Linear Algebra and Matrices

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Contents

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Abstract—**This book provides a simple introduction to linear algebra and matrix analysis. The content and exercises are based on NCERT textbooks from Class 6-12.**

1 Line

1.1. Any point $\mathbf{P}$ in the 2-D plane can be expressed in terms of its coordinates (p_1, p_2) as the column vector

$$\mathbf{P} = \begin{pmatrix} p_1 \\ p_2 \end{pmatrix} \tag{1.1.1}$$

1.2. The *direction vector* of the line joining $\mathbf{P}, \mathbf{Q}$ is defined as

$$\mathbf{m} = \mathbf{P} - \mathbf{Q} = \begin{pmatrix} p_1 - q_1 \\ p_2 - q_2 \end{pmatrix} \tag{1.2.1}$$

$$= (p_1 - q_1) \begin{pmatrix} 1 \\ \frac{p_2 - q_2}{p_1 - q_1} \end{pmatrix} = (p_1 - q_1) \begin{pmatrix} 1 \\ m \end{pmatrix} \tag{1.2.2}$$

where

$$m = \frac{p_2 - q_2}{p_1 - q_1}. \tag{1.2.3}$$

Without loss of generality, k$\mathbf{m}$*, for any real scalar k is also a direction vector. In the rest of the paper,* $\mathbf{m}$ *and k*$\mathbf{m}$ *are interchanged for*

computational simplicity. Thus, if m be the slope of the line PQ,

$$\mathbf{m} = \begin{pmatrix} 1 \\ m \end{pmatrix} \qquad (1.2.4)$$

1.3. Let $\mathbf{P}, \mathbf{Q}$ be two points on a line. The vector equation of the line is given by

$$\mathbf{x} = \mathbf{P} + \lambda\mathbf{m}, \quad \lambda \in \mathbb{R} \qquad (1.3.1)$$
$$\mathbf{m} = \mathbf{P} - \mathbf{Q} \qquad (1.3.2)$$

(1.3.1) can be used in 3D as well.

1.4. The *normal vector* $\mathbf{n}$ to a line is orthogonal to the direction vector $\mathbf{m}$ so that

$$\mathbf{m}^T\mathbf{n} = 0 \qquad (1.4.1)$$

If $\mathbf{P}$ be a point on the line, the equation of the line can be expressed as

$$\mathbf{n}^T(\mathbf{x} - \mathbf{P}) = 0 \qquad (1.4.2)$$
$$\text{or, } \mathbf{n}^T\mathbf{x} = c, \qquad (1.4.3)$$

where

$$c = \mathbf{n}^T\mathbf{P} \qquad (1.4.4)$$

which is the desired equation of the straight line. By subsuming the c in (1.4.3) within $\mathbf{n}$, the equation of a line can also be expressed as

$$\mathbf{n}^T\mathbf{x} = 1 \qquad (1.4.5)$$

Note that in 3D, (1.4.2) and (1.4.3) are used to represent the equation of a plane.

1.5. *Orthogonality:* Show that the points

$$\mathbf{A} = \begin{pmatrix} 2 \\ -1 \\ 1 \end{pmatrix}, \mathbf{B} = \begin{pmatrix} 1 \\ -3 \\ -5 \end{pmatrix}, \mathbf{C} = \begin{pmatrix} 3 \\ -4 \\ -4 \end{pmatrix} \qquad (1.5.1)$$

are the vertices of a right angled triangle.
Solution: Let

$$\mathbf{v}_1 = \mathbf{A} - \mathbf{C} = \begin{pmatrix} -1 \\ 3 \\ 5 \end{pmatrix} \qquad (1.5.2)$$

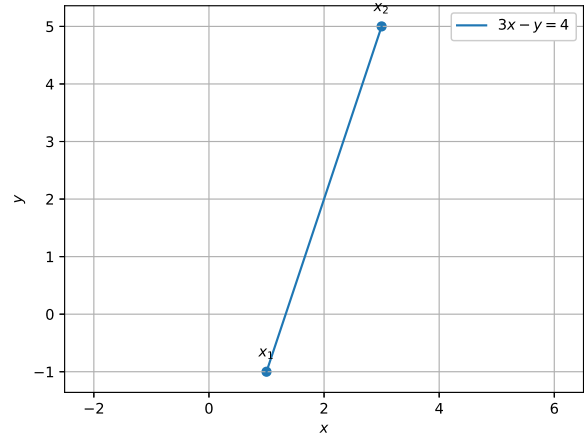$$\mathbf{v}_2 = \mathbf{B} - \mathbf{C} = \begin{pmatrix} -2 \\ 1 \\ -1 \end{pmatrix} \qquad (1.5.3)$$

Fig. 1.6: Line obtained in Problem 1.6.

Then

$$\mathbf{v}_1^T\mathbf{v}_2 = \begin{pmatrix} -1 & 3 & 5 \end{pmatrix}\begin{pmatrix} -2 \\ 1 \\ -1 \end{pmatrix} = 0 \qquad (1.5.4)$$

$$\implies AC \perp BC \qquad (1.5.5)$$

and $\mathbf{v}_1$ and $\mathbf{v}_2$ are said to be orthogonal.

1.6. Find the equation of the line through $\begin{pmatrix} -2 \\ 3 \end{pmatrix}$ with slope - 4
Solution: From (1.2.4), the direction vector is

$$\mathbf{m} = \begin{pmatrix} 1 \\ -4 \end{pmatrix} \qquad (1.6.1)$$

and from (1.4.1), the normal vector is

$$\mathbf{n} = \begin{pmatrix} 4 \\ 1 \end{pmatrix} \qquad (1.6.2)$$

Using (1.4.2), the equation of the line is

$$\begin{pmatrix} 4 & 1 \end{pmatrix}\left\{\mathbf{x} - \begin{pmatrix} -2 \\ 3 \end{pmatrix}\right\} = 0 \qquad (1.6.3)$$

$$\implies \begin{pmatrix} 4 & 1 \end{pmatrix}\mathbf{x} = -5 \qquad (1.6.4)$$

Fig. 1.6 shows the line passing through the given point.

1.7. Write the equation of the line through the points $\mathbf{x}_1 = \begin{pmatrix} 1 \\ -1 \end{pmatrix}$ and $\mathbf{x}_2 = \begin{pmatrix} 3 \\ 5 \end{pmatrix}$.
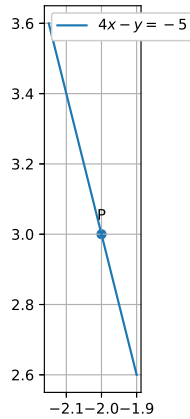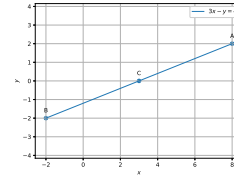
Fig. 1.7: Line obtained in Problem 1.7.

Fig. 1.8: Points on a line and points forming a triangle in Example 1.8.

Thus the equation of the desired line is

$$\frac{1}{4}\begin{pmatrix} 3 & -1 \end{pmatrix} \mathbf{x} = 1 \tag{1.7.11}$$

$$\text{or, } \begin{pmatrix} 3 & -1 \end{pmatrix} \mathbf{x} = 4 \tag{1.7.12}$$

Fig. 1.7 shows the line passing through the given points.

1.8. (*Linear Dependence*) Prove that the three points $\begin{pmatrix} 3 \\ 0 \end{pmatrix}, \begin{pmatrix} -2 \\ -2 \end{pmatrix}, \begin{pmatrix} 8 \\ 2 \end{pmatrix}$ are collinear

Solution: Let

$$
\begin{aligned}
\mathbf{v}_1 &= \begin{pmatrix} 3 \\ 0 \end{pmatrix} - \begin{pmatrix} -2 \\ -2 \end{pmatrix} = \begin{pmatrix} 5 \\ 2 \end{pmatrix} \\
\mathbf{v}_2 &= \begin{pmatrix} -2 \\ -2 \end{pmatrix} - \begin{pmatrix} 8 \\ 2 \end{pmatrix} = \begin{pmatrix} -10 \\ -4 \end{pmatrix}
\end{aligned}
\tag{1.8.1}
$$

Then, the given points are collinear if

$$x_1 \mathbf{v}_1 + x_2 \mathbf{v}_2 = 0 \tag{1.8.2}$$

has a nontrivial solution as well, i.e.

$$\mathbf{x} = \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} \neq \mathbf{0} \tag{1.8.3}$$

Substituting (1.8.1) in (1.8.2) results in the matrix equation

$$\begin{pmatrix} 5 & -10 \\ 2 & -4 \end{pmatrix} \mathbf{x} = 0 \tag{1.8.4}$$

Performing row operations on the matrix,

$$\begin{pmatrix} 5 & -10 \\ 2 & -4 \end{pmatrix} \xrightarrow{R_2 \leftarrow 2R_1 - 5R_2} \begin{pmatrix} 5 & -10 \\ 0 & 0 \end{pmatrix} \tag{1.8.5}$$

which can be expressed as

$$\begin{pmatrix} 5 & -10 \end{pmatrix} \mathbf{x} = 0 \tag{1.8.6}$$

$$\text{or, } \mathbf{x} = x_1 \begin{pmatrix} 1 \\ -2 \end{pmatrix} \tag{1.8.7}$$

Thus, there are infinite solutions. The vectors $\mathbf{v}_1, \mathbf{v}_2$ are are linearly dependent and the given

Solution: From (1.4.5),

$$\mathbf{n}^T \begin{pmatrix} 1 \\ -1 \end{pmatrix} = 1 \tag{1.7.1}$$

$$\mathbf{n}^T \begin{pmatrix} 3 \\ 5 \end{pmatrix} = 1 \tag{1.7.2}$$

resulting in the the matrix equation

$$\begin{pmatrix} 1 & -1 \\ 3 & 5 \end{pmatrix} \mathbf{n} = \begin{pmatrix} 1 \\ 1 \end{pmatrix} \tag{1.7.3}$$

yielding the augmented matrix

$$\begin{pmatrix} 1 & -1 & 1 \\ 3 & 5 & 1 \end{pmatrix} \tag{1.7.4}$$

Performing row reduction,

$$\begin{pmatrix} 1 & -1 & 1 \\ 3 & 5 & 1 \end{pmatrix} \tag{1.7.5}$$

$$\xrightarrow{R_2 \leftarrow R_2 - 3R_1} \begin{pmatrix} 1 & -1 & 1 \\ 0 & 8 & -2 \end{pmatrix} \tag{1.7.6}$$

$$\xrightarrow{R_2 \leftarrow \frac{R_2}{2}} \begin{pmatrix} 1 & -1 & 1 \\ 0 & 4 & -1 \end{pmatrix} \tag{1.7.7}$$

$$\xrightarrow{R_1 \leftarrow 4R_1 + R_2} \begin{pmatrix} 4 & 0 & 3 \\ 0 & 4 & -1 \end{pmatrix} \tag{1.7.8}$$

$$\xrightarrow[R_1 \leftarrow \frac{R_1}{4}]{R_2 \leftarrow \frac{R_2}{4}} \begin{pmatrix} 1 & 0 & \frac{3}{4} \\ 0 & 1 & -\frac{1}{4} \end{pmatrix} \tag{1.7.9}$$

From (1.7.9),

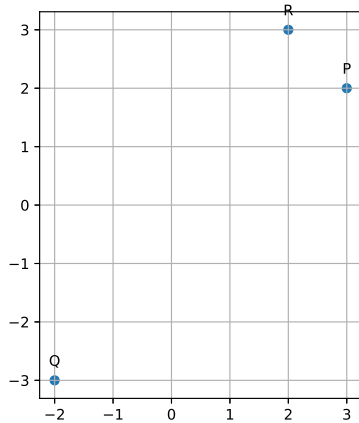$$\mathbf{n} = \frac{1}{4} \begin{pmatrix} 3 \\ -1 \end{pmatrix} \tag{1.7.10}$$

Fig. 1.10: Points on a triangle in Problem 1.10.

points lie on a straight line.

1.9. Alternatively, if the given points are collinear, from (1.4.5),

$$\begin{pmatrix} 3 & 0 \\ -2 & -2 \\ 8 & 2 \end{pmatrix} \mathbf{n} = \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix} \quad (1.9.1)$$

Row reducing the augmented matrix,

$$\begin{pmatrix} 3 & 0 & 1 \\ -2 & -2 & 1 \\ 8 & 2 & 1 \end{pmatrix} \quad (1.9.2)$$

$$\xrightarrow[R_2 \leftarrow 3R_2+2R_1]{R_3 \leftarrow 3R_3-8R_1} \begin{pmatrix} 3 & 0 & 1 \\ 0 & -6 & 5 \\ 0 & 6 & -5 \end{pmatrix} \quad (1.9.3)$$

$$\xrightarrow{R_3 \leftarrow R_3+R_2} \begin{pmatrix} 3 & 0 & 1 \\ 0 & 6 & -5 \\ 0 & 0 & 0 \end{pmatrix} \quad (1.9.4)$$

The above matrix has a zero row in echelon form, hence (1.9.1) is consistent and the given points are on a straight line. Also,

$$\mathbf{n} = \frac{1}{6} \begin{pmatrix} 2 \\ -5 \end{pmatrix} \quad (1.9.5)$$

1.10. (*Linear Independence*) Do the points $\begin{pmatrix} 3 \\ 2 \end{pmatrix}, \begin{pmatrix} -2 \\ -3 \end{pmatrix}, \begin{pmatrix} 2 \\ 3 \end{pmatrix}$ form a triangle?

Solution: In this case

$$\mathbf{v}_1 = \begin{pmatrix} 3 \\ 2 \end{pmatrix} - \begin{pmatrix} -2 \\ -3 \end{pmatrix} = \begin{pmatrix} 5 \\ 5 \end{pmatrix} \quad (1.10.1)$$

$$\mathbf{v}_2 = \begin{pmatrix} -2 \\ -3 \end{pmatrix} - \begin{pmatrix} 2 \\ 3 \end{pmatrix} = \begin{pmatrix} -4 \\ -6 \end{pmatrix} \quad (1.10.2)$$

Thus,

$$x_1\mathbf{v}_1 + x_2\mathbf{v}_2 = 0 \quad (1.10.3)$$

$$\implies \begin{pmatrix} 5 & -4 \\ 5 & -6 \end{pmatrix} \mathbf{x} = 0 \quad (1.10.4)$$

Using row operations,

$$\begin{pmatrix} 5 & -4 \\ 5 & -6 \end{pmatrix} \xrightarrow{R_2 \leftarrow R_1-R_2} \begin{pmatrix} 5 & -4 \\ 0 & 2 \end{pmatrix} \quad (1.10.5)$$

$$\xrightarrow{R_1 \leftarrow R_1+2R_2} \begin{pmatrix} 5 & 0 \\ 0 & 2 \end{pmatrix} \quad (1.10.6)$$

resulting in a *full rank* matrix. Hence,

$$\mathbf{x} = 0 \quad (1.10.7)$$

and $\mathbf{v}_1$ and $\mathbf{v}_2$ are *linearly independent*. The points lie on a triangle.

1.11. Alternatively, from (1.4.5), row reducing the augmented matrix

$$\begin{pmatrix} 3 & 2 & 1 \\ -2 & -3 & 1 \\ 2 & 3 & 1 \end{pmatrix} \xrightarrow{R_3 \leftarrow R_3+R_2} \begin{pmatrix} 3 & 2 & 1 \\ -2 & -3 & 1 \\ 0 & 0 & 2 \end{pmatrix} \quad (1.11.1)$$

The above matrix has a nonzero row in echelon form, hence the given points do not lie on a straight line. So they lie on a triangle.

1.12. Find the angle between the lines

$$\begin{pmatrix} 1 & -\sqrt{3} \end{pmatrix} \mathbf{x} = 5$$
$$\begin{pmatrix} \sqrt{3} & -1 \end{pmatrix} \mathbf{x} = -6. \quad (1.12.1)$$

Solution: The angle between the lines can be expressed in terms of the normal vectors

$$\mathbf{n}_1 = \begin{pmatrix} 1 \\ -\sqrt{3} \end{pmatrix}, \mathbf{n}_2 = \begin{pmatrix} \sqrt{3} \\ -1 \end{pmatrix} \quad (1.12.2)$$

as

$$\cos \theta = \frac{\mathbf{n}_1^T \mathbf{n}_2}{\|\mathbf{n}_1\| \|\mathbf{n}_2\|} \quad (1.12.3)$$

$$= \frac{\sqrt{3}}{2} \implies \theta = 30° \quad (1.12.4)$$

1.13. Find the projection of the vector

$$\mathbf{a} = \begin{pmatrix} 2 \\ 3 \\ 2 \end{pmatrix} \quad (1.13.1)$$

on the vector

$$\mathbf{b} = \begin{pmatrix} 1 \\ 2 \\ 1 \end{pmatrix}. \quad (1.13.2)$$

Solution: If the angle between the vectors be θ, the projection is defined as

$$\mathbf{proj_b a} = (\|\mathbf{a}\| \cos \theta) \frac{\mathbf{b}}{\|\mathbf{b}\|} = \frac{(\mathbf{a}^T \mathbf{b})}{\|\mathbf{b}\|^2} \mathbf{b} \quad (1.13.3)$$

Substituting the values from (1.13.1) and (1.13.2),

$$\mathbf{proj_b a} = \frac{5}{3} \begin{pmatrix} 1 \\ 2 \\ 1 \end{pmatrix} \quad (1.13.4)$$

1.14. (*Reflection*) Assuming that straight lines work as a plane mirror for a point, find the image of the point $\mathbf{P} = \begin{pmatrix} 1 \\ 2 \end{pmatrix}$ in the line

$$L: \quad \begin{pmatrix} 1 & -3 \end{pmatrix} \mathbf{x} = -4. \quad (1.14.1)$$

Solution: From the given equation, the line parameters are

$$\mathbf{n} = \begin{pmatrix} 1 \\ -3 \end{pmatrix}, c = -4, \mathbf{m} = \begin{pmatrix} 3 \\ -1 \end{pmatrix} \quad (1.14.2)$$

Let $\mathbf{R}$ be the reflection of $\mathbf{P}$ such that PR bisects the line L at $\mathbf{Q}$. Then $\mathbf{Q}$ bisects PR. This leads to the following equations

$$2\mathbf{Q} = \mathbf{P} + \mathbf{R} \quad (1.14.3)$$

$$\mathbf{n}^T \mathbf{Q} = c \quad \because \mathbf{Q} \text{ lies on the given line} \quad (1.14.4)$$

$$\mathbf{m}^T \mathbf{R} = \mathbf{m}^T \mathbf{P} \quad \because \mathbf{m} \perp \mathbf{P} - \mathbf{R} \quad (1.14.5)$$

From (1.14.3) and (1.14.4),

$$\mathbf{n}^T \mathbf{R} = 2c - \mathbf{n}^T \mathbf{P} \quad (1.14.6)$$

From (1.14.6) and (1.14.5),

$$\begin{pmatrix} \mathbf{m} & \mathbf{n} \end{pmatrix}^T \mathbf{R} = \begin{pmatrix} \mathbf{m} & -\mathbf{n} \end{pmatrix}^T \mathbf{P} + \begin{pmatrix} 0 \\ 2c \end{pmatrix} \quad (1.14.7)$$

Letting

$$\mathbf{V} = \begin{pmatrix} \mathbf{m} & \mathbf{n} \end{pmatrix} \quad (1.14.8)$$

with the condition that $\mathbf{m}, \mathbf{n}$ are orthonormal, i.e.

$$\mathbf{V}^T \mathbf{V} = \mathbf{I} \quad (1.14.9)$$

Noting that

$$\begin{pmatrix} \mathbf{m} & -\mathbf{n} \end{pmatrix} = \begin{pmatrix} \mathbf{m} & \mathbf{n} \end{pmatrix} \begin{pmatrix} 1 & 0 \\ 0 & -1 \end{pmatrix}, \quad (1.14.10)$$

(1.14.7) can be expressed as

$$\mathbf{V}^T \mathbf{R} = \left[\mathbf{V} \begin{pmatrix} 1 & 0 \\ 0 & -1 \end{pmatrix} \right]^T \mathbf{P} + \begin{pmatrix} 0 \\ 2c \end{pmatrix} \quad (1.14.11)$$

$$\implies \mathbf{R} = \left[\mathbf{V} \begin{pmatrix} 1 & 0 \\ 0 & -1 \end{pmatrix} \mathbf{V}^{-1} \right]^T \mathbf{P} + \mathbf{V} \begin{pmatrix} 0 \\ 2c \end{pmatrix} \quad (1.14.12)$$

$$= \mathbf{V} \begin{pmatrix} 1 & 0 \\ 0 & -1 \end{pmatrix} \mathbf{V}^T \mathbf{P} + 2c\mathbf{n} \quad (1.14.13)$$

upon substituting from (1.14.8) in (1.14.13). It can be verified that the reflection is also given by

$$\mathbf{R} = \begin{pmatrix} \mathbf{m} & \mathbf{n} \end{pmatrix} \begin{pmatrix} 1 & 0 \\ 0 & -1 \end{pmatrix} \begin{pmatrix} \mathbf{m} & \mathbf{n} \end{pmatrix}^T \mathbf{P} + 2c\mathbf{n} \quad (1.14.14)$$

$$= \begin{pmatrix} \mathbf{m} & -\mathbf{n} \end{pmatrix} \begin{pmatrix} \mathbf{m}^T \\ \mathbf{n}^T \end{pmatrix} \mathbf{P} + 2c\mathbf{n} \quad (1.14.15)$$

$$\implies \mathbf{R} = \begin{pmatrix} \mathbf{m}\mathbf{m}^T - \mathbf{n}\mathbf{n}^T \end{pmatrix} \mathbf{P} + 2c\mathbf{n} \quad (1.14.16)$$

If $\mathbf{m}, \mathbf{n}$ are not orthonormal, (1.14.16) can be expressed as

$$\frac{\mathbf{R}}{2} = \frac{\mathbf{m}\mathbf{m}^T - \mathbf{n}\mathbf{n}^T}{\mathbf{m}^T \mathbf{m} + \mathbf{n}^T \mathbf{n}} \mathbf{P} + c\frac{\mathbf{n}}{\|\mathbf{n}\|^2} \quad (1.14.17)$$

1.15. (*Gram-schmidt orthogonalization*) Let

$$\alpha = \begin{pmatrix} 3 \\ -1 \\ 0 \end{pmatrix} \quad (1.15.1)$$

$$\beta = \begin{pmatrix} 2 \\ 1 \\ -3 \end{pmatrix} \quad (1.15.2)$$

Find β_1, β_2 such that

$$\beta = \beta_1 + \beta_2, \quad \beta_1 \parallel \alpha, \beta_2 \perp \alpha \quad (1.15.3)$$

Solution: Let $\beta_1 = k\alpha$. Then, $\beta_1 \parallel \alpha$ and

$$\beta = k\alpha + \beta_2 \qquad (1.15.4)$$

$$\implies \alpha^T\beta = k\|\alpha\|^2 + k\beta_1^T\beta_2 \qquad (1.15.5)$$

$$\text{or, } k = \frac{\alpha^T\beta}{\|\alpha\|^2}, \quad \because \beta_1 \perp \beta_2 \qquad (1.15.6)$$

Thus,

$$\beta_1 = \frac{\alpha^T\beta}{\|\alpha\|^2}\alpha = \frac{1}{2}\begin{pmatrix} 3 \\ -1 \\ 0 \end{pmatrix} \qquad (1.15.7)$$

$$\beta_2 = \beta - \beta_1 = \begin{pmatrix} 2 \\ 1 \\ -3 \end{pmatrix} - \frac{1}{2}\begin{pmatrix} 3 \\ -1 \\ 0 \end{pmatrix} = \frac{1}{2}\begin{pmatrix} 1 \\ 3 \\ -6 \end{pmatrix}$$
$$(1.15.8)$$

Thus, any given set of vectors can be expressed as a linear combination of another set of orthogonal vectors.

2 PLANE

2.1. Find the equation of a plane passing through the points $\mathbf{a} = \begin{pmatrix} 2 \\ 5 \\ -3 \end{pmatrix}, \mathbf{b} = \begin{pmatrix} -2 \\ -3 \\ 5 \end{pmatrix}$ and $\mathbf{c} = \begin{pmatrix} 5 \\ 3 \\ -3 \end{pmatrix}$

Solution: The equation of plane is also given by (1.4.5) in 3D. Following the approach in the previous example results in the matrix equation,

$$\begin{pmatrix} 2 & 5 & -3 \\ -2 & -3 & 5 \\ 5 & 3 & -3 \end{pmatrix}\mathbf{n} = \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix} \qquad (2.1.1)$$

Row reducing the augmented matrix,

$$\begin{pmatrix} 2 & 5 & -3 & 1 \\ -2 & -3 & 5 & 1 \\ 5 & 3 & -3 & 1 \end{pmatrix} \qquad (2.1.2)$$

$$\xrightarrow[R_3 \leftarrow 2R_3 - 5R_1]{R_2 \leftarrow \frac{R_2+R_1}{2}} \begin{pmatrix} 2 & 5 & -3 & 1 \\ 0 & 1 & 1 & 1 \\ 0 & -19 & 9 & -3 \end{pmatrix} \qquad (2.1.3)$$

$$\xrightarrow[R_3 \leftarrow \frac{R_3+19R_2}{4}]{R_1 \leftarrow R_1 - 5R_2} \begin{pmatrix} 2 & 0 & -8 & -4 \\ 0 & 1 & 1 & 1 \\ 0 & 0 & 7 & 4 \end{pmatrix} \qquad (2.1.4)$$

$$\xrightarrow[R_3 \leftarrow 7R_2 - R_3]{R_1 \leftarrow \frac{7R_1+8R_3}{2}} \begin{pmatrix} 7 & 0 & 0 & 2 \\ 0 & 7 & 0 & 3 \\ 0 & 0 & 7 & 4 \end{pmatrix} \qquad (2.1.5)$$

$$\implies \mathbf{n} = \frac{1}{7}\begin{pmatrix} 2 \\ 3 \\ 4 \end{pmatrix} \qquad (2.1.6)$$

Thus, the equation of the plane passing through the given points is

$$\begin{pmatrix} 2 & 3 & 4 \end{pmatrix}\mathbf{x} = 7 \qquad (2.1.7)$$

2.2. Find the angle between the two planes

$$\begin{pmatrix} 2 & 1 & -2 \end{pmatrix}\mathbf{x} = 5 \qquad (2.2.1)$$

$$\begin{pmatrix} 3 & -6 & -2 \end{pmatrix}\mathbf{x} = 7 \qquad (2.2.2)$$

Solution: The angle between two planes is the same as the angle between their normal vectors. For

$$\mathbf{n}_1 = \begin{pmatrix} 2 \\ 1 \\ -2 \end{pmatrix} \mathbf{n}_2 = \begin{pmatrix} 3 \\ -6 \\ -2 \end{pmatrix} \qquad (2.2.3)$$

using (1.12.3),

$$\cos\theta = \frac{6 - 6 + 4}{\sqrt{9}\sqrt{49}} = \frac{4}{21} \qquad (2.2.4)$$

3 PSEUDO INVERSE

3.1. To find the shortest distance between the lines

$$L_1 : \mathbf{x} = \begin{pmatrix} 1 \\ 2 \\ 1 \end{pmatrix} + \lambda_1\begin{pmatrix} 1 \\ -1 \\ 1 \end{pmatrix} \qquad (3.1.1)$$

$$L_2 : \mathbf{x} = \begin{pmatrix} 2 \\ -1 \\ -1 \end{pmatrix} + \lambda_2\begin{pmatrix} 2 \\ 1 \\ 2 \end{pmatrix} \qquad (3.1.2)$$

3.2. If the two lines intersect,

$$\mathbf{x}_1 + \lambda_1 \mathbf{m}_1 = \mathbf{x}_2 + \lambda_2 \mathbf{m}_2 \qquad (3.2.1)$$

$$\implies \begin{pmatrix} \mathbf{m}_1 & \mathbf{m}_2 \end{pmatrix} \begin{pmatrix} \lambda_1 \\ -\lambda_2 \end{pmatrix} = \mathbf{x}_2 - \mathbf{x}_1 \qquad (3.2.2)$$

$$\text{or, } \mathbf{M} \begin{pmatrix} \lambda_1 \\ -\lambda_2 \end{pmatrix} = \mathbf{x}_2 - \mathbf{x}_1 \qquad (3.2.3)$$

where

$$\mathbf{x}_1 = \begin{pmatrix} 1 \\ 2 \\ 1 \end{pmatrix}, \mathbf{x}_2 = \begin{pmatrix} 2 \\ -1 \\ -1 \end{pmatrix}, \mathbf{m}_1 = \begin{pmatrix} 1 \\ -1 \\ 1 \end{pmatrix}, \mathbf{m}_2 = \begin{pmatrix} 2 \\ 1 \\ 2 \end{pmatrix}.$$
$$(3.2.4)$$

$$\mathbf{M} = \begin{pmatrix} \mathbf{m}_1 & \mathbf{m}_2 \end{pmatrix} \qquad (3.2.5)$$

(3.2.3) can be expressed as the matrix equation

$$\begin{pmatrix} 1 & 2 \\ -1 & 1 \\ 1 & 2 \end{pmatrix} \mathbf{x} = \begin{pmatrix} 1 \\ -3 \\ -2 \end{pmatrix} \qquad (3.2.6)$$

From the augmented matrix in (3.2.3),

$$\begin{pmatrix} 1 & -2 & 1 \\ -1 & -1 & -3 \\ 1 & -2 & -2 \end{pmatrix} \qquad (3.2.7)$$

$$\begin{pmatrix} 1 & -2 & 1 \\ -1 & -1 & -3 \\ 1 & -2 & -2 \end{pmatrix} \xleftarrow{R_1 = R_1 - R_2} \begin{pmatrix} 0 & 0 & 3 \\ -1 & -1 & -3 \\ 1 & -2 & -2 \end{pmatrix} \qquad (3.2.8)$$

The above matrix has a *rank* = 3. Hence the lines do not intersect.

3.3. Let

$$\mathbf{A} = \mathbf{x}_1 + \lambda_1 \mathbf{m}_1 \qquad (3.3.1)$$

$$\mathbf{B} = \mathbf{x}_2 + \lambda_2 \mathbf{m}_2 \qquad (3.3.2)$$

be the closest points on L_1 and L_2 respectively. Then the shortest distance between two skew lines will be the length of line perpendicular to both the lines L_1, L_2 and passing through A and B. Thus,

$$\mathbf{m}_1{}^T (\mathbf{A} - \mathbf{B}) = 0 \qquad (3.3.3)$$

$$\mathbf{m}_2{}^T (\mathbf{A} - \mathbf{B}) = 0 \qquad (3.3.4)$$

$$\implies \mathbf{M}^T (\mathbf{A} - \mathbf{B}) = 0 \qquad (3.3.5)$$

From (3.3.2) and (3.2.5)

$$\mathbf{A} - \mathbf{B} = \mathbf{x}_1 - \mathbf{x}_2 + \mathbf{M} \begin{pmatrix} \lambda_1 \\ -\lambda_2 \end{pmatrix} \qquad (3.3.6)$$

and using (3.3.5), in the above,

$$\mathbf{M}^T \mathbf{M} \begin{pmatrix} \lambda_1 \\ -\lambda_2 \end{pmatrix} = \mathbf{M}^T (\mathbf{x}_2 - \mathbf{x}_1) \qquad (3.3.7)$$

3.4. Substituting the values from (3.2.4) in (3.3.7) and forming the augmented matrix,

$$\begin{pmatrix} 3 & 3 & 2 \\ 3 & 9 & -5 \end{pmatrix} \qquad (3.4.1)$$

$$\begin{pmatrix} 3 & 3 & 2 \\ 3 & 9 & -5 \end{pmatrix} \xrightarrow{R_2 = R_2 - R_1} \begin{pmatrix} 3 & 3 & 2 \\ 0 & 6 & -7 \end{pmatrix} \qquad (3.4.2)$$

$$\begin{pmatrix} 3 & 3 & 2 \\ 0 & 6 & -7 \end{pmatrix} \xleftarrow{R_1 = 2R_1 - R_2} \begin{pmatrix} 6 & 0 & 11 \\ 0 & 6 & -7 \end{pmatrix} \qquad (3.4.3)$$

$$\begin{pmatrix} 6 & 0 & 11 \\ 0 & 6 & -7 \end{pmatrix} \xleftarrow{R_1 = \frac{R_1}{6}, R_2 = \frac{R_2}{6}} \begin{pmatrix} 1 & 0 & \frac{11}{6} \\ 0 & 1 & \frac{-7}{6} \end{pmatrix} \qquad (3.4.4)$$

$$\lambda_1 = \frac{11}{6}, \lambda_2 = \frac{7}{6} \qquad (3.4.5)$$

yielding

$$A = \frac{1}{6} \begin{pmatrix} 17 \\ 1 \\ 17 \end{pmatrix}, B = \frac{1}{6} \begin{pmatrix} 26 \\ 1 \\ 8 \end{pmatrix}. \qquad (3.4.6)$$

3.5. The distance is then obtained as

$$\|\mathbf{B} - \mathbf{A}\| = \frac{3}{\sqrt{2}} \qquad (3.5.1)$$

Fig. 3.5 shows the various points and distances between the lines.

4 QUADRATIC FORMS

4.1. The general equation of second degree is given by

$$ax^2 + 2bxy + cy^2 + 2dx + 2ey + f = 0 \quad (4.1.1)$$

and can be expressed as

$$\mathbf{x}^T \mathbf{V} \mathbf{x} + 2\mathbf{u}^T \mathbf{x} + f = 0 \qquad (4.1.2)$$

where

$$\mathbf{V} = \mathbf{V}^T = \begin{pmatrix} a & b \\ b & c \end{pmatrix} \qquad (4.1.3)$$

$$\mathbf{u} = \begin{pmatrix} d & e \end{pmatrix} \qquad (4.1.4)$$
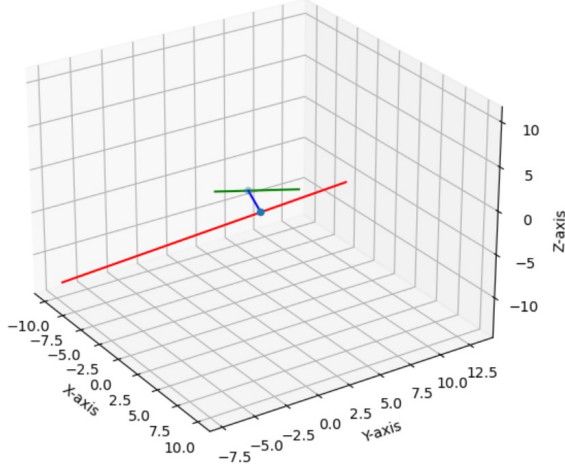
Fig. 3.5: This is the plot of the given skew lines and the blue line indicates the normal to the given lines

4.2. *(Affine Transformation and Eigenvalue Decompostion)* Using

$$\mathbf{x} = \mathbf{P}\mathbf{y} + \mathbf{c} \quad \text{(Affine Transformation)} \quad (4.2.1)$$

such that

$$\mathbf{P}^T\mathbf{V}\mathbf{P} = \mathbf{D}. \quad \text{(Eigenvalue Decomposition)} \quad (4.2.2)$$

$$\mathbf{D} = \begin{pmatrix} \lambda_1 & 0 \\ 0 & \lambda_2 \end{pmatrix}, \quad (4.2.3)$$

$$\mathbf{P} = \begin{pmatrix} \mathbf{p}_1 & \mathbf{p}_2 \end{pmatrix}, \quad \mathbf{P}^T = \mathbf{P}^{-1} \quad (4.2.4)$$

(4.1.2) can be expressed as

$$\mathbf{y}^T\mathbf{D}\mathbf{y} = \mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f \qquad |V| \neq 0 \quad (4.2.5)$$

$$\mathbf{y}^T\mathbf{D}\mathbf{y} = -\eta\begin{pmatrix} 1 & 0 \end{pmatrix}\mathbf{y} \qquad |V| = 0 \quad (4.2.6)$$

with

$$\mathbf{c} = -\mathbf{V}^{-1}\mathbf{u} \qquad |V| \neq 0 \quad (4.2.7)$$

$$\begin{pmatrix} \mathbf{u}^T + \eta\mathbf{p}_1^T \\ \mathbf{V} \end{pmatrix}\mathbf{c} = \begin{pmatrix} -f \\ \eta\mathbf{p}_1 - \mathbf{u} \end{pmatrix} \quad |V| = 0 \quad (4.2.8)$$

$$\text{where } \eta = \mathbf{n}^T\mathbf{p}_1 \quad (4.2.9)$$

Solution: Proofs for (4.2.5), (4.2.6), (4.2.7) and (4.2.8) are available in Appendix A.

4.3. *(Centre/Vertex)* The centre/vertex of the conic section in (4.1.2) is given by $\mathbf{c}$ in (4.2.7) or (4.2.8). This is because from (4.2.1),

$$\mathbf{y} = \mathbf{P}^T(\mathbf{x} - \mathbf{c}) \quad (4.3.1)$$

and

$$\mathbf{y} = \mathbf{0} \implies \mathbf{x} = \mathbf{c} \quad (4.3.2)$$

4.4. *(Circle)* For a circle,

$$\mathbf{V} = \mathbf{D} = \mathbf{P} = \mathbf{I} \quad (4.4.1)$$

and the centre is obtained from (4.2.7), (4.3.2) as

$$\mathbf{c} = -\mathbf{u} \quad (4.4.2)$$

(4.2.5) becomes

$$\mathbf{y}^T\mathbf{y} = \|\mathbf{y}\|^2 = \left(\sqrt{\mathbf{u}^T\mathbf{u} - f}\right)^2 \quad (4.4.3)$$

and the radius is

$$\sqrt{\mathbf{u}^T\mathbf{u} - f} \quad (4.4.4)$$

4.5. *(Ellipse)* For

$$|\mathbf{V}| > 0, \quad \text{or, } \lambda_1 > 0, \lambda_2 > 0 \quad (4.5.1)$$

and (4.2.5) becomes

$$\lambda_1 y_1^2 + \lambda_2 y_1^2 = \mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f \quad (4.5.2)$$

which is the equation of an ellipse with major and minor axes parameters

$$\sqrt{\frac{\lambda_1}{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f}}, \sqrt{\frac{\lambda_2}{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f}}. \quad (4.5.3)$$

The centre is obtained from (4.3.2) as (4.2.7).

4.6. *(Hyperbola)* For

$$|\mathbf{V}| < 0, \quad \text{or, } \lambda_1 > 0, \lambda_2 < 0 \quad (4.6.1)$$

and (4.2.5) becomes

$$\lambda_1 y_1^2 - (-\lambda_2) y_1^2 = \mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f \quad (4.6.2)$$

with major and minor axes parameters

$$\sqrt{\frac{\lambda_1}{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f}}, \sqrt{\frac{\lambda_2}{f - \mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}}}, \quad (4.6.3)$$

The centre is obtained from (4.3.2) as (4.2.7).

4.7. *(Pair of straight lines:)* In (4.6.2), if

$$\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f = 0, \quad (4.7.1)$$

$$\left(\sqrt{\lambda_1} \quad \pm\sqrt{\lambda_2}\right)\mathbf{y} = 0 \quad (4.7.2)$$

and the hyperbola reduces to a pair of straight

lines given by

$$\left(\sqrt{\lambda_1}\ \pm\sqrt{\lambda_2}\right)\mathbf{P}^T\left(\mathbf{x}-\mathbf{c}\right)=0 \qquad (4.7.3)$$

and $\mathbf{c}$ is the point of intersection of the lines. Apart from (4.7.1), another condition for (4.1.2) to represent a pair of straight lines is

$$\begin{vmatrix}\mathbf{V} & \mathbf{u}\\ \mathbf{u}^T & f\end{vmatrix}=0 \qquad (4.7.4)$$

4.8. *(Parabola)* For

$$|\mathbf{V}|=0,\quad \text{or,}\ \lambda_1=0. \qquad (4.8.1)$$

The vertex of the parabola is obtained using (4.2.8) and the focal length is

$$\left|\frac{2\mathbf{p}_1^T\mathbf{u}}{\lambda_2}\right| \qquad (4.8.2)$$

5 TANGENTS AND NORMALS

5.1. *Secant:* The points of intersection of the line

$$L:\quad \mathbf{x}=\mathbf{q}+\mu\mathbf{m}\quad \mu\in\mathbb{R} \qquad (5.1.1)$$

with the conic section in (4.1.2) are given by

$$\mathbf{x}_i=\mathbf{q}+\mu_i\mathbf{m} \qquad (5.1.2)$$

where

$$\mu_i=\frac{1}{\mathbf{m}^T\mathbf{Vm}}\left(-\mathbf{m}^T\left(\mathbf{Vq}+\mathbf{u}\right)\right.$$
$$\left.\pm\ \sqrt{\left[\mathbf{m}^T\left(\mathbf{Vq}+\mathbf{u}\right)\right]^2-\left(\mathbf{q}^T\mathbf{Vq}+2\mathbf{u}^T\mathbf{q}+f\right)\left(\mathbf{m}^T\mathbf{Vm}\right)}\right) \qquad (5.1.3)$$

Solution: Substituting (5.1.1) in (4.1.2),

$$(\mathbf{q}+\mu\mathbf{m})^T\mathbf{V}(\mathbf{q}+\mu\mathbf{m})+2\mathbf{u}^T(\mathbf{q}+\mu\mathbf{m})+f=0$$
$$\implies \mu^2\mathbf{m}^T\mathbf{Vm}+2\mu\mathbf{m}^T(\mathbf{Vq}+\mathbf{u})$$
$$+\mathbf{q}^T\mathbf{Vq}+2\mathbf{u}^T\mathbf{q}+f=0 \quad (5.1.4)$$

Solving the above quadratic in (5.1.4) yields (5.1.3).

5.2. *Tangent:* If L in (5.1.1) touches (4.1.2) at exactly one point $\mathbf{q}$,

$$\mathbf{m}^T\left(\mathbf{Vq}+\mathbf{u}\right)=0 \qquad (5.2.1)$$

Solution: In this case, (5.1.4) has exactly one root. Hence, in (5.1.3)

$$\left[\mathbf{m}^T\left(\mathbf{Vq}+\mathbf{u}\right)\right]^2$$
$$-\left(\mathbf{m}^T\mathbf{Vm}\right)\left(\mathbf{q}^T\mathbf{Vq}+2\mathbf{u}^T\mathbf{q}+f\right)=0 \quad (5.2.2)$$

$\because$ $\mathbf{q}$ is the point of contact, $\mathbf{q}$ satisfies (4.1.2) and

$$\mathbf{q}^T\mathbf{Vq}+2\mathbf{u}^T\mathbf{q}+f=0 \qquad (5.2.3)$$

Substituting (5.2.3) in (5.2.2) and simplifying, we obtain (5.2.1).

5.3. The normal vector is obtained from (5.2.1) and (1.4.1) as

$$\mathbf{n}=\mathbf{Vq}+\mathbf{u} \qquad (5.3.1)$$

5.4. Given the point of contact $\mathbf{q}$, the equation of a tangent is

$$(\mathbf{Vq}+\mathbf{u})^T\mathbf{x}+\mathbf{u}^T\mathbf{q}+f=0 \qquad (5.4.1)$$

Solution: From (5.3.1) and (1.4.2), the equation of the tangent is

$$(\mathbf{Vq}+\mathbf{u})^T\left(\mathbf{x}-\mathbf{q}\right)=0 \quad (5.4.2)$$
$$\implies (\mathbf{Vq}+\mathbf{u})^T\mathbf{x}-\mathbf{q}^T\mathbf{Vq}-\mathbf{u}^T\mathbf{q}=0 \quad (5.4.3)$$

which, upon substituting from (5.2.3) and simplifying yields (5.1.1).

5.5. If $\mathbf{V}^{-1}$ exists, given the normal vector $\mathbf{n}$, the tangent points of contact to (4.1.2) are given by

$$\mathbf{q}_i=\mathbf{V}^{-1}\left(\kappa_i\mathbf{n}-\mathbf{u}\right),i=1,2 \qquad (5.5.1)$$

where $\kappa_i=\pm\sqrt{\dfrac{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}-f}{\mathbf{n}^T\mathbf{V}^{-1}\mathbf{n}}} \qquad (5.5.2)$

Solution: From (5.3.1),

$$\mathbf{q}=\mathbf{V}^{-1}\left(\kappa\mathbf{n}-\mathbf{u}\right),\quad \kappa\in\mathbb{R} \qquad (5.5.3)$$

Substituting (5.5.3) in (5.2.3),

$$(\kappa\mathbf{n}-\mathbf{u})^T\mathbf{V}^{-1}\left(\kappa\mathbf{n}-\mathbf{u}\right)$$
$$+2\mathbf{u}^T\mathbf{V}^{-1}\left(\kappa\mathbf{n}-\mathbf{u}\right)+f=0$$
$$\implies \kappa^2\mathbf{n}^T\mathbf{V}^{-1}\mathbf{n}-\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}+f=0$$
$$\text{or,}\ \kappa=\pm\sqrt{\frac{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}-f}{\mathbf{n}^T\mathbf{V}^{-1}\mathbf{n}}} \qquad (5.5.4)$$

Substituting (5.5.4) in (5.5.3) yields (5.5.2).

5.6. If $\mathbf{V}$ is not invertible, given the normal vector $\mathbf{n}$, the point of contact to (4.1.2) is given by

the matrix equation

$$\begin{pmatrix} \mathbf{u} + \kappa \mathbf{n}^T \\ \mathbf{V} \end{pmatrix} \mathbf{q} = \begin{pmatrix} -f \\ \kappa \mathbf{n} - \mathbf{u} \end{pmatrix} \quad (5.6.1)$$

where $\kappa = \dfrac{\mathbf{p}_1^T \mathbf{u}}{\mathbf{p}_1^T \mathbf{n}}, \quad \mathbf{V}\mathbf{p}_1 = 0 \quad (5.6.2)$

Solution: If $\mathbf{V}$ is non-invertible, it has a zero eigenvalue. If the corresponding eigenvector is $\mathbf{p}_1$, then,

$$\mathbf{V}\mathbf{p}_1 = 0 \quad (5.6.3)$$

From (5.3.1),

$$\kappa \mathbf{n} = \mathbf{V}\mathbf{q} + \mathbf{u}, \quad \kappa \in \mathbb{R} \quad (5.6.4)$$
$$\implies \kappa \mathbf{p}_1^T \mathbf{n} = \mathbf{p}_1^T \mathbf{V}\mathbf{q} + \mathbf{p}_1^T \mathbf{u} \quad (5.6.5)$$
$$\text{or, } \kappa \mathbf{p}_1^T \mathbf{n} = \mathbf{p}_1^T \mathbf{u}, \quad \because \mathbf{p}_1^T \mathbf{V} = 0, \quad (5.6.6)$$
$$\text{from (5.6.3)} \quad (5.6.7)$$

yielding κ in (5.6.2). From (5.6.4),

$$\kappa \mathbf{q}^T \mathbf{n} = \mathbf{q}^T \mathbf{V}\mathbf{q} + \mathbf{q}^T \mathbf{u} \quad (5.6.8)$$
$$\implies \kappa \mathbf{q}^T \mathbf{n} = -f - \mathbf{q}^T \mathbf{u} \quad \text{from (5.2.3),} \quad (5.6.9)$$
$$\text{or, } (\kappa \mathbf{n} + \mathbf{u})\mathbf{q} = -f \quad (5.6.10)$$

(5.6.4) can be expressed as

$$\mathbf{V}\mathbf{q} = \kappa \mathbf{n} - \mathbf{u}. \quad (5.6.11)$$

(5.6.10) and (5.6.11) clubbed together result in (5.6.1).

5.7. All the results related to conics are summarized in Table 5.7.

6 Asymptotes

6.1. The asymptotes of the hyperbola (4.1.2) are defined as the pair of intersecting straight lines

$$\mathbf{x}^T \mathbf{V} \mathbf{x} + 2\mathbf{u}^T \mathbf{x} + K = 0 \quad (6.1.1)$$

such that

$$K = \mathbf{u}^T \mathbf{V}^{-1} \mathbf{u} \quad (6.1.2)$$
$$|\mathbf{V}| < 0 \quad (6.1.3)$$

6.2. Let the pair of straight lines be given by

$$\mathbf{n}_1^T \mathbf{x} = c_1 \quad (6.2.1)$$
$$\mathbf{n}_2^T \mathbf{x} = c_2 \quad (6.2.2)$$

Equating their product with (6.1.1),

$$\left(\mathbf{n}_1^T \mathbf{x} - c_1\right)\left(\mathbf{n}_2^T \mathbf{x} - c_2\right)$$
$$= \mathbf{x}^T \mathbf{V}\mathbf{x} + 2\mathbf{u}^T \mathbf{x} + K = 0 \quad (6.2.3)$$

$$\implies \mathbf{n}_1 * \mathbf{n}_2 = \begin{pmatrix} a \\ 2b \\ c \end{pmatrix} \quad (6.2.4)$$

$$c_2 \mathbf{n}_1 + c_1 \mathbf{n}_2 = -2\mathbf{u} \quad (6.2.5)$$
$$c_1 c_2 = K \quad (6.2.6)$$

where $*$ represents convolution.

6.3. The slopes of the lines are given by the roots of the polynomial

$$cm^2 + 2bm + a = 0 \quad (6.3.1)$$

$$\implies m_i = \frac{-b \pm \sqrt{-|V|}}{c} \quad (6.3.2)$$

and

$$\mathbf{n}_i = k_i \begin{pmatrix} -m_i \\ 1 \end{pmatrix}, \quad i = 1, 2. \quad (6.3.3)$$

6.4. From (6.2.5),

$$\begin{pmatrix} \mathbf{n}_1 & \mathbf{n}_2 \end{pmatrix}\begin{pmatrix} c_2 \\ c_1 \end{pmatrix} = -2\mathbf{u} \quad (6.4.1)$$

c_1, c_2 can be obtained such that they satisfy (6.2.6).

7 Circle

7.1. Find the centre and radius of the circle

$$x^2 + y^2 + 8x + 10y - 8 = 0 \quad (7.1.1)$$

Solution: (7.1.1) can be expressed as

$$\mathbf{x}^T \mathbf{x} + 2\begin{pmatrix} 4 & 5 \end{pmatrix}\mathbf{x} - 8 = 0 \quad (7.1.2)$$

which is of the form (4.1.2) with

$$\mathbf{u} = \begin{pmatrix} 4 \\ 5 \end{pmatrix}, f = -8 \quad (7.1.3)$$

From Table 5.7, the center and radius are given by

$$\mathbf{c} = -\mathbf{u} = \begin{pmatrix} -4 \\ -5 \end{pmatrix}, r = \sqrt{\|u\|^2 - f} = 7 \quad (7.1.4)$$

7.2. Find the equation of a circle which passes through the points $\mathbf{P} = \begin{pmatrix} 2 \\ -2 \end{pmatrix}$ and $\mathbf{Q} = \begin{pmatrix} 3 \\ 4 \end{pmatrix}$ and

Conic	Property	Standard Form	Standard Parameters	Point(s) of Contact
Circle	$\mathbf{V} = \mathbf{I}$	$\dfrac{\mathbf{y}^T \mathbf{D} \mathbf{y}}{\mathbf{u}^T \mathbf{V}^{-1}\mathbf{u}-f} = 1$	$\mathbf{c} = -\mathbf{u},$ $r = \sqrt{\mathbf{u}^T\mathbf{u} - f}$	$\mathbf{q} = \mathbf{V}^{-1}(\kappa\mathbf{n} - \mathbf{u})$ $\kappa = \pm\sqrt{\dfrac{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}-f}{\mathbf{n}^T\mathbf{V}^{-1}\mathbf{n}}}$
Ellipse	$|\mathbf{V}| > 0$ $\lambda_1 > 0, \lambda_2 < 0$	$\mathbf{D} = \begin{pmatrix} \lambda_1 & 0 \\ 0 & \lambda_2 \end{pmatrix}$ $\mathbf{V} = \mathbf{P}\mathbf{D}\mathbf{P}^T$ $\mathbf{P} = \begin{pmatrix} \mathbf{p}_1 & \mathbf{p}_2 \end{pmatrix}$	$\mathbf{c} = -\mathbf{V}^{-1}\mathbf{u},$ $axes = \begin{cases} \sqrt{\dfrac{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}-f}{\lambda_1}} \\ \sqrt{\dfrac{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}-f}{\lambda_2}} \end{cases}$	
Hyperbola	$|\mathbf{V}| < 0$ $\lambda_1 > 0, \lambda_2 < 0$		$\mathbf{c} = -\mathbf{V}^{-1}\mathbf{u},$ $axes = \begin{cases} \sqrt{\dfrac{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}-f}{\lambda_1}} \\ \sqrt{\dfrac{f-\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}}{\lambda_2}} \end{cases}$	
Parabola	$|\mathbf{V}| = 0$ $\lambda_1 = 0$	$\mathbf{y}^T\mathbf{D}\mathbf{y} = -\eta\begin{pmatrix} 1 & 0 \end{pmatrix}\mathbf{y}$	$\text{focal length} = \left|\dfrac{\eta}{\lambda_2}\right|$ $\begin{pmatrix} \mathbf{u}^T + \eta\mathbf{p}_1^T \\ \mathbf{V} \end{pmatrix}\mathbf{c}$ $= \begin{pmatrix} -f \\ \eta\mathbf{p}_1 - \mathbf{u} \end{pmatrix}$ $\eta = 2\mathbf{p}_1^T\mathbf{u}$	$\begin{pmatrix} \mathbf{u} + \kappa\mathbf{n}^T \\ \mathbf{V} \end{pmatrix}\mathbf{q}$ $= \begin{pmatrix} -f \\ \kappa\mathbf{n} - \mathbf{u} \end{pmatrix}$ $\kappa = \dfrac{\mathbf{p}_1^T\mathbf{u}}{\mathbf{p}_1^T\mathbf{n}}$

TABLE 5.7: $\mathbf{x}^T\mathbf{V}\mathbf{x} + 2\mathbf{u}^T\mathbf{x} + f = 0$ can be expressed in the above standard form for various conics. $\mathbf{c}$ represents the centre/vertex of the conic. $\mathbf{q}$ is/are the point(s) of contact for the tangent(s).

whose centre lies on the line

$$\begin{pmatrix} 1 & 1 \end{pmatrix}\mathbf{x} = 2 \qquad (7.2.1)$$

Solution: From (4.1.2) and Table 5.7, the equation of a circle can be expressed as

$$\mathbf{x}^T\mathbf{x} - 2\mathbf{c}^T\mathbf{x} + f = 0 \qquad (7.2.2)$$

where $\mathbf{c}$ is the centre. Substituting the given points in (7.2.2) and using (7.2.1), the following equations are obtained

$$2\begin{pmatrix} 2 & -2 \end{pmatrix}\mathbf{c} - f = 8 \qquad (7.2.3)$$

$$2\begin{pmatrix} 3 & 4 \end{pmatrix}\mathbf{c} - f = 25 \qquad (7.2.4)$$

$$\begin{pmatrix} 1 & 1 \end{pmatrix}\mathbf{c} = 2 \qquad (7.2.5)$$

which can be expressed as the matrix equation

$$\begin{pmatrix} 1 & 1 & 0 \\ 4 & -4 & -1 \\ 6 & 8 & -1 \end{pmatrix}\begin{pmatrix} \mathbf{c} \\ f \end{pmatrix} = \begin{pmatrix} 2 \\ 8 \\ 25 \end{pmatrix} \qquad (7.2.6)$$

Row reducing the augmented matrix

$$\begin{pmatrix} 1 & 1 & 0 & 2 \\ 4 & -4 & -1 & 8 \\ 6 & 8 & -1 & 25 \end{pmatrix} \qquad (7.2.7)$$

$$\xrightarrow[R_3 \leftarrow R_3 - 6R_1]{R_2 \leftarrow -R_2 + 4R_1} \begin{pmatrix} 1 & 1 & 0 & 2 \\ 0 & 8 & 1 & 0 \\ 0 & 2 & -1 & 13 \end{pmatrix} \qquad (7.2.8)$$

$$\xrightarrow[R_3 \leftarrow -\frac{4R_3 - R_2}{2}]{R_1 \leftarrow 8R_1 - R_3} \begin{pmatrix} 8 & 0 & -1 & 16 \\ 0 & 8 & 1 & 0 \\ 0 & 0 & 5 & -52 \end{pmatrix} \qquad (7.2.9)$$

$$\xrightarrow[R_2 \leftarrow \frac{5R_2 - R_3}{4}]{R_1 \leftarrow \frac{5R_1 + R_3}{4}} \begin{pmatrix} 10 & 0 & 0 & 7 \\ 0 & 10 & 0 & 13 \\ 0 & 0 & 5 & -52 \end{pmatrix} \qquad (7.2.10)$$

Thus,

$$\mathbf{c} = \frac{1}{10}\begin{pmatrix} 7 \\ 13 \end{pmatrix} \qquad (7.2.11)$$

$$f = -\frac{52}{5} \qquad (7.2.12)$$

which give the desired equation of the circle. From Table 5.7,

$$r = \sqrt{\|\mathbf{c}\|^2 - f} = \frac{1}{10}\sqrt{1258} \qquad (7.2.13)$$
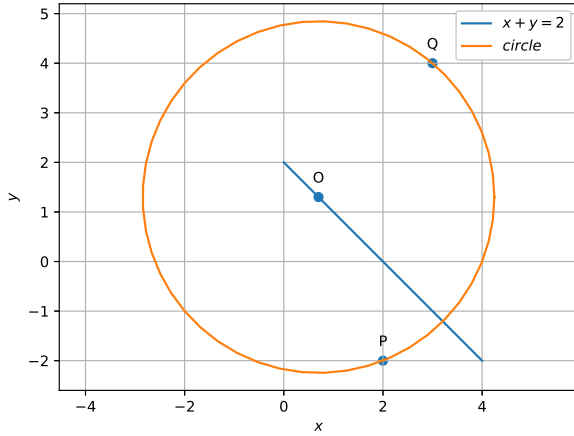
Fig. 7.2 verifies the above results.

Fig. 7.2: Circle passing through $\begin{pmatrix} 2 \\ -2 \end{pmatrix}, \begin{pmatrix} 3 \\ 4 \end{pmatrix}$. Center is on line $\begin{pmatrix} 1 & 1 \end{pmatrix} \mathbf{x} = 2$.
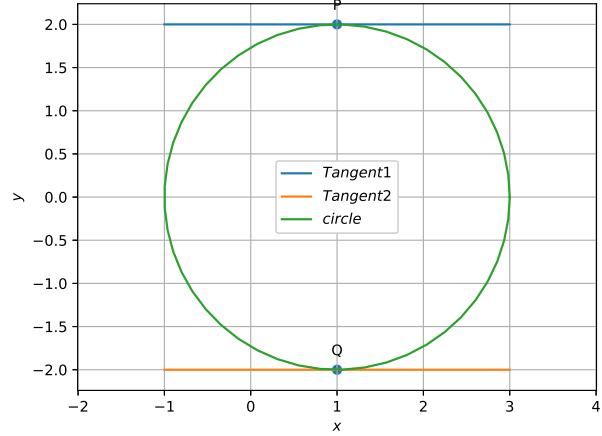

Fig. 7.3: Tangents are parallel to the x-axis.

8 ELLIPSE

7.3. Find the points on the curve

$$x^2 + y^2 - 2x - 3 = 0 \qquad (7.3.1)$$

at which the tangents are parallel to the x-axis.
Solution: (7.3.1) can be expressed as

$$\mathbf{x}^T \mathbf{x} + \begin{pmatrix} -2 & 0 \end{pmatrix} \mathbf{x} - 3 = 0 \qquad (7.3.2)$$

$$\implies \mathbf{V} = \mathbf{I}, \mathbf{u} = \begin{pmatrix} -1 \\ 0 \end{pmatrix}, f = -3 \qquad (7.3.3)$$

From Table 5.7, the centre and radius are

$$\mathbf{c} = -\mathbf{u} = \begin{pmatrix} -1 \\ 0 \end{pmatrix}, r = \sqrt{\|\mathbf{u}\|^2 - f} = 2 \quad (7.3.4)$$

$\because$ the tangents are parallel to the x-axis, their direction and normal vectors are respectively,

$$\mathbf{m} = \begin{pmatrix} 1 \\ 0 \end{pmatrix}, \mathbf{n} = \begin{pmatrix} 0 \\ 1 \end{pmatrix}. \qquad (7.3.5)$$

From Table 5.7,

$$\kappa = \pm \sqrt{\frac{\mathbf{u}^T \mathbf{u} - f}{\mathbf{n}^T \mathbf{n}}} = \pm \sqrt{\frac{4}{1}} = \pm 2 \qquad (7.3.6)$$

and the desired points of contact are

$$\mathbf{q}_1, \mathbf{q}_2 = \begin{pmatrix} 1 \\ 0 \end{pmatrix} \pm 2 \begin{pmatrix} 0 \\ 1 \end{pmatrix} = \begin{pmatrix} 1 \\ 2 \end{pmatrix}, \begin{pmatrix} 1 \\ -2 \end{pmatrix} \qquad (7.3.7)$$

Fig. 7.2 verifies the above results.

8.1. Find $\frac{dy}{dx}$ if

$$E_1 : x^2 + xy + y^2 = 100 \qquad (8.1.1)$$

Solution: Expressing (8.1.1) as (4.1.2),

$$\mathbf{V} = \begin{pmatrix} 1 & \frac{1}{2} \\ \frac{1}{2} & 1 \end{pmatrix}, \mathbf{u} = \mathbf{0}, f = -100. \qquad (8.1.2)$$

$$\because |V| = \begin{vmatrix} 1 & \frac{1}{2} \\ \frac{1}{2} & 1 \end{vmatrix} > 0, \qquad (8.1.3)$$

(8.1.1) is the equation of an ellipse. To verify that this is indeed the case, we do the following exercise. The characteristic equation of $\mathbf{V}$ is obtained by evaluating the determinant

$$|\lambda \mathbf{I} - \mathbf{V}| = \begin{vmatrix} \lambda - 1 & \frac{1}{2} \\ \frac{1}{2} & \lambda - 1 \end{vmatrix} = 0 \qquad (8.1.4)$$

$$\implies \lambda^2 - 2\lambda + \frac{3}{4} = 0 \qquad (8.1.5)$$

The eigenvalues are the roots of (8.1.5) given by

$$\lambda_1 = \frac{1}{2}, \lambda_2 = \frac{3}{2} \qquad (8.1.6)$$

The eigenvector $\mathbf{p}$ is defined as

$$\mathbf{V}\mathbf{p} = \lambda \mathbf{p} \qquad (8.1.7)$$

$$\implies (\lambda \mathbf{I} - \mathbf{V}) \mathbf{p} = 0 \qquad (8.1.8)$$

where λ is the eigenvalue. For $\lambda_1 = \frac{3}{2}$,

$$(\lambda_1 \mathbf{I} - \mathbf{V}) = \begin{pmatrix} \frac{1}{2} & -\frac{1}{2} \\ -\frac{1}{2} & \frac{1}{2} \end{pmatrix} \xleftarrow[R_1 \leftarrow 2R_1]{R_2 \leftarrow R_2 - R_1} \begin{pmatrix} 1 & -1 \\ 0 & 0 \end{pmatrix}$$
(8.1.9)

$$\implies \mathbf{p}_1 = \frac{1}{\sqrt{2}} \begin{pmatrix} 1 \\ 1 \end{pmatrix}$$
(8.1.10)

such that $\|\mathbf{p}_1\| = 1$. Similarly, the eigenvector corresponding to λ_2 can be obtained as

$$\mathbf{p}_2 = \frac{1}{\sqrt{2}} \begin{pmatrix} -1 \\ 1 \end{pmatrix}$$
(8.1.11)

It is easy to verify that

$$\mathbf{V} = \mathbf{PDP}^{-1} = \mathbf{PDP}^T \quad \because \mathbf{P}^{-1} = \mathbf{P}^T$$
(8.1.12)

$$\text{or, } \mathbf{D} = \mathbf{P}^T \mathbf{VP}$$
(8.1.13)

where

$$\mathbf{P} = \begin{pmatrix} \mathbf{p}_1 & \mathbf{p}_2 \end{pmatrix} = \frac{1}{\sqrt{2}} \begin{pmatrix} 1 & 1 \\ -1 & 1 \end{pmatrix}$$
(8.1.14)

$$\mathbf{D} = \begin{pmatrix} \lambda_1 & 0 \\ 0 & \lambda_2 \end{pmatrix} = \begin{pmatrix} \frac{3}{2} & 0 \\ 0 & \frac{1}{2} \end{pmatrix}$$
(8.1.15)

From Table 5.7, ellipse parameters are given by

$$\mathbf{c} = -\mathbf{V}^{-1}\mathbf{u} = \mathbf{0}$$
(8.1.16)

$$\sqrt{\frac{\mathbf{u}^T \mathbf{V}^{-1} \mathbf{u} - f}{\lambda_1}} = 10\sqrt{\frac{2}{3}}$$
(8.1.17)

$$\sqrt{\frac{\mathbf{u}^T \mathbf{V}^{-1} \mathbf{u} - f}{\lambda_2}} = 10\sqrt{2}$$
(8.1.18)

In Fig. 8.1 the actual ellipse ellipse in (8.1.1) is obtained from (4.2.5) using (4.2.1). The anticlockwise 45°rotation is due to the fact that (8.1.14) can be expressed as

$$\mathbf{P} = \begin{pmatrix} \cos 45° & -\sin 45° \\ \sin 45° & \cos 45° \end{pmatrix}$$
(8.1.19)

Coming back to the original question of finding $\frac{dy}{dx}$, if the point of contact

$$\mathbf{q} = \begin{pmatrix} q_1 \\ q_2 \end{pmatrix},$$
(8.1.20)

from (8.1.2), (1.2.4) and (5.2.1),

$$\begin{pmatrix} 1 & m \end{pmatrix} \begin{pmatrix} 1 & \frac{1}{2} \\ \frac{1}{2} & 1 \end{pmatrix} \begin{pmatrix} q_1 \\ q_2 \end{pmatrix} = 0 \quad (8.1.21)$$

$$\implies \begin{pmatrix} 1 + \frac{m}{2} & \frac{1}{2} + m \end{pmatrix} \begin{pmatrix} q_1 \\ q_2 \end{pmatrix} = 0 \quad (8.1.22)$$

$$\implies \frac{m}{2}(q_1 + 2q_2) + q_1 + \frac{q_2}{2} = 0 \quad (8.1.23)$$

$$\text{or, } m = \frac{dy}{dx} = -\frac{2q_1 + q_2}{q_1 + 2q_2} \quad (8.1.24)$$

$\because \frac{dy}{dx}$ is the slope of the tangent. Note that no results from differential calculus were used to obtain (8.1.24).
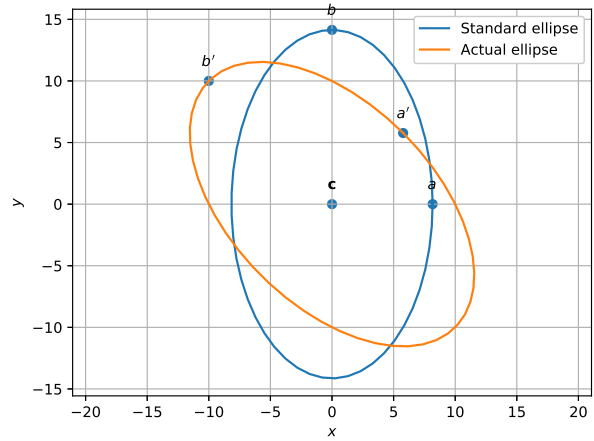

Fig. 8.1: Actual ellipse and transformed ellipse.

8.2. Find the equation of the ellipse, with major axis along the x-axis and passing through the points $\mathbf{a} = \begin{pmatrix} 4 \\ 3 \end{pmatrix}$ and $\mathbf{b} = \begin{pmatrix} -1 \\ 4 \end{pmatrix}$

Solution: This is a standard ellipse given by

$$\mathbf{x}^T \mathbf{Dx} = 1, \quad \mathbf{D} = \begin{pmatrix} \lambda_1 & 0 \\ 0 & \lambda_2 \end{pmatrix}, \lambda_1, \lambda_2 > 0 \quad (8.2.1)$$

$\because \mathbf{a}, \mathbf{b}$ satisfy (8.2.1),

$$\mathbf{a}^T \mathbf{Da} = 1, \quad (8.2.2)$$

$$\mathbf{b}^T \mathbf{Db} = 1 \quad (8.2.3)$$

which can be expressed as

$$\mathbf{a}^T \mathbf{Ad} = 1,$$
$$\mathbf{b}^T \mathbf{Bd} = 1 \quad (8.2.4)$$

where

$$\mathbf{d} = \begin{pmatrix} \lambda_1 \\ \lambda_2 \end{pmatrix}, \mathbf{A} = \begin{pmatrix} 4 & 0 \\ 0 & 3 \end{pmatrix}, \mathbf{B} = \begin{pmatrix} -1 & 0 \\ 0 & 4 \end{pmatrix}. \quad (8.2.5)$$

(8.2.4) can then be expressed as the matrix equation

$$\begin{pmatrix} \mathbf{a}^T\mathbf{A} \\ \mathbf{b}^T\mathbf{B} \end{pmatrix}\mathbf{d} = \begin{pmatrix} 1 \\ 1 \end{pmatrix}, \quad (8.2.6)$$

which, after substituing the appropriate values can be expressed as

$$\begin{pmatrix} 16 & 9 \\ 1 & 16 \end{pmatrix}\mathbf{d} = \begin{pmatrix} 1 \\ 1 \end{pmatrix}, \quad (8.2.7)$$

Forming the augmented matrix and performing row reduction,

$$\begin{pmatrix} 16 & 9 & 1 \\ 1 & 16 & 1 \end{pmatrix} \xrightarrow[R_2 \leftarrow -R_2]{R_2 \leftarrow R_1} \begin{pmatrix} 1 & 16 & 1 \\ 0 & 247 & 15 \end{pmatrix}$$
$$(8.2.8)$$

$$\xrightarrow{R_1 \leftarrow 247R_1 - 16R_2} \begin{pmatrix} 247 & 0 & 7 \\ 0 & 247 & 15 \end{pmatrix}$$
$$(8.2.9)$$

$$\implies \mathbf{d} = \frac{1}{247}\begin{pmatrix} 7 \\ 15 \end{pmatrix}, \text{ or, } \mathbf{D} = \frac{1}{247}\begin{pmatrix} 7 & 0 \\ 0 & 15 \end{pmatrix}$$
$$(8.2.10)$$

The ellipse parameters are obtained from Table 5.7 as

$$\mathbf{c} = \mathbf{0}, \frac{1}{\sqrt{\lambda_1}} = \sqrt{\frac{247}{7}}, \frac{1}{\sqrt{\lambda_2}} = \sqrt{\frac{247}{15}}.$$
$$(8.2.11)$$

Fig. 8.2 verifies the above results.

9 Hyperbola

9.1. Find the equation of all lines having slope 2 and being tangent to the curve

$$y + \frac{2}{x - 3} = 0 \quad (9.1.1)$$

Solution: (9.1.1) can be expressed as

$$xy - 3y + 2 = 0 \quad (9.1.2)$$

which is of the same form as (4.1.2) with

$$\mathbf{V} = \frac{1}{2}\begin{pmatrix} 0 & 1 \\ 1 & 0 \end{pmatrix}, \mathbf{u} = -\frac{3}{2}\begin{pmatrix} 0 \\ 1 \end{pmatrix}, f = 2 \quad (9.1.3)$$
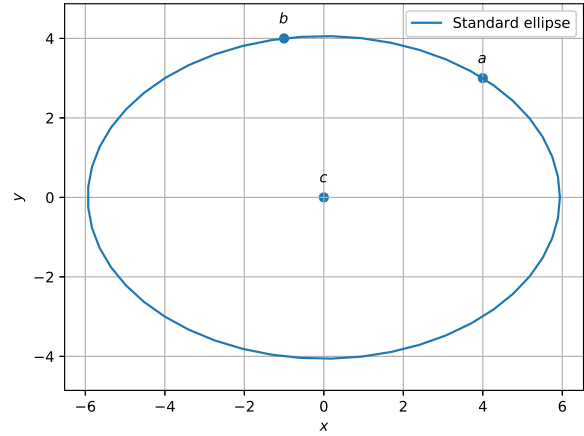

Fig. 8.2: Ellipse through the given points $\mathbf{a} = \begin{pmatrix} 4 \\ 3 \end{pmatrix}$ and $\mathbf{b} = \begin{pmatrix} -1 \\ 4 \end{pmatrix}$.

Using the approach in Example 8.1,

$$\mathbf{D} = \begin{pmatrix} \frac{1}{2} & 0 \\ 0 & -\frac{1}{2} \end{pmatrix}, \mathbf{P} = \frac{1}{\sqrt{2}}\begin{pmatrix} 1 & -1 \\ 1 & 1 \end{pmatrix} \quad (9.1.4)$$

$$\because \mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f = -2 < 0, \quad (9.1.5)$$

the major and minor axis are swapped and from Table 5.7 the hyperbola parameters are given by

$$\mathbf{c} = 3\begin{pmatrix} 1 \\ 0 \end{pmatrix}, \sqrt{\frac{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f}{\lambda_2}} = 2, \quad (9.1.6)$$

$$\sqrt{\frac{f - \mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}}{\lambda_1}} = 2 \quad (9.1.7)$$

with the standard hyperbola equation becoming

$$\frac{y_2^2}{4} - \frac{y_1^2}{4} = 1, \quad (9.1.8)$$

Fig. 9.1 shows the actual hyperbola in (9.1.1) obtained from (9.1.8) using (4.2.1). The direction and normal vectors of the tangent with slope 2 are given by (1.2.4) and (1.4.1) as

$$\mathbf{m} = \begin{pmatrix} 1 \\ 2 \end{pmatrix}, \mathbf{n} = \begin{pmatrix} 2 \\ -1 \end{pmatrix} \quad (9.1.9)$$

From (5.5.2) and (7.3.3), using (9.1.3),

$$\kappa = \frac{1}{2}, \mathbf{q}_1 = \begin{pmatrix} 2 \\ 2 \end{pmatrix}, \mathbf{q}_2 = \begin{pmatrix} 4 \\ -2 \end{pmatrix}. \qquad (9.1.10)$$

The desired tangents are

$$\begin{pmatrix} 2 & -1 \end{pmatrix}\left\{\mathbf{x} - \begin{pmatrix} 2 \\ 2 \end{pmatrix}\right\} = 0 \implies \begin{pmatrix} 2 & -1 \end{pmatrix}\mathbf{x} = 2 \qquad (9.1.11)$$

$$\begin{pmatrix} 2 & -1 \end{pmatrix}\left\{\mathbf{x} - \begin{pmatrix} 4 \\ -2 \end{pmatrix}\right\} = 0 \implies \begin{pmatrix} 2 & -1 \end{pmatrix}\mathbf{x} = 10 \qquad (9.1.12)$$

All the above results are verified in Fig. 9.1. As we can see, the hyperbola in (9.1.1) is obtained by rotating the standard hyperbola by $\mathbf{P}$ and then translating it by $\mathbf{c}$.
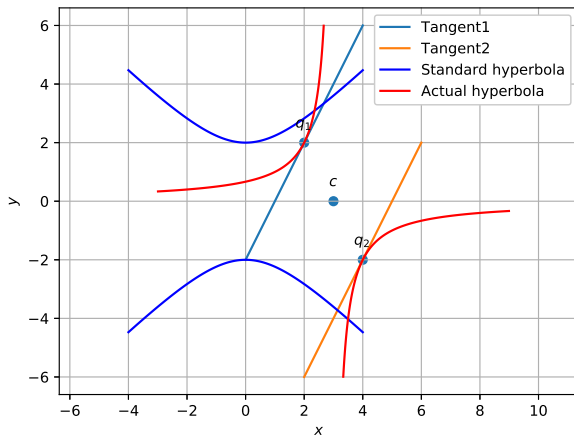

Fig. 9.1: Standard and actual hyperbola.

9.2. Find the asymptotes of the hyperbola given below and also the equations to their conjugate hyperbolas.

$$8x^2 + 10xy - 3y^2 - 2x + 4y - 2 = 0 \quad (9.2.1)$$

a) (9.2.1) can be expressed as (4.1.2) with

$$\mathbf{V} = \mathbf{V}^T = \begin{pmatrix} 8 & 5 \\ 5 & -3 \end{pmatrix} \qquad (9.2.2)$$

$$\mathbf{u} = \begin{pmatrix} -1 \\ 2 \end{pmatrix} \qquad (9.2.3)$$

$$f = -2 \qquad (9.2.4)$$

Expanding the Determinant of $\mathbf{V}$,

$$\Delta_V = \begin{vmatrix} 8 & 5 \\ 5 & -3 \end{vmatrix} = -49 < 0 \qquad (9.2.5)$$

Hence from (4.6.1) and (9.2.5), (9.2.1) represents a hyperbola. The characteristic equation of $\mathbf{V}$ is obtained by evaluating the determinant

$$|V - \lambda\mathbf{I}| = 0 \qquad (9.2.6)$$

$$\begin{vmatrix} 8 - \lambda & 5 \\ 5 & -3 - \lambda \end{vmatrix} = 0 \qquad (9.2.7)$$

$$(8 - \lambda)(-3 - \lambda) - 25 = 0 \qquad (9.2.8)$$

$$\lambda_1 = \frac{5 + \sqrt{221}}{2} \qquad (9.2.9)$$

$$\lambda_2 = \frac{5 - \sqrt{221}}{2} \qquad (9.2.10)$$

The eigenvector $\mathbf{p}$ is defined as

$$\mathbf{Vp} = \lambda\mathbf{p} \qquad (9.2.11)$$

$$\implies (\mathbf{V} - \lambda\mathbf{I})\mathbf{p} = 0 \qquad (9.2.12)$$

For $\lambda_1 = \frac{5 + \sqrt{221}}{2}$,

$$(\mathbf{V} - \lambda_1\mathbf{I}) = \begin{pmatrix} \frac{11 - \sqrt{221}}{2} & 5 \\ 5 & \frac{-11 - \sqrt{221}}{2} \end{pmatrix} \qquad (9.2.13)$$

By row reduction,

$$\begin{pmatrix} \frac{11 - \sqrt{221}}{2} & 5 \\ 5 & \frac{-11 - \sqrt{221}}{2} \end{pmatrix} \qquad (9.2.14)$$

$$\xleftrightarrow{R_1 \leftarrow R_2} \begin{pmatrix} \frac{-11 - \sqrt{221}}{2} & 5 \\ \frac{11 - \sqrt{221}}{2} & 5 \end{pmatrix} \qquad (9.2.15)$$

$$\xleftrightarrow{R_2 \leftarrow R_2 - \frac{11 - \sqrt{221}}{10}R_1} \begin{pmatrix} 5 & \frac{-11 - \sqrt{221}}{2} \\ 0 & 0 \end{pmatrix} \qquad (9.2.16)$$

$$\xleftrightarrow{R_1 \leftarrow R_1/5} \begin{pmatrix} 1 & \frac{-11 - \sqrt{221}}{10} \\ 0 & 0 \end{pmatrix} \qquad (9.2.17)$$

Substituting (9.2.17) in (9.2.12) we get

$$\begin{pmatrix} 1 & \frac{-11 - \sqrt{221}}{10} \\ 0 & 0 \end{pmatrix}\begin{pmatrix} v_1 \\ v_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix} \qquad (9.2.18)$$

Where, $\mathbf{p} = \begin{pmatrix} v_1 \\ v_2 \end{pmatrix}$ Let $v_2 = t$

$$v_1 = \frac{t(11 + \sqrt{221})}{10} \qquad (9.2.19)$$

Eigen vector $\mathbf{p}_1$ is given by

$$\mathbf{p}_1 = \begin{pmatrix} \frac{t(11 + \sqrt{221})}{10} \\ t \end{pmatrix} \qquad (9.2.20)$$

Let $t = 1$, we get

$$\mathbf{p_1} = \begin{pmatrix} \frac{11+\sqrt{221}}{10} \\ 1 \end{pmatrix} \qquad (9.2.21)$$

For $\lambda_2 = \frac{5-\sqrt{221}}{2}$,

$$(\mathbf{V} - \lambda_2\mathbf{I}) = \begin{pmatrix} \frac{11+\sqrt{221}}{2} & 5 \\ 5 & \frac{-11+\sqrt{221}}{2} \end{pmatrix} \qquad (9.2.22)$$

By row reduction ,

$$\begin{pmatrix} \frac{11+\sqrt{221}}{2} & 5 \\ 5 & \frac{-11+\sqrt{221}}{2} \end{pmatrix} \qquad (9.2.23)$$

$$\xleftarrow{R_1 \leftarrow R_2 + \frac{11-\sqrt{221}}{10}R_1} \begin{pmatrix} \frac{11+\sqrt{221}}{2} & 5 \\ 0 & 0 \end{pmatrix} \qquad (9.2.24)$$

$$\xleftarrow{R_1 \leftarrow \frac{R_1}{\frac{11+\sqrt{221}}{10}}} \begin{pmatrix} 1 & \frac{10}{11+\sqrt{221}} \\ 0 & 0 \end{pmatrix} \qquad (9.2.25)$$

Substiuting (9.2.25) in (9.2.12) we get

$$\begin{pmatrix} 1 & \frac{10}{11+\sqrt{221}} \\ 0 & 0 \end{pmatrix}\begin{pmatrix} v_1 \\ v_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix} \qquad (9.2.26)$$

Where, $\mathbf{p} = \begin{pmatrix} v_1 \\ v_2 \end{pmatrix}$ Let $v_2 = t$

$$v_1 = \frac{-t(10)}{11 + \sqrt{221}} \qquad (9.2.27)$$

Eigen vector $\mathbf{p_2}$ is given by

$$\mathbf{p_2} = \begin{pmatrix} \frac{-t(10)}{11+\sqrt{221}} \\ t \end{pmatrix} \qquad (9.2.28)$$

Let $t = 1$, we get

$$\mathbf{p_2} = \begin{pmatrix} \frac{(-10)}{11+\sqrt{221}} \\ 1 \end{pmatrix} \qquad (9.2.29)$$

By eigen decompostion $\mathbf{V}$ can be represented by

$$\mathbf{V} = \mathbf{PDP}^T \qquad (9.2.30)$$

where

$$\mathbf{P} = \begin{pmatrix} \mathbf{p_1} & \mathbf{p_2} \end{pmatrix} \qquad (9.2.31)$$

$$\mathbf{D} = \begin{pmatrix} \lambda_1 & 0 \\ 0 & \lambda_2 \end{pmatrix} \qquad (9.2.32)$$

Substituting equations 9.2.21, 9.2.29 in

(9.2.31) we get

$$\mathbf{P} = \begin{pmatrix} \frac{11+\sqrt{221}}{10} & \frac{-10}{11+\sqrt{221}} \\ 1 & 1 \end{pmatrix} \qquad (9.2.33)$$

Substituting equations 9.2.9, 9.2.10 in 9.2.32 we get

$$\mathbf{D} = \begin{pmatrix} \frac{5+\sqrt{221}}{2} & 0 \\ 0 & \frac{5-\sqrt{221}}{2} \end{pmatrix} \qquad (9.2.34)$$

Centre of the hyperbola is given by

$$\mathbf{c} = -\mathbf{V}^{-1}\mathbf{u} \qquad (9.2.35)$$

$$\implies \mathbf{c} = -\begin{pmatrix} \frac{3}{49} & \frac{5}{49} \\ \frac{5}{49} & \frac{-8}{49} \end{pmatrix}\begin{pmatrix} -1 \\ 2 \end{pmatrix} \qquad (9.2.36)$$

$$\implies \mathbf{c} = \begin{pmatrix} \frac{-3}{49} & \frac{-5}{49} \\ \frac{-5}{49} & \frac{8}{49} \end{pmatrix}\begin{pmatrix} -1 \\ 2 \end{pmatrix} \qquad (9.2.37)$$

$$\implies \mathbf{c} = \begin{pmatrix} \frac{-1}{7} \\ \frac{3}{7} \end{pmatrix} \qquad (9.2.38)$$

Since,

$$\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f = 1 > 0 \qquad (9.2.39)$$

there isn't a need to swap axes In hyperbola,

$$axes = \begin{cases} \sqrt{\frac{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}-f}{\lambda_1}} \\ \sqrt{\frac{f-\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}}{\lambda_2}} \end{cases} \qquad (9.2.40)$$

From above equations we can say that,

$$\sqrt{\frac{\mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f}{\lambda_1}} = \sqrt{\frac{2}{5 + \sqrt{221}}} \qquad (9.2.41)$$

$$\sqrt{\frac{f - \mathbf{u}^T\mathbf{V}^{-1}\mathbf{u}}{\lambda_2}} = \sqrt{\frac{2}{5 - \sqrt{221}}} \qquad (9.2.42)$$

The equation of the hyperbola at the origin is then given by (4.2.5) as

$$\mathbf{y}^T\mathbf{D}\mathbf{y} = \mathbf{u}^T\mathbf{V}^{-1}\mathbf{u} - f$$

$$\qquad (9.2.43)$$

$$\implies \mathbf{y}^T\begin{pmatrix} \frac{5+\sqrt{221}}{2} & 0 \\ 0 & \frac{5-\sqrt{221}}{2} \end{pmatrix}\mathbf{y} = 1 \qquad (9.2.44)$$

b) (*Asymptotes of hyperbola:*) The equation for the asymptotes of (9.2.1) is given by (6.1.1) with

$$\Delta = \begin{vmatrix} 8 & 5 & -1 \\ 5 & -3 & 2 \\ -1 & 2 & K \end{vmatrix} = 0 \quad (9.2.45)$$

$$\implies K = -1 \quad (9.2.46)$$

using (6.1.2). From (6.3.1), (9.2.1) and (6.3.3),

$$-3m^2 + 10m + 8 = 0 \quad (9.2.47)$$

$$m_1 = 4, m_2 = \frac{-2}{3} \quad (9.2.48)$$

$$\implies \mathbf{n_1} = \begin{pmatrix} -4 \\ 1 \end{pmatrix}, \mathbf{n_2} = \begin{pmatrix} -2 \\ -3 \end{pmatrix} \quad (9.2.49)$$

From equation (9.2.49), the Toeplitz matrix for $\mathbf{n_1}$ is

$$T_{\mathbf{n_1}} = \begin{pmatrix} -4 & 0 \\ 1 & -4 \\ 0 & -1 \end{pmatrix} \quad (9.2.50)$$

The product of the above matrix with $\mathbf{n_2}$ is

$$T_{\mathbf{n_1}}\mathbf{n_2} = \begin{pmatrix} -4 & 0 \\ 1 & -4 \\ 0 & 1 \end{pmatrix}\begin{pmatrix} 0 \\ -1 \end{pmatrix} = \begin{pmatrix} 8 \\ 10 \\ -3 \end{pmatrix} = \begin{pmatrix} a \\ 2b \\ c \end{pmatrix} \quad (9.2.51)$$

in (9.2.1) and is equivalent to the convolution operation in (6.2.4), providing a verification of (9.2.49). From (6.4.1)

$$\begin{pmatrix} \mathbf{n_1} & \mathbf{n_2} \end{pmatrix}\begin{pmatrix} c_2 \\ c_1 \end{pmatrix} = -2\mathbf{u} \quad (9.2.52)$$

Substituting (9.2.49) in (9.2.52), the augmented matrix is,

$$\begin{pmatrix} -4 & -2 & -2 \\ 1 & -3 & 4 \end{pmatrix} \xrightarrow[R_2 \leftarrow R_2 - R_1]{R_1 \leftarrow -R_1/4} \begin{pmatrix} 1 & \frac{1}{2} & \frac{1}{2} \\ 0 & -\frac{7}{2} & \frac{7}{2} \end{pmatrix} \quad (9.2.53)$$

$$\xrightarrow[R_1 \leftarrow R_1 - \frac{1}{2}R_2]{R_2 \leftarrow -\frac{2}{7}R_2} \begin{pmatrix} 1 & 0 & 1 \\ 0 & 1 & -1 \end{pmatrix} \quad (9.2.54)$$

$$\implies c_1 = 1, c_2 = -1 \quad (9.2.55)$$

Thus, from (9.2.49) and (9.2.55), the desired equations of the asymptotes are

$$\begin{pmatrix} -4 & 1 \end{pmatrix}\mathbf{x} = 1 \quad (9.2.56)$$

$$\begin{pmatrix} -2 & -3 \end{pmatrix}\mathbf{x} = -1 \quad (9.2.57)$$

The angle between the lines can be expressed as,

$$\mathbf{n_1} = \begin{pmatrix} -4 \\ 1 \end{pmatrix}, \quad \mathbf{n_2} = \begin{pmatrix} -2 \\ -3 \end{pmatrix} \quad (9.2.58)$$

$$\cos\theta = \frac{\mathbf{n_1}^T\mathbf{n_2}}{\|\mathbf{n_1}\|\,\|\mathbf{n_2}\|} \quad (9.2.59)$$

$$\implies \theta = \cos^{-1}\left(\frac{5}{\sqrt{221}}\right). \quad (9.2.60)$$

c) Conjugate Hyperbola: The conjugate hyperbola is obtained from (9.2.1) and (4.1.2) as

$$\mathbf{x}^T\mathbf{V}\mathbf{x} + 2\mathbf{u}^T\mathbf{Q}\mathbf{x} + f = 0 \quad (9.2.61)$$

where

$$\mathbf{Q} = \begin{pmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{pmatrix} \quad (9.2.62)$$

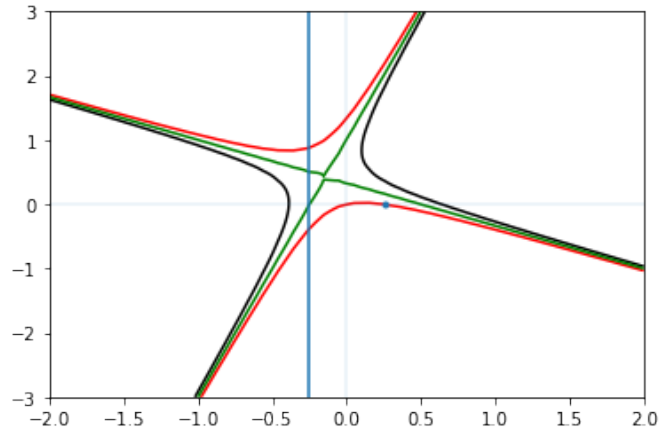is a rotation matrix and θ is the angle between the asymptotes.

Fig. 9.2: Hyperbola with assymptotes and its conjugate

10 PARABOLA

10.1. Find the point at which the tangent to the curve

$$y = \sqrt{4x - 3} - 1 \quad (10.1.1)$$

has slope $\frac{2}{3}$.

Solution: (10.1.1) can be expressed as

$$(y + 1)^2 = 4x - 3 \quad (10.1.2)$$

$$\text{or, } y^2 - 4x + 2y + 4 = 0 \quad (10.1.3)$$

which has the form (4.1.2) with parameters

$$\mathbf{V} = \begin{pmatrix} 0 & 0 \\ 0 & 1 \end{pmatrix}, \mathbf{u} = \begin{pmatrix} -2 \\ 1 \end{pmatrix}, f = 4. \qquad (10.1.4)$$

Thus, the given curve is a parabola. $\because$ $\mathbf{V}$ is diagonal and in standard form,

$$\mathbf{P} = \mathbf{I} \implies \mathbf{p}_1 = \begin{pmatrix} 1 \\ 0 \end{pmatrix} \qquad (10.1.5)$$

From Table 5.7, the focus is 4 and the vertex $\mathbf{c}$ is

$$\begin{pmatrix} -4 & 1 \\ 0 & 0 \\ 0 & 1 \end{pmatrix} \mathbf{c} = \begin{pmatrix} -4 \\ 0 \\ -1 \end{pmatrix} \qquad (10.1.6)$$

$$\implies \begin{pmatrix} -4 & 1 \\ 0 & 1 \end{pmatrix} \mathbf{c} = \begin{pmatrix} -4 \\ -1 \end{pmatrix} \qquad (10.1.7)$$

$$\text{or, } \mathbf{c} = \begin{pmatrix} \frac{3}{4} \\ -1 \end{pmatrix} \qquad (10.1.8)$$

The direction vector and normal vectors are

$$\mathbf{m} = \begin{pmatrix} 1 \\ \frac{2}{3} \end{pmatrix} = \begin{pmatrix} 3 \\ 2 \end{pmatrix}, \mathbf{n} = \begin{pmatrix} 2 \\ -3 \end{pmatrix}. \qquad (10.1.9)$$

Also,

$$\mathbf{V}\mathbf{p} = \mathbf{0} \qquad (10.1.10)$$

$$\implies \mathbf{p} = \begin{pmatrix} 1 \\ 0 \end{pmatrix} \qquad (10.1.11)$$

From (5.6.2), (10.1.9) and (10.1.11),

$$\kappa = -1 \qquad (10.1.12)$$

which, upon substitution in (5.6.1) and simplification yields the matrix equation

$$\begin{pmatrix} -4 & 4 \\ 0 & 0 \\ 0 & 1 \end{pmatrix} \mathbf{q} = \begin{pmatrix} -4 \\ 0 \\ 2 \end{pmatrix} \qquad (10.1.13)$$

$$\implies \begin{pmatrix} -4 & 4 \\ 0 & 1 \end{pmatrix} \mathbf{q} = \begin{pmatrix} -4 \\ 2 \end{pmatrix} \qquad (10.1.14)$$

$$\text{or, } \mathbf{q} = \begin{pmatrix} 3 \\ 2 \end{pmatrix} \qquad (10.1.15)$$

Fig. 10.1 verifies the above results.

10.2. Find a point on the curve

$$y = (x - 2)^2 \qquad (10.2.1)$$

at which the tangent is parallel to the chord joining the points (2, 0) and (4, 4).
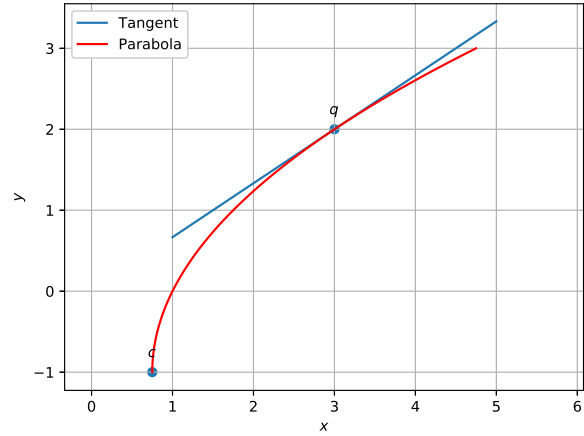

Fig. 10.1: Tangent to parabola in (10.1.1) with slope $\frac{2}{3}$.

Solution: (10.2.1) can be expressed as

$$x^2 - 4x - y + 4 = 0 \qquad (10.2.2)$$

which has the form (4.1.2) with parameters

$$\mathbf{V} = \begin{pmatrix} 1 & 0 \\ 0 & 0 \end{pmatrix}, \mathbf{u} = -\begin{pmatrix} 2 \\ \frac{1}{2} \end{pmatrix}, f = 4. \qquad (10.2.3)$$

Using eigenvalue decomposition,

$$\mathbf{P} = \begin{pmatrix} 0 & 1 \\ 1 & 0 \end{pmatrix}, \mathbf{D} = \begin{pmatrix} 0 & 0 \\ 0 & 1 \end{pmatrix} \qquad (10.2.4)$$

Hence, the eigenvector of $\mathbf{V}$ corresponding to the zero eigenvalue is

$$\mathbf{p}_1 = \begin{pmatrix} 0 \\ 1 \end{pmatrix}. \qquad (10.2.5)$$

Substituting the above parameters in the equation for the vertex of the parabola in Table 5.7,

$$\begin{pmatrix} -2 & -\frac{5}{2} \\ 1 & 0 \\ 0 & 0 \end{pmatrix} \mathbf{c} = \begin{pmatrix} -4 \\ 2 \\ 0 \end{pmatrix} \qquad (10.2.6)$$

$$\implies \begin{pmatrix} -1 & -\frac{5}{2} \\ 1 & 0 \end{pmatrix} \mathbf{c} = \begin{pmatrix} -4 \\ 2 \end{pmatrix} \qquad (10.2.7)$$

$$\text{or, } \mathbf{c} = \begin{pmatrix} 2 \\ 0 \end{pmatrix} \qquad (10.2.8)$$

The direction vector is

$$\mathbf{m} = \begin{pmatrix} 4 \\ 4 \end{pmatrix} - \begin{pmatrix} 2 \\ 0 \end{pmatrix} = \begin{pmatrix} 1 \\ 2 \end{pmatrix} \qquad (10.2.9)$$

and normal vector is

$$\mathbf{n} = \begin{pmatrix} 2 \\ -1 \end{pmatrix} \qquad (10.2.10)$$

From the equation for the point of contact for the parabola in Table 5.7,

$$\kappa = \frac{1}{2} \qquad (10.2.11)$$

resulting in the matrix equation

$$\begin{pmatrix} -1 & -1 \\ 1 & 0 \\ 0 & 0 \end{pmatrix} \mathbf{q} = \begin{pmatrix} -4 \\ 3 \\ 0 \end{pmatrix} \qquad (10.2.12)$$

$$\implies \begin{pmatrix} -1 & -1 \\ 1 & 0 \end{pmatrix} \mathbf{q} = \begin{pmatrix} -4 \\ 3 \end{pmatrix} \qquad (10.2.13)$$

$$\text{or, } \mathbf{q} = \begin{pmatrix} 3 \\ 1 \end{pmatrix} \qquad (10.2.14)$$

Fig. 10.2 verifies the above results. Note that **P** rotates the standard parabola by 90°.
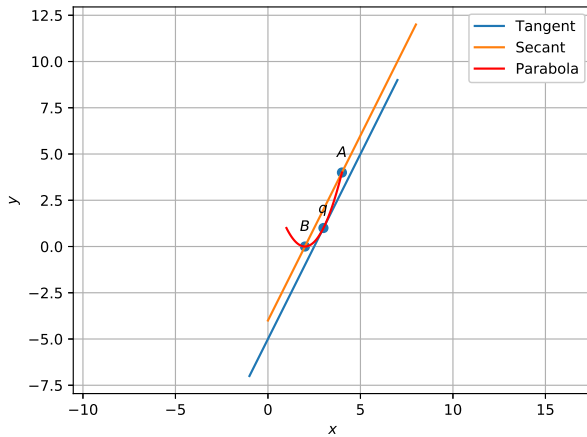

Fig. 10.2: Tangent to parabola in (10.2.1) is parallel to the line joining the points $\begin{pmatrix} 2 \\ 0 \end{pmatrix}$ and $\begin{pmatrix} 4 \\ 4 \end{pmatrix}$.

11 VECTOR CALCULUS

11.1. *Definition:* Let $\mathbf{x} \in \mathbb{R}^2, f(\mathbf{x}) \in \mathbb{R}$. Then,

$$\frac{df(\mathbf{x})}{d\mathbf{x}} = \begin{pmatrix} \frac{\partial f(\mathbf{x})}{\partial x_1} \\ \frac{\partial f(\mathbf{x})}{\partial x_2} \end{pmatrix} \qquad (11.1.1)$$

11.2.

$$\frac{d\mathbf{x}}{dx_1} = \begin{pmatrix} \frac{dx_1}{dx_1} \\ \frac{dx_1}{dx_1} \end{pmatrix}$$

$$= \begin{pmatrix} 1 \\ m \end{pmatrix} = \mathbf{m} \qquad (11.2.1)$$

11.3. Show that

$$\frac{d\left(\mathbf{u}^T \mathbf{x}\right)}{d\mathbf{x}} = \mathbf{u}$$

$$\frac{d\left(\mathbf{x}^T \mathbf{V} \mathbf{x}\right)}{d\mathbf{x}} = 2\mathbf{V}^T \mathbf{x} \qquad (11.3.1)$$

11.4. Differentiating (4.1.2) with respect to x_1,

$$\left[\frac{d\left(\mathbf{x}^T \mathbf{V} \mathbf{x}\right)}{d\mathbf{x}}\right]^T \frac{d\mathbf{x}}{dx_1} + 2\frac{d\left(\mathbf{u}^T \mathbf{x}\right)}{\mathbf{x}} \frac{d\mathbf{x}}{dx_1} = 0 \qquad (11.4.1)$$

$$\implies 2\left(\mathbf{V}^T \mathbf{x} + \mathbf{u}\right) \mathbf{m} = 0 \qquad (11.4.2)$$

from (11.2.1) and (11.3.1). Substituting the point of contact $\mathbf{x} = \mathbf{q}$ and simplifying results in

$$(\mathbf{V}\mathbf{q} + \mathbf{u}) \mathbf{m} = 0 \qquad (11.4.3)$$

which, upon taking the transpose, yields (5.2.1).

12 VECTOR INEQUALITIES

12.1. *(Cauchy-Schwarz Inequality:)* Show that

$$\left|\mathbf{a}^T \mathbf{b}\right| \leq \|\mathbf{a}\| \|\mathbf{b}\| \qquad (12.1.1)$$

Proof. Using the definition of the inner product,

$$\cos\theta = \frac{\mathbf{a}^T \mathbf{b}}{\|\mathbf{a}\| \|\mathbf{b}\|} \qquad (12.1.2)$$

$$\because |\cos\theta| \leq 1, \left|\mathbf{a}^T \mathbf{b}\right| \leq \|\mathbf{a}\| \|\mathbf{b}\| \qquad (12.1.3)$$

(Triangle Inequality:) Show that

$$\|\mathbf{a} + \mathbf{b}\| \leq \|\mathbf{a}\| + \|\mathbf{b}\| \qquad (12.1.4)$$

Proof. Let **O** be the origin. In the triangle formed by $\mathbf{O}, \mathbf{a}$ and $-\mathbf{b}$, the lengths of the sides are

$$\|\mathbf{a}\|, \|\mathbf{b}\|, \|\mathbf{a} + \mathbf{b}\| \qquad (12.1.5)$$

∵ the sum of two sides of a triangle is always greater than the third side,

$$\|\mathbf{a} + \mathbf{b}\| \le \|\mathbf{a}\| + \|\mathbf{b}\| \qquad (12.1.6)$$

13 QR Decomposition

13.1. Revisiting Problem (1.15),

$$\alpha = \begin{pmatrix} 3 \\ -1 \\ 0 \end{pmatrix}, \beta = \begin{pmatrix} 2 \\ 1 \\ -3 \end{pmatrix} \qquad (13.1.1)$$

we can express

$$\alpha = k_1 \mathbf{u}_1$$
$$\beta = r_1 \mathbf{u}_1 + k_2 \mathbf{u}_2 \qquad (13.1.2)$$

where

$$k_1 = \|\alpha\|, \mathbf{u}_1 = \frac{\alpha}{k_1} \qquad (13.1.3)$$

$$r_1 = \frac{\mathbf{u}_1^T \beta}{\|\mathbf{u}_1\|^2}, \mathbf{u}_2 = \frac{\beta - r_1 \mathbf{u}_1}{\|\beta - r_1 \mathbf{u}_1\|} \qquad (13.1.4)$$

$$k_2 = \mathbf{u}_2^T \beta \qquad (13.1.5)$$

From (13.1.2),

$$\begin{pmatrix} \alpha & \beta \end{pmatrix} = \begin{pmatrix} \mathbf{u}_1 & \mathbf{u}_2 \end{pmatrix} \begin{pmatrix} k_1 & r_1 \\ 0 & k_2 \end{pmatrix} \qquad (13.1.6)$$

This is known as **QR** decomposition, where

$$\mathbf{R} = \begin{pmatrix} k_1 & r_1 \\ 0 & k_2 \end{pmatrix} \qquad (13.1.7)$$

$$\mathbf{Q} = \begin{pmatrix} \mathbf{u}_1 & \mathbf{u}_2 \end{pmatrix} \qquad (13.1.8)$$

Note that **R** is an upper triangular matrix and

$$\mathbf{Q}^T \mathbf{Q} = \mathbf{I}. \qquad (13.1.9)$$

13.2. From (13.1.1),

$$k_1 = \sqrt{10}, \mathbf{u}_1 = \frac{1}{\sqrt{10}} \begin{pmatrix} 3 \\ -1 \\ 0 \end{pmatrix}, \qquad (13.2.1)$$

$$r_1 = \frac{1}{2}, \mathbf{u}_2 = \frac{1}{\sqrt{46}} \begin{pmatrix} 1 \\ 3 \\ -6 \end{pmatrix} \qquad (13.2.2)$$

$$k_2 = \sqrt{\frac{23}{2}} \qquad (13.2.3)$$

Thus, we obtain the **QR** decompositon

$$\begin{pmatrix} 3 & 2 \\ -1 & 1 \\ 0 & -3 \end{pmatrix} = \begin{pmatrix} \frac{3}{\sqrt{10}} & \frac{1}{\sqrt{46}} \\ \frac{-1}{\sqrt{10}} & \frac{3}{\sqrt{46}} \\ 0 & \frac{-6}{\sqrt{46}} \end{pmatrix} \begin{pmatrix} \sqrt{10} & \frac{1}{2} \\ 0 & \sqrt{\frac{23}{2}} \end{pmatrix} \qquad (13.2.4)$$

14 Singular Value Decomposition

14.1. We revisit (3.2.6)

$$\begin{pmatrix} 1 & 2 \\ -1 & 1 \\ 1 & 2 \end{pmatrix} \mathbf{x} = \begin{pmatrix} 1 \\ -3 \\ -2 \end{pmatrix} \qquad (14.1.1)$$

14.2. Find $\mathbf{M}^T \mathbf{M}$ and $\mathbf{M} \mathbf{M}^T$.

14.3. Obtain the eigen decomposition

$$\mathbf{M}^T \mathbf{M} = \mathbf{P}_1 \mathbf{D}_1 \mathbf{P}_1^T \qquad (14.3.1)$$

and

$$\mathbf{M} \mathbf{M}^T = \mathbf{P}_2 \mathbf{D}_2 \mathbf{P}_2^T \qquad (14.3.2)$$

14.4. Perform the *QR* decompositions

$$\mathbf{P}_1 = \mathbf{U} \mathbf{R}_1 \mathbf{P}_2 = \mathbf{V} \mathbf{R}_2 \qquad (14.4.1)$$

14.5. The singular value decomposition is the given by

$$\mathbf{M} = \mathbf{U} \mathbf{\Sigma} \mathbf{V}^T, \qquad (14.5.1)$$

where $\mathbf{\Sigma}$ has the same shape as $\mathbf{M}$ and

$$\mathbf{\Sigma} = \begin{pmatrix} \mathbf{D}_1 & \mathbf{0} \\ \mathbf{0} & \mathbf{0} \end{pmatrix} \qquad (14.5.2)$$

14.6. (3.2.6) can then be expressed as

$$\mathbf{U} \mathbf{\Sigma} \mathbf{V}^T \mathbf{x} = \mathbf{b} \qquad (14.6.1)$$

$$\implies \mathbf{x} = \mathbf{V} \mathbf{\Sigma}^{-1} \mathbf{U}^T \mathbf{b} \qquad (14.6.2)$$

where $\mathbf{\Sigma}^{-1}$ is obtained by inverting only the non-zero elements of $\mathbf{\Sigma}$.

14.7. The relevant codes are available at

```
codes/line/skew_builtin.py
codes/line/skew_svd.py
```

Appendix A
Proofs for the Conic Sections

A.1. Substituting (4.2.1) in (4.1.2)

$$(\mathbf{P}\mathbf{y} + \mathbf{c})^T \mathbf{V} (\mathbf{P}\mathbf{y} + \mathbf{c}) + 2\mathbf{u}^T (\mathbf{P}\mathbf{y} + \mathbf{c}) + f = 0, \qquad (A.1.1)$$

which can be expressed as

$$\mathbf{y}^T\mathbf{P}^T\mathbf{V}\mathbf{P}\mathbf{y} + 2\left(\mathbf{V}\mathbf{c} + \mathbf{u}\right)^T\mathbf{P}\mathbf{y}$$
$$+ \mathbf{c}^T\mathbf{V}\mathbf{c} + 2\mathbf{u}^T\mathbf{c} + f = 0 \quad \text{(A.1.2)}$$

From (A.1.2) and (4.2.2),

$$\mathbf{y}^T\mathbf{D}\mathbf{y} + 2\left(\mathbf{V}\mathbf{c} + \mathbf{u}\right)^T\mathbf{P}\mathbf{y}$$
$$+ \mathbf{c}^T\left(\mathbf{V}\mathbf{c} + \mathbf{u}\right) + \mathbf{u}^T\mathbf{c} + f = 0 \quad \text{(A.1.3)}$$

When $\mathbf{V}^{-1}$ exists,

$$\mathbf{V}\mathbf{c} + \mathbf{u} = \mathbf{0}, \quad \text{or,}\, \mathbf{c} = -\mathbf{V}^{-1}\mathbf{u}, \quad \text{(A.1.4)}$$

and substituting (A.1.4) in (A.1.3) yields (4.2.5).

A.2. When $|\mathbf{V}| = 0, \lambda_1 = 0$ and

$$\mathbf{V}\mathbf{p}_1 = 0, \mathbf{V}\mathbf{p}_2 = \lambda_2\mathbf{p}_2. \quad \text{(A.2.1)}$$

where $\mathbf{p}_1, \mathbf{p}_2$ are the eigenvectors of $\mathbf{V}$ such that (4.2.2)

$$\mathbf{P} = \begin{pmatrix} \mathbf{p}_1 & \mathbf{p}_2 \end{pmatrix}, \quad \text{(A.2.2)}$$

Substituting (A.2.2) in (A.1.3),

$$\mathbf{y}^T\mathbf{D}\mathbf{y} + 2\left(\mathbf{c}^T\mathbf{V} + \mathbf{u}^T\right)\begin{pmatrix} \mathbf{p}_1 & \mathbf{p}_2 \end{pmatrix}\mathbf{y}$$
$$+ \mathbf{c}^T\left(\mathbf{V}\mathbf{c} + \mathbf{u}\right) + \mathbf{u}^T\mathbf{c} + f = 0$$
$$\implies \mathbf{y}^T\mathbf{D}\mathbf{y}$$
$$+ 2\left(\left(\mathbf{c}^T\mathbf{V} + \mathbf{u}^T\right)\mathbf{p}_1 \quad \left(\mathbf{c}^T\mathbf{V} + \mathbf{u}^T\right)\mathbf{p}_2\right)\mathbf{y}$$
$$+ \mathbf{c}^T\left(\mathbf{V}\mathbf{c} + \mathbf{u}\right) + \mathbf{u}^T\mathbf{c} + f = 0$$
$$\implies \mathbf{y}^T\mathbf{D}\mathbf{y}$$
$$+ 2\left(\mathbf{u}^T\mathbf{p}_1 \quad \left(\lambda_2\mathbf{c}^T + \mathbf{u}^T\right)\mathbf{p}_2\right)\mathbf{y}$$
$$+ \mathbf{c}^T\left(\mathbf{V}\mathbf{c} + \mathbf{u}\right) + \mathbf{u}^T\mathbf{c} + f = 0$$
$$\text{from (A.2.1)}$$
$$\implies \lambda_2 y_2^2 + 2\left(\mathbf{u}^T\mathbf{p}_1\right)y_1 + 2y_2\left(\lambda_2\mathbf{c} + \mathbf{u}\right)^T\mathbf{p}_2$$
$$+ \mathbf{c}^T\left(\mathbf{V}\mathbf{c} + \mathbf{u}\right) + \mathbf{u}^T\mathbf{c} + f = 0 \quad \text{(A.2.3)}$$

which is the equation of a parabola. From (A.2.3), by comparing the coefficients of y_2^2 and y_1, the focal length of the parabola is obtained as

$$\left|\frac{2\mathbf{u}^T\mathbf{p}_1}{\lambda_2}\right|. \quad \text{(A.2.4)}$$

Thus, (A.2.3) can be expressed as (4.2.6) by choosing

$$\eta = 2\mathbf{u}^T\mathbf{p}_1 \quad \text{(A.2.5)}$$

and $\mathbf{c}$ in (A.1.3) such that

$$\mathbf{P}^T\left(\mathbf{V}\mathbf{c} + \mathbf{u}\right) = \eta\begin{pmatrix} 1 \\ 0 \end{pmatrix} \quad \text{(A.2.6)}$$

$$\mathbf{c}^T\left(\mathbf{V}\mathbf{c} + \mathbf{u}\right) + \mathbf{u}^T\mathbf{c} + f = 0 \quad \text{(A.2.7)}$$

Multiplying (A.2.6) by $\mathbf{P}$ yields

$$\left(\mathbf{V}\mathbf{c} + \mathbf{u}\right) = \eta\mathbf{p}_1, \quad \text{(A.2.8)}$$

which, upon substituting in (A.2.7) results in

$$\eta\mathbf{c}^T\mathbf{p}_1 + \mathbf{u}^T\mathbf{c} + f = 0 \quad \text{(A.2.9)}$$

(A.2.8) and (A.2.9) can be clubbed together to obtain (4.2.8).