

Linear system  $Ax = b$

A small error on  $b$

$$b + \Delta b$$

(ideally  $\Delta b$  is close to zero)

Instead of getting solution  $x$  we get

$$A\hat{x} = b + \Delta b$$

$$\text{Then } \hat{x} = x + \Delta x$$

But how does  $\Delta x$  compare to  $\Delta b$ ?

Let's take any vector norm  $\|\cdot\|$

The size of  $\Delta b$  relative to  $b$  is

$$\frac{\|\Delta b\|}{\|b\|}$$

we would like to say if  $\frac{\|\Delta b\|}{\|b\|}$  is small then

$$\frac{\|\Delta x\|}{\|x\|}$$

is also small.

$$Ax = b$$

and

$$A\hat{x} = b + \Delta b$$

$$A(x + \Delta x) = b + \Delta b$$

$$A(x + \Delta x) = Ax + A\Delta x$$

$$A\Delta x = \Delta b$$

$$\Delta x = A^{-1}\Delta b$$

or

$$\|\Delta x\| = \|A^{-1}\Delta b\| \leq \|A^{-1}\| \|\Delta b\|$$

$$\|A^{-1}\| \|\Delta b\|$$

$$\|\Delta x\| \leq \|A^{-1}\| \|\Delta b\|$$

$$Ax = b$$

$$\|b\| \leq \|A\| \|x\|$$

$$\frac{1}{\|b\|} \geq \frac{1}{\|A\| \|x\|}$$

$$\frac{1}{\|b\|} \geq \frac{1}{\|A\| \|x\|}$$

$$\frac{1}{\|b\|} \|A\| \geq \frac{1}{\|x\|}$$

$$\frac{1}{\|x\|} \leq \frac{1}{\|b\|} \|A\|$$

$$\frac{\|\Delta x\|}{\|x\|} \leq \frac{\|\Delta b\|}{\|b\|} \|A\| \|A^{-1}\|$$

$$\frac{\|\Delta x\|}{\|x\|} \leq \|A\| \|A^{-1}\| \frac{\|\Delta b\|}{\|b\|}$$

The factor  $\|A\| \|A^{-1}\|$  is the condition number of  $A$  denoted by  $K(A)$ .

$$K(A) = \|A\| \|A^{-1}\|$$

Theorem Let  $A$  be nonsingular and let  $x$  and  $\hat{x} = x + \Delta x$  be the solutions of  $Ax = b$  and  $A\hat{x} = b + \Delta b$

Then

$$\frac{\|\Delta x\|}{\|x\|} \leq K(A) \frac{\|\Delta b\|}{\|b\|}$$

this inequality is sharp. That is, there exists  $b$  and  $\Delta b$  such that the equality holds.

Proposition For any induced matrix norm

$$(a) \|I\| = 1$$

$$(b) K(A) \geq 1$$

(b) norm -

Best possible condition number is 1.

The condition number is dependent on the choice of norm.  
We will mainly use 1-, 2-,  $\infty$ -norms

$$K_p(A) = \|A\|_p \|A^{-1}\|_p \quad \text{for } 1 \leq p \leq \infty$$

Example Let  $A = \begin{bmatrix} 1000 & 999 \\ 999 & 998 \end{bmatrix}$

then  $A^{-1} = \begin{bmatrix} -998 & 999 \\ 999 & -1000 \end{bmatrix}$

$$\|A\|_{\infty} = 1999 \quad \|A^{-1}\|_{\infty} = 1999$$

$$\|A\|_1 = 1999 \quad \|A^{-1}\|_1 = 1999$$

$\|\cdot\|_{\infty}$  - row sum norm

$\|\cdot\|_1$  - column sum norm

$$\|A\|_1 = \max_{1 \leq j \leq n} \sum_{i=1}^n |a_{ij}|$$

$$\|A\|_{\infty} = \max_{1 \leq i \leq n} \sum_{j=1}^n |a_{ij}|$$

$$K_{\infty}(A) = K_1(A) = (1999)^2$$

$$A = \begin{bmatrix} 1000 & 999 \\ 999 & 998 \end{bmatrix}$$

$$Ax = b$$

$$b = \begin{bmatrix} b_1 \\ b_2 \end{bmatrix}$$

$$x = \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$$

$$1000x_1 + 999x_2 = b_1$$

$$999x_1 + 998x_2 = b_2$$

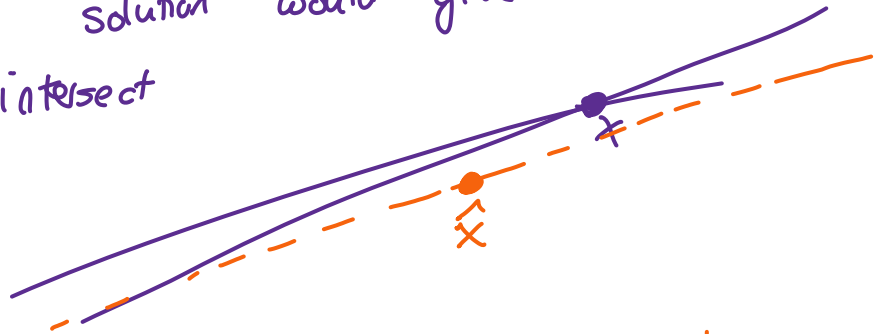
slope of line is  $m_1 = -\frac{1000}{999} \approx -1.001001$

slope of line is  $m_2 = -\frac{999}{998} \approx -1.001002$

→ Slope of line is  $m_2 = -\frac{779}{998} \approx -1.00002$

The two lines are almost parallel

The solution would give where the lines intersect



There is no number where a system goes from well-conditioned to ill-conditioned,

But it is generally agreed that the number

is somewhere between  $10^2$  to  $10^4$ ,

Let's say we are using system that only stores out to 7 decimal places,

and we have  $\frac{\| \Delta b \|}{\| b \|} \approx 10^{-7}$

If  $K(A) \approx 10^7$  we can not be sure

our answer is reasonable,

Example

Hilbert Matrices

A Hilbert Matrix

defined by  $h_{ij} = \frac{1}{i+j-1}$

and  $H_n$  denote the  $n \times n$  Hilbert matrix

$$H_4 = \begin{bmatrix} 1 & \frac{1}{2} & \frac{1}{3} & \frac{1}{4} \\ \frac{1}{2} & \frac{1}{3} & \frac{1}{4} & \frac{1}{5} \\ \frac{1}{3} & \frac{1}{4} & \frac{1}{5} & \frac{1}{6} \\ \frac{1}{4} & \frac{1}{5} & \frac{1}{6} & \frac{1}{7} \end{bmatrix}$$

The matrix is symmetric and positive

The matrix is symmetric and positive definite, but is ill conditioned as  $n$  increases

$$K_2(H_4) \approx 1.6 \times 10^4$$

$$K_2(H_8) = 1.5 \times 10^{10}$$

## Gaussian Elimination

(without pivoting)

We can always transform a linear system of equations using 3 elementary operations.

1. Add a multiple of one equation to another
2. Interchange two equations
3. Multiply an equation by a nonzero constant.

Proposition If  $\hat{A}x = \hat{b}$  is obtained from  $Ax = b$  by an elementary operation of type 1, 2, or 3 then the system  $Ax = b$  and  $\hat{A}x = \hat{b}$  are equivalent.

## Augmented Matrix

$Ax = b$  it is sometimes convenient to write  $[A | b]$

Proposition Suppose  $\hat{A}$  is obtained from  $A$  by an elementary row operation. Then  $\hat{A}$  is non singular if and only if  $A$  is non singular.

Apply Gaussian Elimination to find

Example

Apply Gaussian Elimination to find  $x$  where

$$\begin{bmatrix} 9 & -6 & 6 \\ -6 & 5 & -1 \\ 6 & -1 & 15 \end{bmatrix} x = \begin{bmatrix} 3 \\ -3 \\ 0 \end{bmatrix}$$

Augmented Matrix  $\xrightarrow{\text{Row 1} \times \frac{1}{9}}$

$$\left[ \begin{array}{ccc|c} 9 & -6 & 6 & 3 \\ -6 & 5 & -1 & -3 \\ 6 & -1 & 15 & 0 \end{array} \right] \rightarrow \left[ \begin{array}{ccc|c} 1 & -\frac{2}{3} & \frac{2}{3} & \frac{1}{3} \\ -6 & 5 & -1 & -3 \\ 6 & -1 & 15 & 0 \end{array} \right]$$

$6 \times \text{Row 1} + \text{Row 2}$

$$\rightarrow \left[ \begin{array}{ccc|c} 1 & -\frac{2}{3} & \frac{2}{3} & \frac{1}{3} \\ 0 & 1 & 3 & -1 \\ 6 & -1 & 15 & 0 \end{array} \right]$$

$-6 \times \text{Row 1} + \text{Row 3}$

$$\rightarrow \left[ \begin{array}{ccc|c} 1 & -\frac{2}{3} & \frac{2}{3} & \frac{1}{3} \\ 0 & 1 & 3 & -1 \\ 0 & 3 & 11 & -2 \end{array} \right]$$

$-3 \times \text{Row 2} + \text{Row 3}$

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

$$x = \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix}$$

$$2x_3 = 1 \Rightarrow x_3 = \frac{1}{2}$$

$$x_2 + 3\left(\frac{1}{2}\right) = -1 \Rightarrow x_2 = -1 - \frac{3}{2} = -\frac{5}{2}$$

Back substitution

$$x_1 - \frac{2}{3}\left(-\frac{5}{2}\right) + \frac{2}{3}\left(\frac{1}{2}\right) = \frac{1}{3} \Rightarrow x_1 + \frac{5}{3} + \frac{1}{3} = \frac{1}{3} \Rightarrow x_1 = \frac{1}{3} - \frac{5}{3} - \frac{1}{3} = -\frac{5}{3}$$

$$x = \begin{bmatrix} -\frac{5}{3} \\ -\frac{5}{2} \\ \frac{1}{2} \end{bmatrix}$$

$$A = \begin{bmatrix} a_{11} & a_{12} & \dots & a_{1n} \\ \vdots & \vdots & \ddots & \vdots \\ a_{n1} & a_{n2} & \dots & a_{nn} \end{bmatrix}$$

$M_{ii} = \frac{a_{ii}}{a_{ii}}$   
 $i^{\text{th}} \text{ row} \leftarrow i^{\text{th}} \text{ row} - M_{i1} (1^{\text{st}} \text{ row})$

we may find it helpful to keep track of the multiplier

$$\begin{array}{c} \downarrow \\ \left[ \begin{array}{c|ccc} a_{11} & a_{12} & \dots & a_{1n} \\ \hline 0 & a_{22}^* & \dots & a_{2n}^* \\ 0 & \vdots & \ddots & \vdots \\ \vdots & \vdots & & \vdots \\ 0 & a_{n2}^* & \dots & a_{nn}^* \end{array} \right] \end{array}$$

we may find it helpful to use the multiplier

$$\left[ \begin{array}{c|ccc} a_{11} & a_{12} & \dots & a_{1n} \\ \hline m_{21} & a_{22}^* & \dots & a_{2n}^* \\ m_{31} & \vdots & \ddots & \vdots \\ \vdots & \vdots & & \vdots \\ m_{n1} & a_{n2}^* & \dots & a_{nn}^* \end{array} \right]$$