Linear Algebra

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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: Solving Linear Systems.** Solve a system of linear equations.
- **E4: Homogeneous Systems.** Find a basis for the solution set of a homogeneous linear system.

Before beginning this module, each student should be able to...

- Determine if a system to a two-variable system of linear equations will have zero, one, or infinitely-many solutions by graphing.
- Find the unique solution to a two-variable system of linear equations by back-substitution.

The following resources will help you prepare for this module.

- `https://www.khanacademy.org/math/cc-eighth-grade-math/cc-8th-systems-topic/cc-8th-systems-graphically/a/systems-of-equations-with-graphing`
- `https://www.khanacademy.org/math/algebra/systems-of-linear-equations/solving-systems-of-equations-with-substitution/v/practice-using-substitution-for-systems`

Definition

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

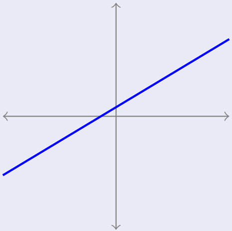
$$\begin{bmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{bmatrix} = \begin{bmatrix} s_1 \\ s_2 \\ \vdots \\ s_n \end{bmatrix}$$

and must satisfy

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

Observation

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

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

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

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

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

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

Remark

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:

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

Verbose standard form:

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

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

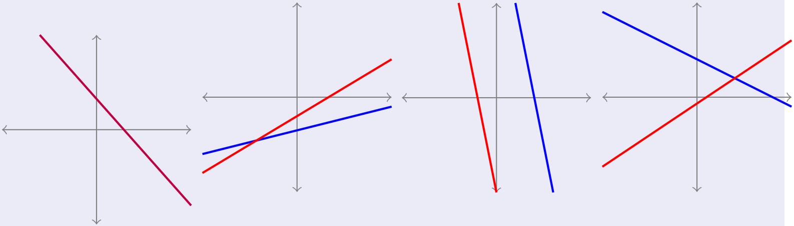
A linear system is **consistent** if there exists a solution for the system. Otherwise it is **inconsistent**.

Fact

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

Activity

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

All inconsistent linear systems contain a logical **contradiction**. Find a contradiction in this system by solving for x_1 in the first equation, substituting the resulting expression into the second equation, and then simplifying.

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

Activity

Consider the following consistent linear system.

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

Part X: 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 X: 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.

Remark

The solution set of a consistent linear system with infinitely many solutions may be described by setting each certain variable equal to an arbitrary parameter, and expressing the other variables in terms of those parameters. (Later we will learn how to do this methodically.)

Activity

Consider the following linear system.

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

Describe the solution set

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

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

Observation

Solving linear systems of two variables by graphing or substitution is reasonable for two-variable systems, but won't cut it for equations with more variables.

Definition

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

$$\begin{array}{ccccccccc} a_{11}x_1 & + & a_{12}x_2 & + & \dots & + & a_{1n}x_n & = & b_1 \\ a_{21}x_1 & + & a_{22}x_2 & + & \dots & + & a_{2n}x_n & = & b_2 \\ \vdots & & \vdots & & & & \vdots & & \vdots \\ a_{m1}x_1 & + & a_{m2}x_2 & + & \dots & + & a_{mn}x_n & = & b_m \end{array} \left[\begin{array}{cccc|c} a_{11} & a_{12} & \cdots & a_{1n} & b_1 \\ a_{21} & a_{22} & \cdots & a_{2n} & b_2 \\ \vdots & \vdots & \ddots & \vdots & \vdots \\ a_{m1} & a_{m2} & \cdots & a_{mn} & b_m \end{array}\right]$$

Definition

Two systems of linear equations (and their corresponding augmented matrices) are said to be **equivalent** if they have the same solution set.

Activity

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 conzero constant.
e) Add a constant multiple of one row to another row.
f) Replace a column with zeros.

Definition

The following **row operations** produce equivalent augmented matrices:

1. Swap two rows.
2. Multiply a row by a conzero 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

Show that the following two linear systems:

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

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 $\frac{1}{3}$.

Definition

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.

Activity

Reproduce the steps that manipulated the matrix

$$\left[\begin{array}{ccc|c} 3 & -2 & 13 & 6 \\ 2 & -2 & 10 & 2 \\ -1 & 3 & -6 & 11 \end{array}\right] \sim \left[\begin{array}{ccc|c} 1 & -1 & 5 & 1 \\ 0 & 1 & -2 & 3 \\ 0 & 0 & 1 & 2 \end{array}\right]$$

into row echelon form by using the following algorithm.

1. Identify the top cell of the first non-zero column as your **pivot position**; you will ignore anything in the matrix that is above or left of your current pivot position.
2. If the pivot position contains a 0, swap its row

can first swap the pivot row with a lower row to make this division easier.)

4. Add multiples of the pivot row to all lower rows so that all terms below pivot position become 0.
5. Move your pivot position down and right one step.
6. If all terms in and below

Definition

A matrix is in **reduced row echelon form** if it is in row echelon form and all terms above leading terms are 0.

Activity

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 performing the following row operations to obtain an augmented matrix equivalent to the second system.

1. Add $2R_3$ to R_2.
2. Add $-5R_3$ to R_1.
3. Add R_2 to R_1.

Then write the solution to the linear system.

Remark

We may verify that $(x_1, x_2, x_3) = (-2, 7, 2)$ 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

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

Definition

The following algorithm that reduces A to $\mathrm{RREF}(A)$ is known as **Gauss-Jordan elimination**.

1. Identify the top cell of the first non-zero column as your pivot position; you will ignore anything in the matrix that is above or left of your current pivot position.
2. If the pivot position contains a 0, swap its row with a lower row that does not contain a 0 in its column.
3. Divide the pivot row by the term in pivot position
4. Add multiples of the pivot row to all lower rows so that all terms below pivot position become 0.
5. Move your pivot position down and right one step.
6. If all terms in and below pivot position are zero, move your pivot position right. Repeat this step as needed.
7. If the matrix is not yet in row echelon form, return to Step 2.

Activity

Find RREF(A) where

$$A = \left[\begin{array}{cccc|c} -1 & 1 & -3 & 2 & 0 \\ 2 & -1 & 5 & 3 & -11 \\ 3 & 2 & 4 & 1 & 1 \\ 0 & 1 & -1 & 1 & 1 \end{array}\right].$$

Definition

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.

Activity

Given the linear system and its equivalent augmented matrices

$$\begin{alignedat}{5} -x_1 &+{} & x_2 &-{} 3x_3 &+{} 2x_4 &= 0 \\ 2x_1 &-{} & x_2 &+{} 5x_3 &+{} 3x_4 &= -11 \\ 3x_1 &+{} & 2x_2 &+{} 4x_3 &+{} x_4 &= 1 \\ & & x_2 &-{} x_3 &+{} x_4 &= 1 \end{alignedat} \qquad \left[\begin{array}{cccc|c} -1 & 1 & -3 & 2 & 0 \\ 2 & -1 & 5 & 3 & -11 \\ 3 & 2 & 4 & 1 & 1 \\ 0 & 1 & -1 & 1 & 1 \end{array}\right] \sim \begin{bmatrix} 1 \\ 0 \\ 0 \\ 0 \end{bmatrix}$$

describe the solution set $\begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ x_4 \end{bmatrix} = a \begin{bmatrix} r_1 \\ r_2 \\ r_3 \\ r_4 \end{bmatrix} + \begin{bmatrix} s_1 \\ s_2 \\ s_3 \\ s_4 \end{bmatrix}$ to the linear system by setting the free variable $x_3 = a$, and then expressing each of the bounded variables x_1, x_2, x_4 equal to an expression in terms of a.

Remark

It's not necessary to completely find RREF(A) to deduce that a linear system is inconsistent.

Activity

Find a contradiction in the inconsistent linear system

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

by considering the following equivalent augmented matrices:

$$\left[\begin{array}{cc|c} 2 & -3 & 17 \\ 1 & 2 & -2 \\ -1 & -1 & 1 \end{array}\right] \sim \left[\begin{array}{cc|c} 1 & 2 & -2 \\ 0 & 1 & 3 \\ 0 & 0 & 2 \end{array}\right].$$

Remark

In Module TODO, we will

Definition

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

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

Activity

Show that all homogeneous systems are consistent by finding a quickly verifiable solution for

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

Fact

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

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

Find a basis for the solution set of the following homogeneous linear system.

$$\begin{alignedat}{5} x_1 &+ 2x_2 & & &-& x_4 &= 0 \\ & & & x_3 &+& 4x_4 &= 0 \\ 2x_1 &+ 4x_2 &+& x_3 &+& 2x_4 &= 0 \end{alignedat}$$

At the end of this module, students will be able to...

- **V1: Vector Spaces.** Determine if a set with given operations forms a vector space.
- **V2: Linear Combinations.** Determine if a vector can be written as a linear combination of a given set of vectors.
- **V3: Spanning Sets.** Determine if a set of vectors spans a vector space.
- **V4: Subspaces.** Determine if a subset of a vector space is a subset or not.

Before beginning this module, each student should be able to...

- Add Euclidean vectors and multiply Euclidean vectors by scalars.
- Add complex numbers and multiply complex numbers by scalars.
- Add polynomials and multiply polynomials by scalars.
- Perform basic manipulations of augmented matrices and linear systems **(Standard(s) E1,E2,E3)**.

The following resources will help you prepare for this module.

- https://www.khanacademy.org/math/precalculus/vectors-precalc/vector-addition-subtraction/v/adding-and-subtracting-vectors
- https://www.khanacademy.org/math/precalculus/vectors-precalc/combined-vector-operations/v/combined-vector-operations-example
- https://www.khanacademy.org/math/precalculus/imaginary-and-complex-numbers/adding-and-subtracting-complex-numbers/v/adding-complex-numbers
- https://www.khanacademy.org/math/algebra/introduction-to-polynomial-expressions/adding-and-subtracting-polynomials/v/adding-and-subtracting-polynomials-1

Activity

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 $\mathbf{m}$
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.**

Definition

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

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

Activity

Consider the following vector space that models motion along the curve $y = e^x$. Let $V = \{(x, y) : y = e^x\}$, where $(a_1, b_1) + (a_2, b_2) = (a_1 + a_2, b_1 b_2)$, and $c(a, b) = (ca, b^c)$.

Part X: Verify that $3((1, e) + (-2, \frac{1}{e^2})) = 3(1, e) + 3(-2, \frac{1}{e^2})$.

Part X: Prove the scalar distribution property for this space: $c(\mathbf{u} + \mathbf{v}) = c\mathbf{u} + c\mathbf{v}$.

Remark

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

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

- **Addition associativity.** $\mathbf{u}+(\mathbf{v}+\mathbf{w}) = (\mathbf{u}+\mathbf{v})+\mathbf{w}$.
- **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

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 $c_1, c_2, \dots, c_m$.

Definition

The **span** of a set of vectors is the collection of all linear combinations of that set:

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

Activity

Consider $\operatorname{span}\left\{\begin{bmatrix}1\\2\end{bmatrix}\right\}$.

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

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

Activity

Consider $\operatorname{span}\left\{\begin{bmatrix}1\\2\end{bmatrix}, \begin{bmatrix}-1\\1\end{bmatrix}\right\}$.

Part X: Sketch $c_1\begin{bmatrix}1\\2\end{bmatrix} + c_2\begin{bmatrix}-1\\1\end{bmatrix}$ in the xy plane for $\begin{bmatrix}c_1\\c_2\end{bmatrix} = \begin{bmatrix}1\\0\end{bmatrix}, \begin{bmatrix}0\\1\end{bmatrix}, \begin{bmatrix}2\\0\end{bmatrix}, \begin{bmatrix}2\\1\end{bmatrix}$.

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

Activity

Sketch a representation of all the vectors given by $\operatorname{span}\left\{\begin{bmatrix}6\\-4\end{bmatrix},\begin{bmatrix}-2\\3\end{bmatrix}\right\}$ in the xy plane.

Activity

The vector $\begin{bmatrix} -1 \\ -6 \\ 1 \end{bmatrix}$ belongs to 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 X: Reinterpret this vector equation as a system of linear equations.

Part X: Solve this system. (From now on, feel free to use a calculator to solve linear systems.)

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

Fact

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

Remark

To determine if $\mathbf{b}$ belongs to $\operatorname{span}\{\mathbf{v}_1, \dots, \mathbf{v}_n\}$, find $\operatorname{RREF}[\mathbf{v}_1 \, \dots \, \mathbf{v}_n \,|\, \mathbf{b}]$.

Activity

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

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

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

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

Activity

Does the matrix $\begin{bmatrix} 6 & 3 \\ 2 & -1 \end{bmatrix}$ belong to $\operatorname{span}\left\{\begin{bmatrix} 1 & 0 \\ 0 & -1 \end{bmatrix}, \begin{bmatrix} 4 & 3 \\ 2 & 1 \end{bmatrix}\right\}$?

Activity

Does the complex number $2i$ belong to $\operatorname{span}\{-3+i, 6-2i\}$?

Activity

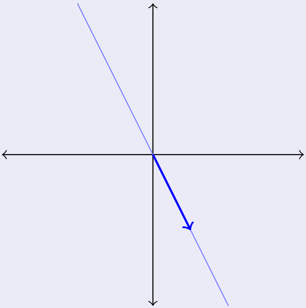
How many vectors are required to span $\mathbb{R}^2$? Sketch a drawing in the xy plane to support your guess.

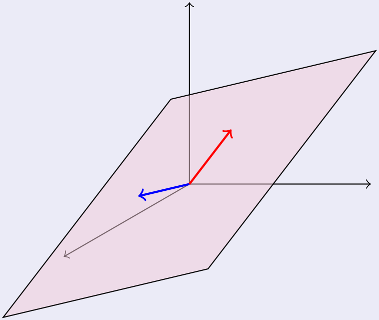
Activity

How many vectors are required to span $\mathbb{R}^3$?

Fact

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





Activity

Find 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 doing the following.

Part X: Choose simple values for x, y, z such that $\left[\begin{array}{cc|c} 1 & 0 & x \\ 0 & 1 & y \\ 0 & 0 & z \end{array}\right]$ represents an inconsistent linear equation.

Part X: Use row operations to manipulate

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

Part X: Write a sentence explaining why $\begin{bmatrix} a \\ b \\ c \end{bmatrix}$ cannot be in span $\left\{ \begin{bmatrix} 1 \\ -1 \\ 0 \end{bmatrix}, \begin{bmatrix} -2 \\ 0 \\ 1 \end{bmatrix} \right\}$.

Fact

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

Activity

Consider the set of vectors $S=\left\{\begin{bmatrix}2\\3\\0\\-1\end{bmatrix},\begin{bmatrix}1\\-4\\3\\0\end{bmatrix},\begin{bmatrix}2\\0\\0\\3\end{bmatrix},\begin{bmatrix}0\\3\\5\\7\end{bmatrix},\begin{bmatrix}3\\13\\7\\16\end{bmatrix}\right\}$. Prove that $\mathbb{R}^4=\operatorname{span} S$.

Activity

Consider the set of third-degree polynomials

$$S = \{2x^3 + 3x^2 - 1, 2x^3 + 3, 3x^3 + 13x^2 + 7x + 16, -x^3 + 10x^2 +$$

Prove that $\mathcal{P}^3 \neq \operatorname{span} S$.

Definition

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

Fact

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

Remark

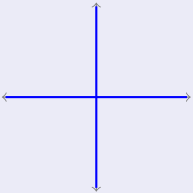
To prove that a subset is a subspace, you need only verify that $c\mathbf{v} + d\mathbf{w}$ belongs to the subset for any choice of vectors $\mathbf{v}, \mathbf{w}$ from the subset and any real scalars c, d.

Activity

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

Consider the subset of $\mathbb{R}^2$ where at least one coordinate of each vector is 0.



Part X: Find a linear combination $c \begin{bmatrix} v_1 \\ v_2 \end{bmatrix} + d \begin{bmatrix} w_1 \\ w_2 \end{bmatrix}$ that does not belong to this subset.

Part X: Use this linear combination to sketch a picture illustrating why this subset is not a subspace.

Fact

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

Activity

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 finding a Euclidean space isomorphic to S.

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 vectors is a basis of a vector space
- **S3. Basis construction** Construct a basis for the subspace spanned by a given set of vectors.
- **S4. Dimension** I can compute the dimension of a vector space.

Before beginning this module, each student should be able to...

- Add Euclidean vectors and multiply Euclidean vectors by scalars.
- Perform basic manipulations of augmented matrices and linear systems **(Standard(s) E1,E2,E3)**.
- Apply linear combinations and spanning sets **(Standard(s) V2)**.

The following resources will help you prepare for this module.

- https://www.khanacademy.org/math/precalculus/vectors-precalc/vector-addition-subtraction/v/adding-and-subtracting-vectors
- https://www.khanacademy.org/math/precalculus/vectors-precalc/combined-vector-operations/v/combined-vector-operations-example

Activity

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 span $S \neq \mathbb{R}^4$. Find two vectors that are in the span of the other three vectors.

Definition

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**.