

1 Vectors

D 1.4 (Linear Combination):

- let $v, w \in \mathbb{R}^m, \lambda, \mu \in \mathbb{R}$

$\Rightarrow \sum_{i=1}^n \lambda_i v_i$ are scaled combinations of n vectors v_i .

D 1.7 (Combination types):

- **Affine Combination:** $\sum_{i=1}^n \lambda_i = 1$

Conic Combination: if $\lambda_j \geq 0$ for $j = 1, 2, \dots, n$

Convex Combination: Affine + Conic

D 1.9 (Scalar/dot product):

- $\mathbf{v} \cdot \mathbf{w} := \sum_{i=1}^m v_i w_i$, alternative notation: $[z_i]_{i=1}^m := [v_i + w_i]_{i=1}^m$

D 1.11 (Euclidean norm, squared norm, unit vector):

- $\|\mathbf{v}\| := \sqrt{\mathbf{v}^\top \mathbf{v}} = \sqrt{\mathbf{v}^\top \mathbf{v}}$, Squared norm: $\|\mathbf{v}\|^2 := \mathbf{v}^\top \mathbf{v}$,

Unit vector: $\|\mathbf{u}\| = 1 = \frac{\mathbf{v}}{\|\mathbf{v}\|} = \frac{1}{\|\mathbf{v}\|} \mathbf{v}$ (for any vector $\mathbf{v} \neq 0$)

L 1.12 (Cauchy-Schwarz inequality):

- $|\mathbf{v} \cdot \mathbf{w}| \leq \|\mathbf{v}\| \|\mathbf{w}\|$ for any two vectors $\mathbf{v}, \mathbf{w} \in \mathbb{R}^m$

D 1.14 (Angle between vectors):

- $\cos(\alpha) = \frac{\mathbf{v} \cdot \mathbf{w}}{\|\mathbf{v}\| \|\mathbf{w}\|} \in [-1, 1]$

D 1.16 (Hyperplane through origin):

- Let $\mathbf{d} \in \mathbb{R}^m, \mathbf{d} \neq 0, H_{\mathbf{d}} = \{\mathbf{v} \in \mathbb{R}^m : \mathbf{v} \cdot \mathbf{d} = 0\}$

L 1.16 (Triangle inequality):

- $\|\mathbf{v} + \mathbf{w}\| \leq \|\mathbf{v}\| + \|\mathbf{w}\|$

D 1.21 (Linear (in)dependence):

- vectors are linearly dependent if one of them is linear combination of the others: $\mathbf{v}_k = \sum_{j=1, j \neq k}^n \lambda_j \mathbf{v}_j$

\Leftrightarrow There are scalars $\lambda_1, \lambda_2, \dots, \lambda_n$ besides $0, 0, \dots, 0$ such that $\sum_{j=1}^n \lambda_j \mathbf{v}_j = \mathbf{0}$. We also say that $\mathbf{0}$ is a nontrivial linear combination of the vectors.

\Leftrightarrow At least one of the vectors is a linear combination of the previous ones.

D 1.25 (Span):

- Span of vectors is a set of all linear combinations of those vectors: $\text{Span}(\mathbf{v}_1, \mathbf{v}_2, \dots, \mathbf{v}_n) := \left\{ \sum_{j=1}^n \lambda_j \mathbf{v}_j : \lambda_j \in \mathbb{R} \text{ for all } j \in [n] \right\}$

Construction of vectors with standard unit vectors:

- Every target vector can be written as: $\mathbf{u} = \sum_{i=1}^m u_i \mathbf{e}_i$, where \mathbf{e} is a standard unit vector.

2 Matrices

D 2.1 (Matrix):

- $A = [a_{ij}]_{i=1, j=1}^{m, n}$ - m rows, n columns (Zeilen zuerst, Spalten später)

D 2.2 (Matrix addition, scalar multiplication):

- Addition: $A + B = [a_{ij} + b_{ij}]_{i=1, j=1}^{m, n}$

- Scalar multiplication: $\lambda A = [\lambda a_{ij}]_{i=1, j=1}^{m, n}$

Matrix types:

- Identity matrix ($a_{ii} = 1$ for all i): I
- Diagonal matrix ($a_{ij} = 0$ for all $i \neq j$): $\text{diag}(d_1, \dots, d_n)$
- Upper triangular matrix ($a_{ij} = 0$ for all $i > j$): U
- Lower triangular matrix ($a_{ij} = 0$ for all $i < j$): L
- Symmetric matrix ($a_{ij} = a_{ji}$ for all i, j): $A = A^\top$
- Skew-symmetric matrix ($a_{ij} = -a_{ji}$ for all i, j): $A = -A^\top$

D 2.4 (Matrix-vector product):

- Rows of matrix ($m \times n$) with vector (n elements), i.e.

$u_1 = \sum_{i=1}^m a_{1, i} v_i, Ix = x$; **Trace:** Sum of the diagonal entries.

D 2.9 (Column space):

- The column space $C(A)$ of A is the span (set of all linear combinations) of the columns: $C(A) := \{Ax : x \in \mathbb{R}^n\} \subseteq \mathbb{R}^m$

D 2.10 (Rank):

- $\text{rank}(A) :=$ the number of linearly independent column vectors of A .

D 2.11 (Transpose):

- Mirror the matrix along its diagonal. $A = \begin{bmatrix} 1 & 2 & 3 \\ 4 & 5 & 6 \end{bmatrix} \leftrightarrow A^\top = \begin{bmatrix} 1 & 4 \\ 2 & 5 \\ 3 & 6 \end{bmatrix}$

(A^T)^T = A

D 2.13 (Row space):

- $R(A) := C(A^\top)$

D 2.17 (Nullspace):

- Nullspace contains all input vectors that lead to output vector $\mathbf{0}$.

$N(A) = \{\mathbf{x} \in \mathbb{R}^n : Ax = \mathbf{0}\} \subseteq \mathbb{R}^n$

D 2.27 (Kernel & Image):

- **Kernel:** $N(A) = \text{Ker}(T) := \{\mathbf{x} \in \mathbb{R}^n : T(\mathbf{x}) = \mathbf{0}\} \subseteq \mathbb{R}^n$ (If A is the unique $m \times n$ matrix such that $T = TA$)

- **Image:** $C(A) = \text{Im}(T) := \{T(\mathbf{x}) : \mathbf{x} \in \mathbb{R}^n\} \subseteq \mathbb{R}^m$ (If A is the unique $m \times n$ matrix such that $T = TA$), the set of all outputs that T can produce.

2.2.2 Working with linear transformations:

A matrix can be understood as a re-mapping of the unit vectors, scaling and re-orienting them. Each column vector can then be understood as the new unit vector e_i , hence essentially adding another coordinate system to the original one, which is moved and rotated a certain way. The rotation matrix under 2 is such an example. To prove that T is a linear transformation, use $T(x+y) = T(x) + T(y)$ and $T(\lambda x) = \lambda T(x)$. Then insert the linear transformation given by the task and replace x (or whatever variable there is) with $x+y$ or λx . $Ax = \sum_{i=1}^n x_i v_i$, where v_i is the i -th column of A .

O 2.39 (Matrix multiplication):

- $A \times B = C, c_{ij} = \sum_{k=1}^n a_{ik} b_{kj}$. Dimension restrictions: A is $m \times n$, B is $n \times p$, result is $m \times p$. For each entry, multiply the i -th row of A with the j -th column of B .

Not commutative, but associative & distributive.

L 2.40 Matrix multiplication with transposition:

- $(AB)^\top = B^\top A^\top$

D 2.44 Outer product:

- $\text{rank}(A) = 1 \iff \exists$ non-zero vectors $v \in \mathbb{R}^m, w \in \mathbb{R}^n$ such that A is an outer product, i.e. $A = vw^\top$, thus $\text{rank}(vw^\top) = 1$.

T 2.46 (CR decomposition):

- $A = CR$. Get R from (reduced) row echelon form. C is the columns from A where there is a pivot in R . $C \in \mathbb{R}^{m \times r}, R \in \mathbb{R}^{r \times n}$ (in RREF), $r = \text{rank}(A)$.

Row Echelon Form: To find REF, try to create pivots: $R_0 = \begin{bmatrix} 1 & 0 & 2 & 3 \\ 0 & 1 & 2 & 1 \\ 0 & 0 & 0 & 0 \end{bmatrix}$. Use Gauss-Jordan elimination to find it (row formations). **Reduced REF:** RREF is simply REF without any zero rows (i.e. in R_0 , R (in RREF) would be R_0 without the last row).

O 2.5.6 (Invertible matrix):

- Matrix A is invertible if it is square and there is B such that:

$$AB = I \Leftrightarrow BA = I \Leftrightarrow AB = BA = I$$

D 2.57 (Inverse matrix and its properties):

- If $AB = I$ for invertible A , then B is its inverse and denoted as A^{-1} . $(A^{-1})^{-1} = A$ • $(AB)^{-1} = B^{-1}A^{-1}$ • $(A^\top)^{-1} = (A^{-1})^\top$

4 Four Fundamental Subspaces

4.1 Vector Spaces

D 4.1 (Vector Space):

- Vector space is a triple $(V, +, \cdot)$ where V is a set (the vectors) with two operations \oplus and \odot . They are based on algebras called fields and satisfy axioms: *commutativity*, *associativity*, *zero vector*, *negative vector*, *identity element*, *compatibility of multiplications of vectors and scalars* ($\in \mathbb{R}$), *distributivity over \oplus* both for vectors and scalars ($\in \mathbb{R}$)).

D 4.8 (Subspace):

- Let V be a vector space. A nonempty subset $U \subseteq V$ is a subspace of V if

following axioms are true $\forall \mathbf{v}, \mathbf{w} \in U$ and $\forall \lambda \in \mathbb{R}$:

- $\mathbf{v} + \mathbf{w} \in U$

They guarantee that vector addition and scalar multiplication "doesn't take us outside of a subspace".

L 4.9 (Subspace always has 0):

- Let $U \subseteq V$ be a subspace of a vector space V . Then $\mathbf{0} \in U$ (at least).

L 4.11 (Column space is a subspace):

- Let $A \in \mathbb{R}^{m \times n}$, then $C(A) = \{Ax : x \in \mathbb{R}^n\}$ is subspace of \mathbb{R}^m . $\Rightarrow R(A) = C(A^\top)$ is a subspace of \mathbb{R}^n .

E 4.13 (The nullspace is a subspace):

- Let $A \in \mathbb{R}^{m \times n}$. Then the nullspace $N(A) = \{\mathbf{x} \in \mathbb{R}^n : Ax = \mathbf{0}\}$ is a subspace of \mathbb{R}^n

L 4.14 (Subspaces are vector spaces):

- V is a vector space and U is its subspace. Then U is also a vector space with the same \oplus and \odot as V .

4.2 Bases and dimension

D 4.18 (Basis):

- Let V be a vector space. A subset $B \subseteq V$ is called a basis of V if B is linearly independent and it spans V : $\text{Span}(B) = V$.

L 4.19 (Independent columns is a basis):

- Independent columns form basis of column space $C(A)$.

O 4.20 (Non-uniqueness of basis):

- Every set $B = \{\mathbf{v}_1, \mathbf{v}_2, \dots, \mathbf{v}_n\} \subseteq \mathbb{R}^m$ of m linearly independent vectors is a basis of \mathbb{R}^m .

D 4.21 (Finitely generated vector space):

- There is a finite subset $G \subseteq V$ with $\text{Span}(G) = V$. Then V has a basis $B \subseteq G$.

T 4.22 (Finitely generated VS has a basis):

- If V is finitely generated, then V has a basis $B \subseteq V$.

L 4.23 (Steinitz exchange lemma):

- "exchanging elements between G and F "

V is finitely generated vector space, $F \subseteq V$ a finite set of lin. independent vectors, and $G \subseteq V$ a finite set of vectors with $\text{Span}(G) = V$, then:

- $|V| \leq |G|$ and • $\exists E \subseteq G$ of size $|G| - |F|$ such that $\text{Span}(F \cup E) = V$.

T 4.24 (All bases have the same size):

- All bases have the same size: $B, B' \in V \Rightarrow |B| = |B'|$.

D 4.25 (Dimension):

- $\dim(V)$ - the dimensions of V . It has a size of arbitrary basis B of V .

D 4.26 (Linear transformation between vector spaces):

- Let V, W be vector spaces. A function $T : V \rightarrow W$ is linear if, for all $x_1, x_2 \in V$ and $\lambda_1, \lambda_2 \in \mathbb{R}$, $T(\lambda_1 x_1 + \lambda_2 x_2) = \lambda_1 T(x_1) + \lambda_2 T(x_2)$.

L 4.27 (Bijective lin. transformations preserve basis):

- If $T : V \rightarrow W$ is a bijective linear map, then $B \subseteq V$ is a basis of $V \Leftrightarrow T(B)$ is a basis of W , and hence $\dim(V) = \dim(W)$.

D 4.28 (Isomorphic vector spaces):

- $V \cong W \iff \exists T : V \rightarrow W$ linear and bijective.

T 4.29 (Basis writes vectors as a unique lin. combination):

- Let V be a finite-dimensional vector space with basis $B = \{v_1, \dots, v_m\}$. Then every $v \in V$ can be written uniquely as $v = \sum_{j=1}^m \lambda_j v_j$, for unique scalars $\lambda_1, \dots, \lambda_m$.

L 4.30 (Less than dim(V) vectors do not span V):

- If $|G| < \dim V$, then $\text{span}(G) \neq V$.

4.3 Computing the three fundamental subspaces

T 4.31 (Basis of C(A): Pivots columns of RREF):

- R is RREF of A , then all columns at pivots of R form a basis of $C(A)$: $\dim(C(A)) = \text{rank}(A) = r$

T 4.32 (Basis of $R(A)$: Nonzero rows of RREF(A)):

- Nonzero rows of RREF(A) form a basis of $R(A)$, so, $\dim(R(A)) = r$.

T 4.33 (Row rank equals columns rank):

- $\text{rank}(A) = \text{rank}(A^\top)$

C 4.34 (Rank is at most min of the matrix dimensions):

- A is a $m \times n$ matrix with rank $r \Rightarrow r \leq \min(n, m)$.

L 4.35 (Nullspace isomorphism):

- $R = \text{RREF}(A)$, then $T : N(R) \rightarrow \mathbb{R}^{n-r}$ is an isomorphism between $N(R)$ and $\mathbb{R}^{n-r} \Rightarrow \dim(N(R)) = n - r$.

T 4.36 (Basis of $N(A)$: Non-pivot columns of RREF(A)):

- If $\text{rank}(A) = r$, then $\dim(N(A)) = n - r$.

4.4 All solutions of $Ax = b$

D 4.37 (Solution space):

- Solution space of $Ax = b$:

$$\text{Sol}(A, b) := \{x \in \mathbb{R}^n : Ax = b\} \subseteq \mathbb{R}^n$$

T 4.38 (Solution space from shifting the nullspace):

- Let s be some solution of $Ax = b$, then:

$$\text{Sol}(A, b) := \{s + x \in \mathbb{R}^n : x \in N(A)\}.$$

We can also compute $\text{Sol}(A, b)$, although it is not a subspace.

T 4.39 (Dimension of a solution space):

- Let $A \in \mathbb{R}^{m \times n}$ with rank r . If $Ax = b$ is solvable, then:

$$\dim(\text{Sol}(A, b)) = n - r, \text{ and } \dim(\text{Sol}(A, b)) := \dim(N(A)).$$

T 4.40 (Systems of rank m are solvable):

- Let $A \in \mathbb{R}^{m \times n}$ with $\text{rank}(A) = m$, $Ax = b$ is solvable for all $b \in \mathbb{R}^m$.

T 4.41 (Systems of rank less than m are typ. unsolvable):

- Systems of rank $r < m$ are typically unsolvable.

D 4.42 (Types of systems):

- Let $A \in \mathbb{R}^{m \times n}$ and $b \in \mathbb{R}^m$. The system $A \in \mathbb{R}^{m \times n}$ is called:

• $m = n \Rightarrow$ square (A is a square matrix) * typ. solvable

• $m < n \Rightarrow$ underdetermined (A is a wide matrix) * typ. solvable

• $m > n \Rightarrow$ overdetermined (A is a tall matrix) * typ. unsolvable. "Typical" matrices are with $m \leq n$ and have rank $r = m$.

5 Orthogonality and Projections

5.1 Definition

Orthogonality:

- A geometric and algebraic tool in order to be able to decompose a space into subspaces.

D 5.1.1 (Orthogonal subspaces):

- Two vectors are orthogonal if their scalar product is 0: $v^\top w = \sum_{i=1}^n v_i w_i = 0$. Two subspaces are orthogonal if all v and w are orthogonal.

L 5.1.2 (Orthogonality of bases):

- Let v_1, \dots, v_r and w_1, \dots, w_s be bases of subspaces W and V . W and V are orthogonal \Leftrightarrow all v_i orthogonal to all w_j

L 5.1.3 (Combinations and interaction of subspaces):

- The set of vectors $\{v_1, \dots, v_r, w_1, \dots, w_s\}$ are linearly independent.
- The union of bases of two subspaces gives a basis for the new subspace: $V \cup W = V + W = \{\lambda v + \mu w \mid \lambda, \mu \in \mathbb{R}, v \in V, w \in W\}$.
- If V and W are subspaces of \mathbb{R}^n , then $V + W$ is a subspace of \mathbb{R}^n .
- $V \cap W = \{0\}$ if subspaces are orthogonal.
- $\dim(V) = k$ and $\dim(W) = l$, then $\dim(V + W) = k + l \leq n$.

D 5.1.5 (Orthogonal complement):

- Let V be a subspace of \mathbb{R}^n , its orthogonal complement: $V^\perp = \{w \in \mathbb{R}^n \mid w^\top v = 0 \text{ for all } v \in V\}$.

T 5.1.6 (Relations between subspaces):

- $N(A) = C(A^\top)^\perp = R(A)^\perp$ and $C(A^\top) = N(A)^\perp$

T 5.1.7 (Vector decomposition by orth. complements):

- $W = V^\perp \Leftrightarrow \dim(V) + \dim(W) = n \Leftrightarrow$ every $u \in \mathbb{R}^n$ is $u = v + w$, v and w are unique.

L 5.1.10 (Justification of exist. of sol. for normal eq.):

- Let $A \in \mathbb{R}^{m \times n}$. Then $N(A) = N(A^\top A)$ and $C(A^\top) = C(A^\top A)$.

5.2 Projections

D 5.2.1 (Projection):

- Projection of $b \in \mathbb{R}^m$ on a subspace S (of \mathbb{R}^m) is the point in S that is closest to b : $\text{proj}_S(b) = \arg \min_{p \in S} \|b - p\|$.

L 5.2.2 (One-dimensional Projection Formula):

- Projection of b on $S = \{\lambda a \mid \lambda \in \mathbb{R}\} = C(a)$: $\text{proj}_S(b) = \frac{a a^\top}{a^\top a} b$.
- "Error vector" ($e = b - p$) is perpendicular projection: $(e = b - \text{proj}_S(b)) \perp \text{proj}_S(b)$.

L 5.2.3 (General Projection Formula):

- Let S be a subspace in \mathbb{R}^m with a basis a_1, \dots, a_n that span S . Let A be the matrix with column vectors a_1, \dots, a_n .

- The general formula: $\text{proj}_S(b) = A \hat{x}$, where \hat{x} is $A^\top A \hat{x} = A^\top b$.

L 5.2.4 (Properties of $A^\top A$):

- $A^\top A$ is invertible $\Leftrightarrow A$ has linearly independent columns. $\Rightarrow A^\top A$ is a square matrix, symmetric, invertible.

T 5.2.5 (Projection in terms of projection matrix):

- $\text{proj}_S(b) = Pb$ with projection matrix $P = A(A^\top A)^{-1} A^\top$. A is matrix given in a task.

6 Applications of Orthogonality and Projections

6.1 Least Squares Approximation

Least Squares:

- Approximate a solution to System of equations: find x for which Ax is as close as possible to b : $\min_{x \in \mathbb{R}^n} \|Ax - b\|^2$

usage:

- find $M = A^\top A$, $b' = A^\top b$, solve $M\hat{x} = b'$

Linear Regression:

- Fitting a parabola

$$(t_k, b_k) = \{(0, 1), (1, 2), (2, 5)\}, b_k \approx \alpha_0 + \alpha_1 t_k + \alpha_2 t_k^2 \\ A = \begin{pmatrix} 1 & 0 & 0 \\ 1 & 1 & 1 \\ 1 & 2 & 4 \end{pmatrix}, b = \begin{pmatrix} 1 \\ 2 \\ 5 \end{pmatrix}, \hat{\alpha} = (A^\top A)^{-1} A^\top b = \begin{pmatrix} 1 \\ 0 \\ 1 \end{pmatrix}, \hat{b}(t) = 1 + t + t^2.$$

L 6.1.2:

- Matrix A ($m \times 2$) has linearly dependent columns $\Leftrightarrow t_i = t_j \forall i \neq j$.

6.2 The set of all solutions to a system of linear equations

L 6.2.1 (Injectivity of A on $C(A^\top)$, uniqueness of sol.):

- $A \in \mathbb{R}^{m \times n}$, $x, y \in C(A^\top) : Ax = Ay \Leftrightarrow x = y$

This leads to: $C(A^\top) \cap N(A) = \{0\}$

T 6.2.2 (Set of all solution of linear equations):

- Set of all sol. : $\{x \in \mathbb{R}^n \mid Ax = b\} \neq \emptyset$, then:

$$\{x \in \mathbb{R}^n \mid Ax = b\} = x_1 + N(A), \quad x_1 \in R(A) \text{ is unique s.t. } Ax_1 = b.$$

T 6.2.4 (Linear equations with no solution):

- Linear equations has no solution:

$$\{x \in \mathbb{R}^n \mid Ax = b\} = \emptyset \Leftrightarrow \{z \in \mathbb{R}^m \mid A^\top z = 0, b^\top z = 1\} \neq \emptyset.$$

6.3 Orthonormal Bases and Gram Schmidt

D 6.3.1 (Orthonormal vectors):

- $q_i^\top q_j = \delta_{ij} = \begin{cases} 0 & i \neq j \\ 1 & i = j \end{cases}$ (orthogonal and have norm 1)

D 6.3.3 (Orthogonal Matrix):

- A square matrix $Q \in \mathbb{R}^{n \times n}$ is an *orthogonal matrix* when $Q^\top Q = I$. If it is square, then, $QQ^\top = I$, $Q^{-1} = Q^\top$, and the columns of Q form an orthonormal basis for \mathbb{R}^n .

- Orthogonal (rotation) matrix example: $R_\theta = \begin{bmatrix} \cos \theta & -\sin \theta \\ \sin \theta & \cos \theta \end{bmatrix}$.

P 6.3.6 (Preserving qualities of orthogonal matrices):

- Orthogonal matrices preserve norm and inner product of vectors: $\|Qx\| = \|x\|$ and $(Qx)^\top (Qy) = x^\top y$

P 6.3.7 (Least square solution to $Qx = b$):

- The least square solution to $Qx = b$, where Q is the matrix whose columns are the vectors forming the orthonormal basis of $S \subseteq \mathbb{R}^m$, is given by $\hat{x} = Q^\top b$ and the projection matrix is given by QQ^\top .

D 6.3.8 (Gram-Schmidt algorithm):

- Gram-Schmidt: used to construct orthonormal bases.

We have linearly independent vectors a_1, \dots, a_n that span a subspace S , then we can construct their orthonormal basis q_1, \dots, q_n by:

$$q_1 = \frac{a_1}{\|a_1\|}.$$

$$\text{For } k = 2, \dots, n \text{ do } q'_k = a_k - \sum_{i=1}^{k-1} (a_k^\top q_i) q_i, \quad q_k = \frac{q'_k}{\|q'_k\|}.$$

$$\text{normalise } q_k = \frac{q'_k}{\|q'_k\|}.$$

D 6.3.10 (QR-Decomposition):

- $A = QR$, where $R = Q^\top A$, and Q is a matrix with orthonormal columns produced by Gram-Schmidt.

D 6.3.11 (Well-Defined QR Decomposition):

- R - upper-triangular and invertible $\Rightarrow QQ^\top A = A$, and hence, $A = QR$ is well-defined.

Simplicity of calculation with Q :

- Projection: $\text{proj}_{C(A)}(b) = QQQ^\top b$, Least Squares: $R\hat{x} = Q^\top b$

This is possible because $C(A) = C(Q)$ and R is triangular - we can use back-substitution with it.

6.4 Pseudoinverses

D 6.4.1 (Left pseudoinverse):

- For $A \in \mathbb{R}^{m \times n}$ with full-column rank $\text{rank}(A) = n$, we get pseudoinverse $A^\dagger \in \mathbb{R}^{n \times m}$ as $A^\dagger = (A^\top A)^{-1} A^\top$. A^\dagger is a left inverse: $A^\dagger A = I$

D 6.4.3 (Right pseudoinverse):

- For $A \in \mathbb{R}^{m \times n}$ with full row rank $\text{rank}(A) = m$ we get $A^\dagger \in \mathbb{R}^{n \times m}$ as $A^\dagger = A^\top (AA^\top)^{-1}$. A^\dagger is a right inverse: $AA^\dagger = I$

D 6.4.7 (CR decomposition with pseudoinverses):

- For $A \in \mathbb{R}^{m \times n}$ with $\text{rank}(A) = r$ and a CR-decomposition $A = CR$, we define $A^\dagger = R^\dagger C^\dagger$. In general, $A^\dagger = R^\dagger (RR^\top)^{-1} (C^\top C)^{-1} C^\dagger = R^\dagger (C^\top CRR^\top)^{-1} C^\dagger = R^\dagger (C^\top AR^\top)^{-1} C^\dagger$.

L 6.4.8 (Unique solution of least sq. with pseudoinverses):

- For any matrix A and vector $b \in C(A)$, the unique solution of the least squares problem is given by a vector $\hat{x} \in C(A^\top)$ satisfying $A\hat{x} = b$. The solution is $\hat{x} = A^\dagger b$, with $A\hat{x} = b$, and in the general case $A^\dagger = R^\dagger C^\dagger = R^\dagger (C^\top AR^\top)^{-1} C^\dagger$.

P 6.4.9 (TS decomposition):

- For $A \in \mathbb{R}^{m \times n}$ with $\text{rank}(A) = r$, let $S \in \mathbb{R}^{m \times r}$, $T \in \mathbb{R}^{r \times n}$ such that $A = ST$. Then $A^\dagger = T^\dagger S^\dagger$.

T 6.4.10 (Pseudoinverses properties):

- Let $A \in \mathbb{R}^{m \times n}$. Then $AA^\dagger A = A$, $A^\dagger AA^\dagger = A^\dagger$, $(A^\dagger)^T = (A^\top)^\dagger$.

AA^\dagger is symmetric \Rightarrow projection matrix onto $C(A)$,

$A^\dagger A$ is symmetric \Rightarrow projection matrix onto $C(A^\top)$.

Moreover, $AA^\dagger = CRR^\top (RR^\top)^{-1} (C^\top C)^{-1} C^\dagger = C(C^\top C)^{-1} C^\dagger$, which is the projection onto $C(A)$, and $(AA^\dagger)^T = AA^\dagger$.

7 The Determinant

7.1 2 times 2

D 7.1.1 (2 × 2 Determinant):

- For $A = \begin{bmatrix} a & b \\ c & d \end{bmatrix}$, $\det(A) = ad - bc$.

L 7.1.2 (Multiplication of determinants):

- $\det(AB) = \det(A)\det(B)$.

Hence, for an LU-decomposition, $\det(A) = \det(L)\det(U)$.

D 7.2.1 (Permutation sign):

- The sign of a permutation is defined as the number of swaps of rows or columns. $\det(\text{permuted matrix}) = (-1)^k \det(\text{original matrix})$, where k is the number of swaps. Even number of swaps $\Rightarrow +1$, odd number $\Rightarrow -1$. $\text{sgn}(\sigma \circ \gamma) = \text{sgn}(\sigma) \text{sgn}(\gamma)$. For all $n \geq 2$, half of the permutations have sign $+1$, half have sign -1 .

7.2 General case:

D 7.2.3 (Determinant big formula):

- For a square matrix $A \in \mathbb{R}^{n \times n}$, $\det(A) = \sum_{\sigma \in \Pi_n} \text{sgn}(\sigma) \prod_{i=1}^n A_{i,\sigma(i)}$. (Number of permutations: $n!$)

• Determinant Properties:

- Matrix $T \in \mathbb{R}^{n \times n}$ is triangular, then $\det(T) = \prod_{k=1}^n T_{kk}$, in particular $\det(I) = 1$.
- Matrix $A \in \mathbb{R}^{n \times n}$, $\det(A) = \det(A^T)$.
- Matrix $Q \in \mathbb{R}^{n \times n}$ is orthogonal $\iff \det(Q) = 1$ or $\det(Q) = -1$.
- Matrix $A \in \mathbb{R}^{n \times n}$ is invertible $\iff \det(A) \neq 0$.
- Matrices $A, B \in \mathbb{R}^{n \times n}$, $\det(AB) = \det(A)\det(B)$, in particular $\det(A^n) = \det(A)^n$.
- Matrix $A \in \mathbb{R}^{n \times n}$, $\det(A^{-1}) = \frac{1}{\det(A)}$.
- $\det(\lambda A) = \lambda^n \det(A)$.

P 7.2.4 (Determinant of orthogonal matrices):

- $1 = \det(I) = \det(Q^T Q) = \det(Q^T) \det(Q) = \det(Q)^2$, so $\det(Q) = \pm 1$. If $\det(Q) = 1$, then Q is a rotation matrix. If $\det(Q) = -1$, then Q is a reflection matrix.

P 7.3.2 (Cofactor determinant calculation):

• Co-factor method:

$$\det(A) = \sum_{j=1}^n A_{ij} C_{ij}, \text{ where cofactors are } C_{ij} = (-1)^{i+j} \det(A_{ij}),$$

P 7.3.5 (Cramer's Rule):

- Cramer's Rule: For $Ax = b$ with $\det(A) \neq 0$, $x_j = \frac{\det(\mathcal{B}_j)}{\det(A)}$, where \mathcal{B}_j is the matrix obtained from A by replacing the j -th column with b .

P 7.3.7 (Linearity of a determinant):

- The determinant is linear in each row (and column). For example, $\det \left[\alpha_0 a_0^T + \alpha_1 a_1^T \right] = \alpha_0 \det \left[a_0^T \right] + \alpha_1 \det \left[a_1^T \right]$.

8 Eigenvalues and Eigenvectors

8.1 Complex Numbers

- Solve $x^2 + 1 = 0 \Rightarrow x = \sqrt{-1} \Rightarrow \mathbb{C} = \{a + ib : a, b \in \mathbb{R}\}$.
- $(a + ib) + (x + iy) = (a + x) + i(b + y)$,
- $(a + ib)(x + iy) = (ax - by) + i(ay + bx)$,
- $(a + ib)(a - ib) = a^2 + b^2$.
- $\frac{a+ib}{x+iy} = \frac{(a+ib)(x-iy)}{x^2+y^2} = \frac{ax+by}{x^2+y^2} + i \frac{bx-ay}{x^2+y^2}$.
- $|z| = \sqrt{a^2 + b^2}$, $z = a + ib$,
- $a + ib = a - ib$.

R 8.1.1 (Euler's formula):

- For $\theta \in \mathbb{R}$, $e^{i\theta} = \cos \theta + i \sin \theta \Rightarrow e^{i\pi} = -1$

Polar form of a complex number:

- $z = re^{i\theta}$, $z \in \mathbb{C}$, $r > 0$ is the modulus of z , $\theta \in [0, 2\pi)$.

T 8.1.2 (Fundamental Theorem of Algebra):

- Any degree n non-constant ($n \geq 1$) polynomial $P(z) = \alpha_n z^n + \alpha_{n-1} z^{n-1} + \dots + \alpha_1 z + \alpha_0$, ($\alpha_n \neq 0$) has a zero: there exists $\lambda \in \mathbb{C}$ such that $P(\lambda) = 0$. \Rightarrow A degree- n polynomial has at most n distinct zeros (roots).

C 8.1.3 (Algebraic multiplicity, num. of 0 in polynomial):

- Any degree n non-constant ($n \geq 1$) polynomial has n zeros $\lambda_1, \dots, \lambda_n \in \mathbb{C}$, and $P(z) = \alpha_n(z - \lambda_1)(z - \lambda_2) \dots (z - \lambda_n)$. The number of times $\lambda \in \mathbb{C}$ appears in the expression is called the *algebraic multiplicity* of the zero.

Inner product on \mathbb{C}^n :

- The inner product on \mathbb{C}^n is given by $\langle v, w \rangle = w^* v$.

Conjugate transpose:

- $A^* = \bar{A}^T$.

8.2 Introduction to Eigenvalues and Eigenvectors

D 8.2.1 (EW/EV pair):

- Given $A \in \mathbb{R}^{n \times n}$, we say $\lambda \in \mathbb{C}$ is an *eigenvalue* of A and $v \in \mathbb{C}^n \setminus \{0\}$ is an *eigenvector* of A associated with λ when $Av = \lambda v$. (λ, v) is an eigenvalue–eigenvector pair. If $\lambda \in \mathbb{R}$, then we have a real eigenvalue–eigenvector pair.

L 8.2.3 (Real EW/EV):

- Let $A \in \mathbb{R}^{n \times n}$. Then $\lambda \in \mathbb{R}$ is a real eigenvalue of A if and only if $\det(A - \lambda I) = 0$. A vector $v \in \mathbb{R}^n \setminus \{0\}$ is an eigenvector associated with λ if and only if $v \in \mathcal{N}(A - \lambda I)$.

D 8.3.4 (Characteristic Polynomial):

- The characteristic polynomial: $(-1)^n \det(A - zI) = \det(zI - A) = (z - \lambda_1)(z - \lambda_2) \dots (z - \lambda_n)$. The coefficient of z^n is $(-1)^n$.

T 8.2.5 (Existence of EW):

- Every matrix $A \in \mathbb{R}^{n \times n}$ has an eigenvalue (possibly complex-valued).

P 8.2.7 (EW of orthogonal matrix):

- If $Q \in \mathbb{R}^{n \times n}$ is orthogonal and $\lambda \in \mathbb{C}$ is an eigenvalue of Q , then $|\lambda| = 1$.

L 8.2.8 (Complex EW exist in conjugate pairs for real A):

- Let $A \in \mathbb{R}^{n \times n}$. If (λ, v) is an eigenvalue–eigenvector pair, then $(\bar{\lambda}, \bar{v})$ is also an eigenvalue–eigenvector pair.

8.3 Properties of Eigenvalues and Eigenvectors

P 8.3.1 (EW modifications based on types of a matrix):

- If (λ, v) is an eigenvalue–eigenvector pair of A , then (λ^k, v) is an eigenvalue–eigenvector pair of A^k for $k \geq 1$.
- If (λ, v) is an eigenvalue–eigenvector pair of A with $\lambda \neq 0$, then $(\frac{1}{\lambda}, v)$ is an eigenvalue–eigenvector pair of A^{-1} .

L 8.3.2 (Linear independence):

- If $\lambda_1, \dots, \lambda_n$ are all distinct, the corresponding eigenvectors v_1, \dots, v_n are linearly independent.

T 8.3.3 (Existence of a basis from EV):

- Let $A \in \mathbb{R}^{n \times n}$ with n distinct real eigenvalues. Then there exists a basis of \mathbb{R}^n , v_1, \dots, v_n , made of eigenvectors of A .

D 8.3.4 (Trace of a matrix):

- The trace of A is defined by $\text{Tr}(A) = \sum_{i=1}^n A_{ii}$.

L 8.3.5 (Transposition equality of EW):

- The eigenvalues of $A \in \mathbb{R}^{n \times n}$ are the same as those of A^T .

L 8.3.6 (Determinant and Trace via EW):

- Let $A \in \mathbb{R}^{n \times n}$ and let $\lambda_1, \dots, \lambda_n$ be its eigenvalues as they appear in the characteristic polynomial. Then

$$\det(A) = \prod_{i=1}^n \lambda_i, \quad \text{Tr}(A) = \sum_{i=1}^n \lambda_i.$$

L 8.3.7 (Cyclic invariance of the trace):

- For $A, B, C \in \mathbb{R}^{n \times n}$:

$$\text{Tr}(AB) = \text{Tr}(BA), \text{ and } \text{Tr}(ABC) = \text{Tr}(BCA) = \text{Tr}(CAB).$$

9 Diagonalizable Matrices, Singular Value Decomposition

9.1 Diagonalization

T 9.1.1 (Diagonalization Theorem, ability changing basis):

- $A = V\Lambda V^{-1}$, where V 's columns are its eigenvectors and Λ is a diagonal matrix with $\Lambda_{ii} = \lambda_i$ and all other entries 0. $A \in \mathbb{R}^{n \times n}$ and has to have a complete set of real eigenvectors (eigenbasis). Equivalently, $\Lambda = V^{-1}AV$, since V is invertible.

$$\text{Std. coord.} \xrightarrow{V^{-1}} \text{EV. coord.} \xrightarrow{\Lambda} \text{EV. coord.} \xrightarrow{V} \text{Std. coord.}$$

D 9.1.2 (Diagonalizable matrix):

- A matrix $A \in \mathbb{R}^{n \times n}$ is called *diagonalizable* if there exists an invertible matrix V such that $V^{-1}AV = \Lambda$, where Λ is a diagonal matrix.

D 9.1.3 (Complete set of EV):

- If we can find eigenvectors forming a basis of \mathbb{R}^n for A , we say that A has a *complete set of real eigenvectors*.

P 9.1.6 (Projection and EW/EV):

- Let P be a projection matrix onto a subspace $U \subset \mathbb{R}^n$. Then P has two eigenvalues, 0 and 1, and a complete set of real eigenvectors.

D 9.1.7 (Similar matrices):

- Matrices $A \in \mathbb{R}^{n \times n}$ and $B \in \mathbb{R}^{n \times n}$ are called *similar* if there exists an invertible matrix S such that $B = S^{-1}AS$. **P 9.1.8:** Similar matrices have the same eigenvalues.

D 9.1.10 (Geometric multiplicity):

- Let $A \in \mathbb{R}^{n \times n}$ and let λ be an eigenvalue of A . Then $\dim \mathcal{N}(A - \lambda I)$ is called the *geometric multiplicity* of λ .

L 9.1.11 (Complete set of real EV):

- A matrix has a complete set of real eigenvectors if and only if all its eigenvalues are real and the geometric multiplicities equal the algebraic multiplicities for all eigenvalues.

9.2 Symmetric Matrices, Spectral Theorem

T 9.2.1 (Spectral Theorem):

- Any symmetric matrix $A \in \mathbb{R}^{n \times n}$ has n real eigenvalues and an orthonormal basis of \mathbb{R}^n consisting of eigenvectors of A .

C 9.2.2 (Eigendecomposition):

- For any symmetric matrix $A \in \mathbb{R}^{n \times n}$, there exists an orthogonal matrix $V \in \mathbb{R}^{n \times n}$ (whose columns are eigenvectors of A) such that $A = V\Lambda V^T$, where $\Lambda \in \mathbb{R}^{n \times n}$ is diagonal with diagonal entries equal to the eigenvalues of A , and $V^T V = I$. This decomposition is called the *eigendecomposition*.

C 9.2.4 (Rank of real symmetric matrix):

- If A is a real symmetric matrix, then $\text{rank}(A)$ is the number of nonzero eigenvalues of A (counting repetitions).
- For a general $n \times n$ matrix, $\text{rank}(A) = n - \dim \mathcal{N}(A)$, so the geometric multiplicity of the eigenvalue $\lambda = 0$ equals $\dim \mathcal{N}(A)$.

P 9.2.6 (Rank-One Spectral Decomposition):

- Let $A \in \mathbb{R}^{n \times n}$ be symmetric, and let v_1, \dots, v_n be an orthonormal basis of eigenvectors of A (the columns of V), with associated eigenvalues $\lambda_1, \dots, \lambda_n$. Then $A = \sum_{k=1}^n \lambda_k v_k v_k^T$.

A *real symmetric matrix* is a weighted sum of orthogonal projections onto its eigenvector directions, with weights given by the eigenvalues.

L 9.2.7 (Orthogonality of EV):

- Let $A \in \mathbb{R}^{n \times n}$ be symmetric and let $\lambda_1 \neq \lambda_2 \in \mathbb{R}$ be two distinct eigenvalues of A with corresponding eigenvectors v_1, v_2 . Then v_1 and v_2 are orthogonal.

L 9.2.8 (Symmetric matrix has real EW):

- A symmetric matrix $A \in \mathbb{R}^{n \times n}$ has only real eigenvalues: $\lambda \in \mathbb{C} \Rightarrow \lambda \in \mathbb{R}$. Indeed, if $Av = \lambda v$:
 $\lambda \|v\|^2 = \bar{\lambda} v^* v = (\lambda v)^* v = (Av)^* v = v^* A^* v = v^* Av = v^* \lambda v = \lambda \|v\|^2 \Rightarrow$ every symmetric matrix $A \in \mathbb{R}^{n \times n}$ has a real eigenvalue. (C 9.2.9)

P 9.2.10 (Rayleigh Quotient):

- $A \in \mathbb{R}^{n \times n}$ is symmetric. For $x \in \mathbb{R}^n \setminus \{0\}$, the Rayleigh quotient $R(x) = \frac{x^T Ax}{x^T x}$.

The minimum of $R = R(v_{\min}) = \lambda_{\min}$, and the maximum $R(v_{\max}) = \lambda_{\max}$. Here $\lambda_{\max}/\lambda_{\min}$ are the largest/smallest eigenvalues of A , and v_{\max}/v_{\min} their associated eigenvectors.

D 9.2.11 (PSD and PD matrices):

- $A = A^\top$
- $A \succeq 0$ (PSD) $\Leftrightarrow \lambda_i(A) \geq 0$
- $A \succ 0$ (PD) $\Leftrightarrow \lambda_i(A) > 0$.

P 9.2.12 (Positivity of the quadratic form):

- Let $A \in \mathbb{R}^{n \times n}$ be symmetric. Then $A \succeq 0 \Leftrightarrow x^\top Ax \geq 0 \quad \forall x \in \mathbb{R}^n$, and $A \succ 0 \Leftrightarrow x^\top Ax > 0 \quad \forall x \neq 0$.

D 9.2.13 (Gram Matrix):

- Given vectors $v_1, \dots, v_n \in \mathbb{R}^m$, their Gram matrix is $G \in \mathbb{R}^{n \times n}$ defined by $G_{ij} = v_i^\top v_j$. If $V = [v_1 \dots v_n] \in \mathbb{R}^{m \times n}$, then $G = V^\top V$.
- If $A = [a_1 \dots a_n] \in \mathbb{R}^{m \times n}$, one also calls AA^\top a Gram matrix; note that $AA^\top = \sum_{i=1}^n a_i a_i^\top$. It is $m \times m$ matrix.

P 9.2.15 (Same EV of transposed matrices):

- For a real matrix $A \in \mathbb{R}^{m \times n}$, the non-zero eigenvalues of $A^\top A \in \mathbb{R}^{n \times n}$ and $AA^\top \in \mathbb{R}^{m \times m}$ are the same. Also both are symmetric and PSD.

P 9.2.16 (Cholesky Decomposition):

- Every symmetric PSD matrix M is a Gram matrix of upper-triangular matrix C : $M = C^\top C$.

9.3 Singular Value Decomposition

D 9.3.1 (Singular Value Decomposition):

- Let $A \in \mathbb{R}^{m \times n}$. There exist orthogonal matrices $U \in \mathbb{R}^{m \times m}$ and $V \in \mathbb{R}^{n \times n}$ and a diagonal matrix $\Sigma \in \mathbb{R}^{m \times n}$ with nonnegative diagonal entries $\sigma_1 \geq \dots \geq \sigma_{\min(m,n)}$ such that

$$A = U\Sigma V^\top.$$

The columns of U and V are called the left and right singular vectors of A , and the diagonal entries of Σ are the singular values of A .

R 9.3.2 (Compact form of SVD):

- If $\text{rank}(A) = r$, then the SVD can be written as

$$A = U_r \Sigma_r V_r^\top,$$

where $U_r \in \mathbb{R}^{m \times r}$ and $V_r \in \mathbb{R}^{n \times r}$ have orthonormal columns, and $\Sigma_r = \text{diag}(\sigma_1, \dots, \sigma_r)$. This representation stores $r(m+n+1)$ real numbers instead of mn . For small r , this yields substantial savings and motivates low-rank approximations.

T 9.3.3 (Every matrix has SVD):

- Every matrix $A \in \mathbb{R}^{m \times n}$ has SVD: $A = U\Sigma V^\top$. Equivalently, every linear transformation is diagonal in orthonormal bases of singular vectors.

P 9.3.4 (SVD as a sum of rank-one matrices):

- Let $A \in \mathbb{R}^{m \times n}$ have rank r , with singular values $\sigma_1, \dots, \sigma_r$ and corresponding singular vectors u_1, \dots, u_r and v_1, \dots, v_r . Then

$$A = \sum_{k=1}^r \sigma_k u_k v_k^\top.$$

Main idea: We can write any rank- r matrix $A \in \mathbb{R}^{m \times n}$ as a sum of r rank-1 matrices.

Algorithms

Gaussian Elimination.

Given $Ax = b$, form the augmented matrix $[A | b]$ and apply elementary row operations to reach row echelon form (REF): pivot \rightarrow swap \rightarrow eliminate below \rightarrow repeat. If a row $(0 \dots 0 | c)$ with $c \neq 0$ appears, the system is inconsistent; otherwise solve by back-substitution.

$$\left[\begin{array}{cc|c} 1 & 1 & 3 \\ 2 & 1 & 4 \end{array} \right] \xrightarrow{R_2 - 2R_1} \left[\begin{array}{cc|c} 1 & 1 & 3 \\ 0 & -1 & -2 \end{array} \right] \Rightarrow (x, y) = (1, 2).$$

Gauss-Jordan Elimination.

Starting from $[A | b]$, apply Gaussian elimination, then normalize each pivot to 1 and eliminate all other entries in the pivot columns. The resulting reduced row echelon form (RREF) gives the solution directly. Solve:

$$\left\{ \begin{array}{l} x + y = 3, \\ 2x + y = 4. \end{array} \right. \iff \left[\begin{array}{cc|c} 1 & 1 & 3 \\ 2 & 1 & 4 \end{array} \right]$$

Row-reduce to RREF:

$$\left[\begin{array}{cc|c} 1 & 1 & 3 \\ 2 & 1 & 4 \end{array} \right] \xrightarrow{R_2 - R_2 - 2R_1} \left[\begin{array}{cc|c} 1 & 1 & 3 \\ 0 & -1 & -2 \end{array} \right] \xrightarrow{R_2 \leftarrow -R_2} \left[\begin{array}{cc|c} 1 & 1 & 3 \\ 0 & 1 & 2 \end{array} \right] \xrightarrow{R_1 \leftarrow R_1 - R_2} \left[\begin{array}{cc|c} 1 & 0 & 1 \\ 0 & 1 & 2 \end{array} \right].$$

$x = 1, \quad y = 2.$

Inverse via Gauss-Jordan.

To compute A^{-1} , form the augmented matrix $[A | I]$ and apply Gauss-Jordan elimination. If

$$[A | I] \longrightarrow [I | B],$$

then $B = A^{-1}$. If I cannot be obtained on the left, A is not invertible.

$$[A | I] \xrightarrow{R_2 \leftarrow R_2 - 3R_1} \left[\begin{array}{cc|cc} 1 & 2 & 1 & 0 \\ 3 & 4 & 0 & 1 \end{array} \right] \xrightarrow{R_2 \leftarrow -\frac{1}{2}R_2} \left[\begin{array}{cc|cc} 1 & 2 & 1 & 0 \\ 0 & 1 & \frac{3}{2} & -\frac{1}{2} \end{array} \right] \xrightarrow{R_1 \leftarrow R_1 - 2R_2} \left[\begin{array}{cc|cc} 1 & 0 & -2 & 1 \\ 0 & 1 & \frac{3}{2} & -\frac{1}{2} \end{array} \right].$$

Fitting a line with least squares.

$$\hat{\alpha} = \arg \min_{\alpha \in \mathbb{R}^2} \|A\alpha - b\|^2 = (A^T A)^{-1} A^T b, \quad A = \begin{pmatrix} 1 & t_1 \\ \vdots & \vdots \\ 1 & t_m \end{pmatrix}$$

$$A = \begin{pmatrix} 1 & 0 \\ 1 & 1 \\ 1 & 2 \end{pmatrix}, b = \begin{pmatrix} 1 \\ 2 \\ 2 \end{pmatrix}, \hat{\alpha} = (A^T A)^{-1} A^T b = \begin{pmatrix} \frac{7}{6} \\ \frac{1}{2} \end{pmatrix}, \hat{b}(t) = \frac{7}{6} + \frac{1}{2}t.$$

Forming orthonormal basis via Gram-Schmidt.

Gram-Schmidt used to construct orthonormal bases.

We have linearly independent vectors a_1, \dots, a_n that span a subspace S , then we can construct their orthonormal basis q_1, \dots, q_n by:

- $q_1 = \frac{a_1}{\|a_1\|}$.
- For $k = 2, \dots, n$ do $q'_k = a_k - \sum_{i=1}^{k-1} (a_k^\top q_i) q_i$,
- normalize $q_k = \frac{q'_k}{\|q'_k\|}$.

Solving Linear Recurrences via Matrix Diagonalization

We are given the recurrence relation

$$a_n = 5a_{n-1} - 6a_{n-2}, \quad \text{for } n \geq 2.$$

Using the given formula, we can derive a matrix M such that

$$\begin{pmatrix} a_{n+1} \\ a_n \end{pmatrix} = \begin{pmatrix} 5 & -6 \\ 1 & 0 \end{pmatrix} \begin{pmatrix} a_{n-1} \\ a_{n-2} \end{pmatrix}, \quad M = \begin{pmatrix} 5 & -6 \\ 1 & 0 \end{pmatrix}, \quad \mathbf{g}_n = \begin{pmatrix} a_{n+1} \\ a_n \end{pmatrix},$$

With initial vector $\mathbf{g}_0 = \begin{pmatrix} 2 \\ 0 \end{pmatrix}$, we have $\mathbf{g}_n = M^n \mathbf{g}_0$.

Eigenvalues of M

We compute $\det(M - \lambda I) = (5 - \lambda)(-\lambda) + 6 = \lambda^2 - 5\lambda + 6$. Solving, $\lambda^2 - 5\lambda + 6 = 0 \Rightarrow (\lambda - 3)(\lambda - 2) = 0$.

Hence, $\lambda_1 = 3, \quad \lambda_2 = 2$.

Eigenvectors

For $\lambda = 3$:

$$(M - 3I) = \begin{pmatrix} 2 & -6 \\ 1 & -3 \end{pmatrix}.$$

Solving $(M - 3I)\mathbf{v} = 0$ gives $2x - 6y = 0 \Rightarrow x = 3y$, so $\text{EV } \mathbf{v}_1 = \begin{pmatrix} 3 \\ 1 \end{pmatrix}$.

For $\lambda = 2$:

$$(M - 2I) = \begin{pmatrix} 3 & -6 \\ 1 & -2 \end{pmatrix}.$$

Solving $(M - 2I)\mathbf{v} = 0$ gives $x - 2y = 0 \Rightarrow x = 2y$, so $\text{EV } \mathbf{v}_2 = \begin{pmatrix} 2 \\ 1 \end{pmatrix}$.

Closed Form

Since \mathbf{v}_1 and \mathbf{v}_2 are linearly independent, we can write

$$\mathbf{g}_0 = \alpha_1 \mathbf{v}_1 + \alpha_2 \mathbf{v}_2.$$

That is,

$$\begin{pmatrix} 2 \\ 0 \end{pmatrix} = \alpha_1 \begin{pmatrix} 3 \\ 1 \end{pmatrix} + \alpha_2 \begin{pmatrix} 2 \\ 1 \end{pmatrix}.$$

Solving,

$$\alpha_1 = 2, \quad \alpha_2 = -2.$$

Therefore, $\mathbf{g}_n = \alpha_1 3^n \mathbf{v}_1 + \alpha_2 2^n \mathbf{v}_2 = 2 \cdot 3^n \begin{pmatrix} 3 \\ 1 \end{pmatrix} - 2^{n+1} \begin{pmatrix} 2 \\ 1 \end{pmatrix}$.

Thus, $a_n = 2 \cdot 3^n - 2^{n+1}$.

Notes from correction

Notes and ideas

Pythagorean theorem:

- If two vectors are orthogonal, then their squared lengths add:

$$\|\mathbf{x} + \mathbf{y}\|^2 = \mathbf{x}^\top \mathbf{x} + 2\overbrace{\mathbf{x}^\top \mathbf{y}}^{=0} + \mathbf{y}^\top \mathbf{y} = \|\mathbf{x}\|^2 + \|\mathbf{y}\|^2$$

Linearity Proof:

- To prove linearity insert arbitrary $\mathbf{v}, \mathbf{w} \in \mathbb{R}$ and $\alpha \in \mathbb{R}$ to $f(\mathbf{v} + \alpha\mathbf{w})$

Non-trivial nullspace and solutions:

- When $m < n$ then there exists a nontrivial null space, which prevents uniqueness of a solution. Let $A \in \mathbb{R}^{m \times n}$, then there exists $\mathbf{x} \neq 0$ but $A\mathbf{x} = 0$:
 $\text{rank}(A) \leq m < n \Rightarrow \dim(N(A)) = n - \text{rank}(A)$

Linear dependence:

- The vectors v_1, v_2, v_3 are *linearly dependent* if there exist scalars a_1, a_2, a_3 , not all zero, such that $a_1v_1 + a_2v_2 + a_3v_3 = 0$.

Invertible matrix properties:

- A is invertible
 $\Leftrightarrow A\mathbf{x} = \mathbf{b}$ has a unique solution for every \mathbf{b}
 $\Leftrightarrow N(A) = \{0\}$
 $\Leftrightarrow \text{rank}(A) = n$
 \Leftrightarrow columns of A are lin. independent

Homogenous system solutions:

- A homogenous system $A\mathbf{x} = 0$ has either one solution $\mathbf{x} = 0$ or infinitely many solutions: all scaled $\alpha\mathbf{x}$.

Square a sum:

$$\sum_{i=1}^n \lambda_i^2 = (\sum_{i=1}^n \lambda_i)(\sum_{j=1}^n \lambda_j) = \sum_{i=1}^n \sum_{j=1}^n \lambda_i \lambda_j = \sum_{i=1}^n \lambda_i^2 + \sum_{i \neq j} \lambda_i \lambda_j$$

That is why $\text{Tr}(A^2) \leq \text{Tr}(A)^2$. When all eigenvalues are zero or at most one is not zero, then this becomes equal.

Dot product concept:

- Dot product tells you how much two vectors point in the same direction.
 - $u^\top w < 0$: pointing opposite to w
 - $u^\top w = 0$: perpendicular to w
 - $u^\top w > 0$: pointing partly in the same direction as w

Prove the dimension of a subspace:

- Write the general matrix, apply the constraints, deconstruct into linear combination of independent variables, prove that they span the space, show that they are linearly independent.

Singular Values inversion:

- Since $\sigma_1 \geq \dots \geq \sigma_n > 0$, it follows that $\frac{1}{\sigma_1} \leq \dots \leq \frac{1}{\sigma_n}$, and therefore, when ordered decreasingly, the singular values of A^{-1} are $\frac{1}{\sigma_n}, \dots, \frac{1}{\sigma_1}$.

Invertible matrix singular values:

- Invertible matrix singular values are strictly positive.

Creative Cauchy-Schwarz Inequality:

- To prove

$$\sum_{i=1}^n \frac{a_i^2}{b_i} \geq \frac{(\sum_{i=1}^n a_i)^2}{\sum_{i=1}^n b_i},$$

apply the Cauchy-Schwarz inequality to the vectors

$$\left(\frac{a_1}{\sqrt{b_1}}, \dots, \frac{a_n}{\sqrt{b_n}} \right) \quad \text{and} \quad \left(\sqrt{b_1}, \dots, \sqrt{b_n} \right).$$

Their dot product is

$$\sum_{i=1}^n a_i,$$

and their squared norms are

$$\sum_{i=1}^n \frac{a_i^2}{b_i} \quad \text{and} \quad \sum_{i=1}^n b_i.$$

By Cauchy-Schwarz,

$$\left(\sum_{i=1}^n a_i \right)^2 \leq \left(\sum_{i=1}^n \frac{a_i^2}{b_i} \right) \left(\sum_{i=1}^n b_i \right),$$

which rearranges by division with a sum of b to the desired inequality.

Why $\text{Tr}(A) = \sum_{i=1}^n \lambda_i$:

- Eigenvalues are the roots of the characteristic polynomial.
Let $A \in \mathbb{R}^{n \times n}$ with eigenvalues $\lambda_1, \dots, \lambda_n$. The characteristic polynomial is

$$\chi_A(z) = (-1)^n \det(A - zI) = \det(zI - A) = \prod_{i=1}^n (z - \lambda_i).$$

Determinant. Evaluating at $z = 0$ gives

$$\det(A) = \prod_{i=1}^n \lambda_i.$$

Trace. Expanding $\chi_A(z)$,

$$\prod_{i=1}^n (z - \lambda_i) = z^n - \left(\sum_{i=1}^n \lambda_i \right) z^{n-1} + \dots$$

Hence the coefficient of z^{n-1} is $-\sum_{i=1}^n \lambda_i$.

On the other hand, using the determinant expansion,

$$\det(zI - A) = (z - A_{11})(z - A_{22}) \cdots (z - A_{nn}) + \dots,$$

where the remaining terms correspond to non-identity permutations and have degree at most z^{n-2} . Therefore, the coefficient of z^{n-1} is

$$-\sum_{i=1}^n A_{ii} = -\text{Tr}(A).$$

Comparing coefficients yields

$$\text{Tr}(A) = \sum_{i=1}^n \lambda_i.$$

9.4 Quiz

Determining when matrix returns to identity:

- If $A^m = I$ and $A^n = I$, then

$$A^{\gcd(m,n)} = I.$$

Proof sketch to template:

Let $d = \gcd(m, n)$. Then there exist integers x, y with $d = xm + yn$ (Bézout). Assuming A is invertible (true in any group; for matrices this means $A \in GL$),

$$A^d = A^{xm+yn} = (A^m)^x (A^n)^y = I^x I^y = I.$$

When can you conclude $A = I$? You can conclude $A = I$ if $\gcd(m, n) = 1$, because then $A^1 = A = I$. Otherwise, you can only conclude that the order of A divides $\gcd(m, n)$ (i.e., A is a root of unity of that exponent).

Pairwise linear independence:

- Pairwise independence is weaker than (joint) linear independence. \Rightarrow Linear independence is a global property: checking vectors two at a time is not enough. Collectively, they might still fail independence.
Geometrically in \mathbb{R}^2 : you can have infinitely many vectors that are pairwise non-collinear, but at most two vectors can be linearly independent.

Linear Dependence Criterion via Dimension:

- In a vector space of dimension n , any set of more than n vectors is linearly dependent. More formally:
- Let V be a vector space with $\dim V = n$. Then any set of $n+1$ (or more) vectors in V is linearly dependent.

Complex expression and geometric Interpretation:

- Using $z\bar{z} = |z|^2$, the condition reduces to $x^2 + y^2 = 1$, which describes the unit circle.

SVD validity check:

- To verify whether a proposed factorization $A = U\Sigma V^\top$ is a valid SVD, it suffices to check the following:

- Orthogonality:** U (and V) has orthonormal columns, i.e. $U^\top U = I$ and $V^\top V = I$;
- Singular values:** Σ is diagonal with non-negative entries;
- Dimensions:** if $A \in \mathbb{R}^{m \times n}$, then $\Sigma \in \mathbb{R}^{m \times n}$.

Invertible matrix and EW:

- A matrix is invertible iff 0 is not an eigenvalue.
- $A = A^\top \Rightarrow A$ has real eigenvalues $\Rightarrow \lambda + i \neq 0 \Rightarrow \det(A + iI) \neq 0 \Rightarrow A + iI$ is invertible