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Q.1).

$$\left. \begin{array}{l} ax + 2y = 0 \\ 2x + ay = 0 \end{array} \right\} \text{given eq}^n$$

The value of a for which there will be whole lines of solⁿ:

$$\frac{a}{2} = \frac{2}{a}$$

$$a^2 = 4$$

$$\boxed{a = \pm 2} \quad \underline{\underline{\text{Ans}}}$$

Q.2).

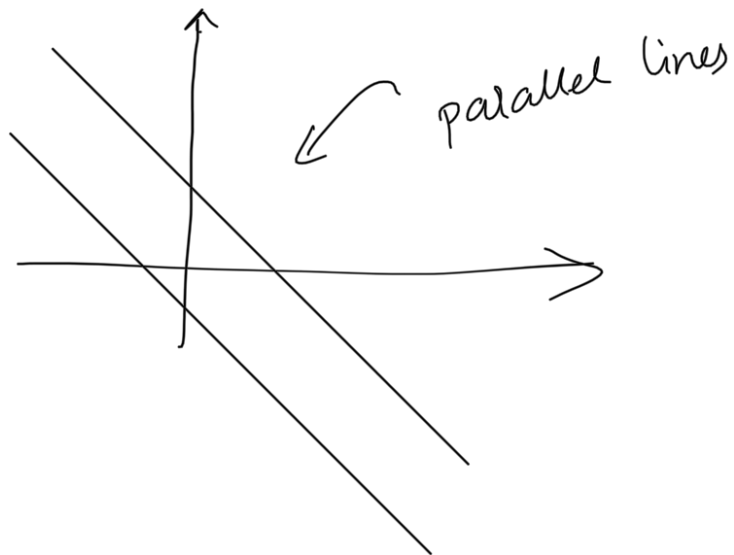
$$\left. \begin{array}{l} 3x + 2y = 10 \\ 6x + 4y = a \end{array} \right\} \text{given eq}^n\text{'s.}$$

i) No solⁿ:

Possible when both the lines are parallel

$$3x + 2y = 10 \quad - \textcircled{1}$$

$$3x + 2y = \frac{a}{2} \quad - \textcircled{2}$$



\therefore Condition for no solⁿ

$$\frac{a}{2} \neq 10$$

$$\boxed{a \neq 20}$$

ii)

Infinitely Many solⁿ:

$$\frac{a}{2} = 10$$

$$\boxed{a = 20}$$

when both lines overlap.

Q.3).

$$A(\theta) = \begin{bmatrix} \cos \theta & -\sin \theta \\ \sin \theta & \cos \theta \end{bmatrix}$$

$$A(\theta_1) = \begin{bmatrix} \cos \theta_1 & -\sin \theta_1 \\ \sin \theta_1 & \cos \theta_1 \end{bmatrix} \quad A(\theta_2) = \begin{bmatrix} \cos \theta_2 & -\sin \theta_2 \\ \sin \theta_2 & \cos \theta_2 \end{bmatrix}$$

To prove $A(\theta_1)A(\theta_2) = A(\theta_1 + \theta_2)$

$$A(\theta_1)A(\theta_2) = \begin{bmatrix} (\cos \theta_1 \cos \theta_2 - \sin \theta_1 \sin \theta_2) & -(\sin \theta_1 \cos \theta_2 + \cos \theta_1 \sin \theta_2) \\ (\sin \theta_1 \cos \theta_2 + \cos \theta_1 \sin \theta_2) & (\cos \theta_1 \cos \theta_2 - \sin \theta_1 \sin \theta_2) \end{bmatrix}$$

$$= \begin{bmatrix} \cos(\theta_1 + \theta_2) & -\sin(\theta_1 + \theta_2) \\ \sin(\theta_1 + \theta_2) & \cos(\theta_1 + \theta_2) \end{bmatrix} = \text{L.H.S}$$

$$A(\theta_1 + \theta_2) = \begin{bmatrix} \cos(\theta_1 + \theta_2) & -\sin(\theta_1 + \theta_2) \\ \sin(\theta_1 + \theta_2) & \cos(\theta_1 + \theta_2) \end{bmatrix}$$

$$L.H.S = R.H.S$$

$$A(\theta) \cdot A(-\theta) = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} \cos\theta & \sin\theta \\ -\sin\theta & \cos\theta \end{bmatrix}$$

$$= \begin{bmatrix} \sin^2\theta + \cos^2\theta & \sin\theta\cos\theta - \cos\theta\sin\theta \\ -\sin\theta\cos\theta + \sin\theta\cos\theta & \sin^2\theta + \cos^2\theta \end{bmatrix}$$

$$= \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix} = \underline{\underline{I}}$$

Q.4).

$$A = \begin{bmatrix} 1 & 1 & 0 \\ 4 & 6 & 1 \\ -2 & 2 & 0 \end{bmatrix} \quad \begin{array}{l} R_3' \rightarrow R_3 + 2R_1 \\ R_2' \rightarrow R_2 - 4R_1 \end{array}$$

$$= \begin{bmatrix} 1 & 1 & 0 \\ 0 & 2 & 1 \\ 0 & 4 & 0 \end{bmatrix} \quad R_3'' \rightarrow R_3' - 2R_2'$$

$$= \begin{bmatrix} 1 & 1 & 0 \\ 0 & 2 & 1 \\ 0 & 0 & -2 \end{bmatrix} = U$$

$$I = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix} \xrightarrow{R_2' \quad R_2 - 4R_1}$$

$$E_{21}(-4) = \begin{bmatrix} 1 & 0 & 0 \\ -4 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$E_{31}(2) = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 2 & 0 & 1 \end{bmatrix}$$

$$E_{32}(-2) = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & -2 & 1 \end{bmatrix}$$

These three matrices
put A into
upper triangular
form U .

$$E_{32} E_{31} E_{21} A = U$$

$$A = LU$$

$$L^{-1}A = L^{-1}LU$$

$$\bar{L} A = I U$$

$$M A = U$$

$$M = L^{-1}$$

$$M = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & -2 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 2 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ -4 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$= \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 2 & -2 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ -4 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$M = \begin{bmatrix} 1 & 0 & 0 \\ -4 & 1 & 0 \\ 10 & -2 & 1 \end{bmatrix}$$

$$L = E_{32}^{-1}(-2) E_{31}^{-1}(2) E_{21}^{-1}(4)$$

$$A = L U$$

$$L = M^{-1}$$

Q. 5): on \mathbb{R}^2

$$(x, y) + (x_1, y_1) = (x + x_1, 0) \quad \text{--- (1)}$$

$$c(x, y) = (cx, 0) \quad \text{--- (2)}$$

$$\therefore a(x, y) + b(x_1, y_1) = (ax + bx_1, 0)$$

for any linear combination of points in \mathbb{R}^2

the solution space is x axis which is on \mathbb{R} .

The above set of operations maps from \mathbb{R}^2 to \mathbb{R} on x axis.

\therefore The above set of operations are vector space from $\mathbb{R}^2 \rightarrow \mathbb{R}$.