. SYMMETRIC

$$\omega \in \mathbb{R}$$
 $\omega = \omega - \omega^{-1} = 1$
 $\omega \neq 0$
 $\omega^{-1} = \frac{1}{2}$
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 $\omega = \omega - \omega^{-1} = 1$

DEFINITION: A EIR A IS CACCED INVERTIBLE IF IT EXISTS CEIR SUCH THAT CA=AC=IN

OBSERVATION: IF IT EXISTS, THE MATRIX C IS UNIQUE

N=2
$$A = \begin{bmatrix} \omega_{11} & \omega_{12} \\ \omega_{21} & \omega_{22} \end{bmatrix}$$
 THEN A is invertible, its inverse being $A = \begin{bmatrix} 1 \\ \omega_{11} & \omega_{22} - \omega_{12} & \omega_{21} \end{bmatrix}$ $\begin{bmatrix} \omega_{22} & -\omega_{12} \\ -\omega_{21} & \omega_{21} & \omega_{21} \end{bmatrix}$ $\begin{bmatrix} \omega_{22} & -\omega_{12} \\ -\omega_{21} & \omega_{21} & \omega_{21} \end{bmatrix}$

$$A^{-1}A = I_{N}$$

$$A^{-1}A = \frac{1}{(\omega_{11}\omega_{12} - \omega_{12}\omega_{21})} \begin{bmatrix} \omega_{22} - \omega_{12} \\ -\omega_{21} - \omega_{11} \end{bmatrix} \begin{bmatrix} \omega_{11} - \omega_{12} \\ \omega_{21} - \omega_{22} \end{bmatrix} = \frac{1}{(\omega_{11}\omega_{12} - \omega_{12}\omega_{21})} \begin{bmatrix} \omega_{11} - \omega_{12} \\ -\omega_{21}\omega_{11} + \omega_{11}\omega_{21} \\ -\omega_{21}\omega_{11} + \omega_{11}\omega_{21} \end{bmatrix} = \frac{1}{(\omega_{11}\omega_{12} - \omega_{12}\omega_{21})} \begin{bmatrix} \omega_{11} - \omega_{12} \\ -\omega_{21}\omega_{11} + \omega_{11}\omega_{21} \\ -\omega_{21}\omega_{11} + \omega_{11}\omega_{21} \end{bmatrix}$$

THEOREM: IF AE IR" IS AN INVERTIBLE MATRIX, THEN THE CINERR SYSTEM AZ = b

(GEIR", ZEIR") ALWRYS HAS ONE UNIQUE SOCUTION Z FOR ANY GEIR"

Ax=6 x=A⁻¹b is a socution check
$$A(A^{-1}b) \stackrel{?}{=} \stackrel{?}{=}$$

THEOREM

- O AEIR INVERTIBLE. THEN ALSO A 1 IS INVERTIBLE AND ITS INVERSE IS A
- @ A,B elRnxh inventible. THEN AB IS ALSO INVERTIBLE, WITH (AB) = A-1B-1
- 3 A EIR INVERTIBLE. THEN AT IS INVERTIBLE, WITH (AT) = (A-1) T
- $AA^{-1} = A^{-1}A = I_N$ $A^{-1} = A^{-1}A = I_N$ $A^{-1} = A^{-1}C = I_N ? Ce(R^{N\times N})$ C = A
- (AB) = (AB) C = IN C = B-1A-1 C (AB) = (B-1A-1)(AB) = B-1AB = B-1B = B-1B = IN

OBSERVATION A1, A2, .. Ap EIR NXN ALL INVERTIBLE

THEN (A1A2A3 ... Ap) EIR NXN IS INVERTIBLE, AND THE INVERSE IS (A-1 ... A-1 A-1 A-1 A-1)

BY APPLYING AN ELEMENTARY ROW OPERATION TO IN

SWITCH THE FIRST AND THIRD ROWS
$$\rightarrow E_1 = \begin{pmatrix} 0 & 0 & 1 \\ 0 & 1 & 0 \\ 1 & 0 & 0 \end{pmatrix}$$

N=3 (100)

ROW OPERATION

MULTIPLY THE SECOND ROW BY 3 $\rightarrow E_2 = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 3 & 0 \\ 0 & 0 & 1 \end{pmatrix}$

SUBTRACT THE FIRST ROW MULTIPLIED $\rightarrow E_3 = \begin{pmatrix} 1 & 0 & 0 \\ -2 & 1 & 0 \\ 0 & 0 & 1 \end{pmatrix}$

BY 2 TO THE SECOND ROW

$$A = \begin{bmatrix} \frac{1}{2} & \frac{4}{5} \\ \frac{2}{3} & \frac{6}{6} \end{bmatrix} \in \mathbb{R}^{3\times2} \quad E_{1}A = \begin{bmatrix} 0 & 0 & 1 \\ 0 & 1 & 0 \\ 1 & 0 & 0 \end{bmatrix} \begin{bmatrix} 1 & 4 \\ 2 & 5 \\ 3 & 6 \end{bmatrix} = \begin{bmatrix} 3 & 6 \\ 2 & 5 \\ 1 & 4 \end{bmatrix}$$

$$E_{2}A = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 3 & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 4 \\ 2 & 5 \\ 3 & 6 \end{bmatrix} = \begin{bmatrix} 1 & 4 \\ 6 & 15 \\ 3 & 6 \end{bmatrix}$$

$$E_{3}A = \begin{bmatrix} 1 & 0 & 0 \\ -2 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 4 \\ 2 & 5 \\ 3 & 6 \end{bmatrix} = \begin{bmatrix} 1 & 4 \\ 0 & -3 \\ 3 & 6 \end{bmatrix}$$

- OBSERVATION: (IMPORTANT!) APPLYING AN ELEMENTARY ROW OPERATION TO A MATRIX AE IR MAN IS THE ELEMENTARY EQUIVALENT TO CALCULATE THE PRODUCT EA, WHERE EEIR MAN IS THE ELEMENTARY MATRIX ASSOCIATED TO THAT SAME ROW OPERATION (THAT IS, THE MATRIX OBTAINED BY APPLYING THE SAME ROW OPERATION TO IM)
 - ALL ELEMENTARY ROW OPERATION ARE REVERSIBLE THERFORE ALL MATRIXES ARE INVERTIBLE

THE INVERSE MATRIX
IS THE ELEMENTARY
MATRIX ASSOCIATED TO
THE REVERSE ROW
OPERATION

$$E_2 = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 3 & 0 \\ 0 & 0 & 1 \end{pmatrix} \qquad \begin{array}{l} \bullet \text{ DIVIDE THE SECOND ROW BY 3} = \text{ MULTIPLY THE 2}^{NO} \text{ Row By 43} \longrightarrow \begin{pmatrix} 1 & 0 & 0 \\ 0 & 0 & 1 \end{pmatrix} = E$$

$$\begin{pmatrix} 1 & 0 & 0 \\ 0 & 0 & 1 \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 0 & 1 \end{pmatrix}$$

$$EE_{2} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1/3 & 0 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} 1 & 0 & 0 \\ 0 & 3 & 0 \\ 0 & 0 & 1 \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{pmatrix}$$

$$\begin{array}{c} \varepsilon^{-1} & 0 & 0 & 1 \\ 1 & 0 & 1 & 0 \\ 1 & 0 & 0 \end{array}$$

$$E_3^{-1} = \begin{pmatrix} 1 & 0 & 0 \\ 2 & 1 & 0 \\ 2 & 0 & 1 \end{pmatrix}$$

A EIR ECHECON FORM AEIR +x4

IF THE MATRIX IS SQUARED AND YOU HUST HAVE A PIVOUT POSITION THERE IS ONLY ONE SOUTION

THEOREM A EIR "X" (SQUARE) THE FOLLOWING STATEMENTS ARE EQUIVALENT

- · A HAS A FIVOT POSITION IN EVERY ROW
- A HAS A FIVOT POSITION IN EVERY COLUMN
- THE PIVOT POSITION ARE ALL ON THE DINGONAL
- THERE ARE EXACTLY N PIVOT POSITION

THEOREM AEIR IS INVERTIBLE IF AND ONLY IF IS ROW EQUALENT TO THE IDENTITY MATRIX I_n .

THE INVERSE MATRIX A^{-1} can be computed by applying to I_n the same row operations that where applied in order to transform A into I_n

LETS EXPLAIN WHY THIS IS TRUE ("PROOF")

WHY IF A IS INVERTIBLE THEN IT MUST BE ROW EQUIVALENT TO IN?

TODAY A IS INVERTIBLE => THE SYSTEM AX=6 ACWAYS HAVE A SOCUTION YE GIR > THE MATRIX A HAS A PIVOT POSITION IN EVERY ROW

WHY A MATRIX THAT IS ROW EQUIVALENT TO THE IDENTITY MUST BE INVERTIBLE?

ELEMENTARY

ROW OPERATION

CP...E3E2E1A

PERATION

ELEMENTARY MATRIX

A IS INVERTIBLE AND A = Ep. E3E2E1=Ep. E3E2E1 IN

A E IR (SQUARE) THE FOCCOWING STMEMENTS ARE EQUIVACENT

- A IS INVERTIBLE
- · A IS ROW EQUIVACENT TO IN
- A MPS N PIVOT POSITIONS (ALL ON THE DIRECHAL)
- THE SYSTEM AX = 0 HAS ONLY THE TRIVIAL SOLUTION
- THE EQUATION AZE HAS (AT LEAST) ONE SOCUTION FOR EACH & EIRN
- THE COLUMNS OF A SPAN ALL IRN
- * THERE IS CEIRNXN SUCH THAT CA=IN
- THERE IS CE IR NEW SUCH THAT AC=IN
- · AT IS AN INVERTIBLE MATRIX