

**Definition 5.1** An algorithm that reduces  $A$  to  $\text{RREF}(A)$  is called **Gauss-Jordan elimination**. For example:

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.
4. Finally, zero out any terms above pivot positions.

**Definition 5.4** The columns of  $\text{RREF}(A)$  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  $A$ .

**Definition 5.9** A **homogeneous system** is a linear system satisfying  $b_i = 0$ , that is, it is a linear system of the form

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

**Definition 5.11** 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:

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