}$ from the subset and any real scalars c, d.

Activity V.4.9 *(5 min)* Prove that $P = \{ax^2 + b : a, b \text{ are both real numbers}\}$ is a subspace of the vector space of all degree-two polynomials by showing that $c(a_1x^2 + b_1) + d(a_2x^2 + b_2)$ belongs to P.

Activity V.4.10 *(10 min)* Consider the subset of $\mathbb{R}^2$ where at least one coordinate of each vector is 0.



Find a linear combination $c\mathbf{v} + d\mathbf{w}$ that does not belong to this subset. **(Instructor Note:)** Use this linear combination to sketch a picture illustrating why this subset is not a subspace.

Fact V.4.11 Suppose a subset S of V is isomorphic to another vector space W. Then S is a subspace of V.

Activity V.4.12 *(5 min)* Show that the set of 2×2 matrices

$$S = \left\{ \begin{bmatrix} a & b \\ -b & -a \end{bmatrix} : a, b \text{ are real numbers} \right\}$$

is a subspace of $\mathbb{R}^{2\times 2}$ by identifying a Euclidean space isomorphic to S.

Module S: Structure of vector spaces

Standards for this Module

What structure do vector spaces have? At the end of this module, students will be able to...

S1. Linear independence. ... determine if a set of Euclidean vectors is linearly dependent or independent.

S2. Basis verification. ... determine if a set of Euclidean vectors is a basis of $\mathbb{R}^n$.

S3. Basis computation. ... compute a basis for the subspace spanned by a given set of Euclidean vectors.

S4. Dimension. ... compute the dimension of a subspace of $\mathbb{R}^n$.

S5. Abstract vector spaces. ... solve exercises related to standards V3-S4 when posed in terms of polynomials or matrices.

S6. Basis of solution space. ... find a basis for the solution set of a homogeneous system of equations.

Module S Part 1

Activity S.1.1 *(15 min)* In the previous module, we considered

$$S = \left\{ \begin{bmatrix} 2 \\ 3 \\ 0 \\ -1 \end{bmatrix}, \begin{bmatrix} 2 \\ 0 \\ 0 \\ 3 \end{bmatrix}, \begin{bmatrix} 3 \\ 13 \\ 7 \\ 16 \end{bmatrix}, \begin{bmatrix} -1 \\ 10 \\ 7 \\ 14 \end{bmatrix}, \begin{bmatrix} 4 \\ 3 \\ 0 \\ 2 \end{bmatrix} \right\}$$

and showed that $\operatorname{span} S \neq \mathbb{R}^4$. Find two vectors from this set that are linear combinations of the other three vectors.
(Instructor Note:) Actually, the activity involved the corresponding vectors in $\mathcal{P}^3$.

Definition S.1.2 We say that a set of vectors is **linearly dependent** if one vector in the set belongs to the span of the others. Otherwise, we say the set is **linearly independent**.

Activity S.1.3 *(10 min)* Suppose $3\mathbf{v}_1 - 5\mathbf{v}_2 = \mathbf{v}_3$, so the set $\{\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3\}$ is linearly dependent. Is the vector equation $x_1\mathbf{v}_1 + x_2\mathbf{v}_2 + x_3\mathbf{v}_3 = \mathbf{0}$ consistent with one solution, consistent with infinitely many solutions, or inconsistent?

Fact S.1.4 The set $\{\mathbf{v}_1, \dots \mathbf{v}_n\}$ is linearly dependent if and only if $x_1\mathbf{v}_1 + \cdots + x_n\mathbf{v}_n = \mathbf{0}$ is consistent with infinitely many solutions.

Activity S.1.5 *(10 min)* Find

$$\operatorname{RREF}\left[\begin{array}{ccccc|c} 2 & 2 & 3 & -1 & 4 & 0 \\ 3 & 0 & 13 & 10 & 3 & 0 \\ 0 & 0 & 7 & 7 & 0 & 0 \\ -1 & 3 & 16 & 14 & 2 & 0 \end{array}\right]$$

and mark the part of the matrix that demonstrates that

$$S = \left\{ \begin{bmatrix} 2 \\ 3 \\ 0 \\ -1 \end{bmatrix}, \begin{bmatrix} 2 \\ 0 \\ 0 \\ 3 \end{bmatrix}, \begin{bmatrix} 3 \\ 13 \\ 7 \\ 16 \end{bmatrix}, \begin{bmatrix} -1 \\ 10 \\ 7 \\ 14 \end{bmatrix}, \begin{bmatrix} 4 \\ 3 \\ 0 \\ 2 \end{bmatrix} \right\}$$

is linearly dependent.

Fact S.1.6 A set of Euclidean vectors $\{\mathbf{v}_1, \dots \mathbf{v}_n\}$ is linearly dependent if and only if RREF $\begin{bmatrix} \mathbf{v}_1 & \dots & \mathbf{v}_n \end{bmatrix}$ has a column without a pivot position.

Activity S.1.7 *(5 min)* Is the set of Euclidean vectors $\left\{ \begin{bmatrix} -4 \\ 2 \\ 3 \\ 0 \\ -1 \end{bmatrix}, \begin{bmatrix} 1 \\ 2 \\ 0 \\ 0 \\ 3 \end{bmatrix}, \begin{bmatrix} 1 \\ 10 \\ 10 \\ 2 \\ 6 \end{bmatrix}, \begin{bmatrix} 3 \\ 4 \\ 7 \\ 2 \\ 1 \end{bmatrix} \right\}$ linearly dependent or linearly independent?

Activity S.1.8 *(10 min)* Is the set of polynomials $\left\{x^3+1, x^2+2, 4-7x, 2x^3+x\right\}$ linearly dependent or linearly independent?

Module S Part 2

Activity S.2.1 *(10 min)* Last time we saw that $\left\{x^3+1, x^2+2, 4-7x, 2x^3+x\right\}$ is linearly independent. Show that it spans $\mathcal{P}^3$.

Definition S.2.2 A **basis** is a linearly independent set that spans a vector space.

Observation S.2.3 A basis may be thought of as a collection of building blocks for a vector space, since every vector in the space can be expressed as a unique linear combination of basis vectors.

Activity S.2.4 *(15 min)* Which of the following sets are bases for $\mathbb{R}^4$?

$$\left\{\begin{bmatrix}1\\0\\0\\0\end{bmatrix},\begin{bmatrix}0\\1\\0\\0\end{bmatrix},\begin{bmatrix}0\\0\\1\\0\end{bmatrix},\begin{bmatrix}0\\0\\0\\1\end{bmatrix}\right\} \qquad \left\{\begin{bmatrix}2\\3\\0\\-1\end{bmatrix},\begin{bmatrix}2\\0\\0\\3\end{bmatrix},\begin{bmatrix}4\\3\\0\\2\end{bmatrix},\begin{bmatrix}-3\\0\\1\\3\end{bmatrix}\right\}$$

$$\left\{\begin{bmatrix}2\\3\\0\\-1\end{bmatrix},\begin{bmatrix}2\\0\\0\\3\end{bmatrix},\begin{bmatrix}3\\13\\7\\16\end{bmatrix},\begin{bmatrix}-1\\10\\7\\14\end{bmatrix},\begin{bmatrix}4\\3\\0\\2\end{bmatrix}\right\} \qquad \left\{\begin{bmatrix}2\\3\\0\\-1\end{bmatrix},\begin{bmatrix}4\\3\\0\\2\end{bmatrix},\begin{bmatrix}-3\\0\\1\\3\end{bmatrix},\begin{bmatrix}3\\6\\1\\5\end{bmatrix}\right\}$$

$$\left\{\begin{bmatrix}5\\3\\0\\-1\end{bmatrix},\begin{bmatrix}-2\\1\\0\\3\end{bmatrix},\begin{bmatrix}4\\5\\1\\3\end{bmatrix}\right\}$$

Activity S.2.5 *(10 min)* If $\{\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3, \mathbf{v}_4\}$ is a basis for $\mathbb{R}^4$, that means RREF$[\mathbf{v}_1\,\mathbf{v}_2\,\mathbf{v}_3\,\mathbf{v}_4]$ doesn't have a column without a pivot position, and doesn't have a row of zeros. What is RREF$[\mathbf{v}_1\,\mathbf{v}_2\,\mathbf{v}_3\,\mathbf{v}_4]$?

Fact S.2.6 The set $\{\mathbf{v}_1, \dots, \mathbf{v}_m\}$ is a basis for $\mathbb{R}^n$ if and only if $m = n$ and RREF$[\mathbf{v}_1\ \dots\ \mathbf{v}_n] = \begin{bmatrix}1 & 0 & \dots & 0\\0 & 1 & \dots & 0\\\vdots & \vdots & \ddots & \vdots\\0 & 0 & \dots & 1\end{bmatrix}$.

That is, a basis for $\mathbb{R}^n$ must have exactly n vectors and its square matrix must row-reduce to the **identity matrix** containing all zeros except for a downward diagonal of ones.

Activity S.2.7 *(10 min)* Consider the set $\left\{\begin{bmatrix}2\\3\\0\\1\end{bmatrix},\begin{bmatrix}2\\0\\1\\-1\end{bmatrix},\begin{bmatrix}2\\-3\\2\\-3\end{bmatrix},\begin{bmatrix}1\\5\\-1\\0\end{bmatrix}\right\}$.

Part 1: Use RREF $\begin{bmatrix}2 & 2 & 2 & 1\\3 & 0 & -3 & 5\\0 & 1 & 2 & -1\\1 & -1 & -3 & 0\end{bmatrix}$ to identify which vector may be removed to make the set linearly independent.

Part 2: Find a basis for span $\left\{\begin{bmatrix}2\\3\\0\\1\end{bmatrix},\begin{bmatrix}2\\0\\1\\-1\end{bmatrix},\begin{bmatrix}2\\-3\\2\\-3\end{bmatrix},\begin{bmatrix}1\\5\\-1\\0\end{bmatrix}\right\}$.

Module S Part 3

Fact S.3.1 To compute a basis for the subspace span$\{\mathbf{v}_1, \dots, \mathbf{v}_m\}$, simply remove the vectors corresponding to the non-pivot columns of RREF$[\mathbf{v}_1\ \dots\ \mathbf{v}_m]$.

Activity S.3.2 *(10 min)* Find all subsets of $S = \left\{ \begin{bmatrix} 2 \\ 3 \\ 0 \\ 1 \end{bmatrix}, \begin{bmatrix} 2 \\ 0 \\ 1 \\ -1 \end{bmatrix}, \begin{bmatrix} 2 \\ -3 \\ 2 \\ -3 \end{bmatrix}, \begin{bmatrix} 1 \\ 5 \\ -1 \\ 0 \end{bmatrix} \right\}$ that are a basis for $\operatorname{span} S$ by changing the order of the vectors in S.

Activity S.3.3 *(10 min)* Assume $\mathbf{w}_1 \neq \mathbf{w}_2$ are distinct vectors in V, which has a basis containing a single vector: $\{\mathbf{v}\}$. Could $\{\mathbf{w}_1, \mathbf{w}_2\}$ be a basis?

Fact S.3.4 All bases for a vector space are the same size.

Definition S.3.5 The **dimension** of a vector space is given by the cardinality/size of any basis for the vector space.

Activity S.3.6 *(15 min)* Find the dimension of each subspace of $\mathbb{R}^4$.

$$\operatorname{span}\left\{ \begin{bmatrix} 1 \\ 0 \\ 0 \\ 0 \end{bmatrix}, \begin{bmatrix} 0 \\ 1 \\ 0 \\ 0 \end{bmatrix}, \begin{bmatrix} 0 \\ 0 \\ 1 \\ 0 \end{bmatrix}, \begin{bmatrix} 0 \\ 0 \\ 0 \\ 1 \end{bmatrix} \right\} \qquad \operatorname{span}\left\{ \begin{bmatrix} 2 \\ 3 \\ 0 \\ -1 \end{bmatrix}, \begin{bmatrix} 2 \\ 0 \\ 0 \\ 3 \end{bmatrix}, \begin{bmatrix} 4 \\ 3 \\ 0 \\ 2 \end{bmatrix}, \begin{bmatrix} -3 \\ 0 \\ 1 \\ 3 \end{bmatrix} \right\}$$

$$\operatorname{span}\left\{ \begin{bmatrix} 2 \\ 3 \\ 0 \\ -1 \end{bmatrix}, \begin{bmatrix} 2 \\ 0 \\ 0 \\ 3 \end{bmatrix}, \begin{bmatrix} 3 \\ 13 \\ 7 \\ 16 \end{bmatrix}, \begin{bmatrix} -1 \\ 10 \\ 7 \\ 14 \end{bmatrix}, \begin{bmatrix} 4 \\ 3 \\ 0 \\ 2 \end{bmatrix} \right\} \qquad \operatorname{span}\left\{ \begin{bmatrix} 2 \\ 3 \\ 0 \\ -1 \end{bmatrix}, \begin{bmatrix} 4 \\ 3 \\ 0 \\ 2 \end{bmatrix}, \begin{bmatrix} -3 \\ 0 \\ 1 \\ 3 \end{bmatrix}, \begin{bmatrix} 3 \\ 6 \\ 1 \\ 5 \end{bmatrix} \right\}$$

$$\operatorname{span}\left\{ \begin{bmatrix} 5 \\ 3 \\ 0 \\ -1 \end{bmatrix}, \begin{bmatrix} -2 \\ 1 \\ 0 \\ 3 \end{bmatrix}, \begin{bmatrix} 4 \\ 5 \\ 1 \\ 3 \end{bmatrix} \right\}$$

Activity S.3.7 *(5 min)* What is the dimension of the vector space of 7th-degree (or less) polynomials $\mathcal{P}^7$?

a) 6 b) 7 c) 8 d) infinite

Activity S.3.8 *(5 min)* What is the dimension of the vector space of all polynomials $\mathcal{P}$?

a) 6 b) 7 c) 8 d) infinite

Observation S.3.9 Several interesting vector spaces are infinite-dimensional:

- The space of polynomials $\mathcal{P}$ (consider the set $\{1, x, x^2, x^3, \dots\}$).
- The space of continuous functions $C(\mathbb{R})$ (which contains all polynomials, in addition to other functions like $e^x = 1 + x + x^2/2 + x^3/3 + \dots$).
- The space of real number sequences $\mathbb{R}^\infty$ (consider the set $\{(1, 0, 0, \dots), (0, 1, 0, \dots), (0, 0, 1, \dots), \dots\}$).

Fact S.3.10 Every vector space with finite dimension, that is, every vector space with a basis of the form $\{\mathbf{v}_1, \mathbf{v}_2, \dots, \mathbf{v}_n\}$ is isomorphic to a Euclidean space $\mathbb{R}^n$:

$$c_1\mathbf{v}_1 + c_2\mathbf{v}_2 + \cdots + c_n\mathbf{v}_n \leftrightarrow \begin{bmatrix} c_1 \\ c_2 \\ \vdots \\ c_n \end{bmatrix}$$