Things to Remember

- a_{ij} is the ith row and jth column of A.
- $\pm 0.d_1 d_2 \dots d_k \times 10^n$ is the decimal floating point representation of a number.
- Chopping is cheaper than rounding.

Error

- Error: $p - \hat{p}$
- Abs. Err: $|p - \hat{p}|$
- Rel. Err: $\frac{|p-\hat{p}|}{p}$ (for accuracy)

Significant Digits

An aprxmtn $\hat{p}$ has t significant digits if: $\dfrac{|p-\hat{p}|}{|p|} \leq 5 \times 10^{-t}$

Catastrophic Cancellation (Roundoff)

When subtracting nearly equal numbers, the relative error is large, and you lose a lot of significant digits (and accuracy).

How to Reduce Errors

- Reformat the formula to avoid roundoff
- Reduce num. of ops (avoid rounding)
  - Nested Arithmetic: Rewrite polynomials to reduce operations
    $x^3 - 6.1x^2 + 3.2x \to ((x-6.1)x + 3.2)x$

Algorithms and Convergence

- Stable $\to$ errors grow linearly
- Unstable $\to$ errors grow exponentially

Rate of Convergence

- For sequences, if $\alpha_n \to \alpha$ and $|\alpha_n - \alpha| \leq k\beta_n, \quad \beta_n \to 0$ then α_n is $\mathcal{O}(\beta_n)$
- For functions, if $\lim_{h\to 0} f(h) = L$ and $|f(h)| \leq kh^p$ then $f(h) = L + \mathcal{O}(h^p)$

Taylor Series

$$f(x) = \sum_{n=0}^{\infty} \frac{f^{(n)}(a)}{n!}(x-a)^n$$

$e^x = 1 + x + \frac{x^2}{2!} + \frac{x^3}{3!} + \cdots$

$\sin x = x - \frac{x^3}{3!} + \frac{x^5}{5!}$ $\qquad \cos x = 1 - \frac{x^2}{2!} + \frac{x^4}{4!}$

$\ln(1+x) = x - \frac{x^2}{2} + \frac{x^3}{3} + \cdots$

$(1+x)^{-p} = 1 - px + \frac{p(p+1)x^2}{2} - \frac{p(p+1)(p+2)x^3}{3!}$ **The Error Term** is the $(n+1)^{th}$ term.

Root Finding

- Find p such that $f(p) = 0$.

Generic Stopping Criterion

1. $\frac{|p_n - p_{n-1}|}{|p_n|} \leq \mathcal{E}; p_n \neq 0$: relative error
2. $|f(p_n)|| \leq \mathcal{E}$
   - Ensures small $f(p_n)$
   - p_n may differ significantly from p
3. Have a fixed number of iterations
4. (bisection) $\frac{b_n - a_n}{2} \leq \mathcal{E}$ **or** $|p_n - p_{n-1}| < \mathcal{E}$
   - Ensures p_n is within $\mathcal{E}$ of p
   - Does not ensure small $f(p_n)$

Bisection Method:

- **Conditions:** $f(x) \in C[a,b]$;
  $f(a)$ and $f(b)$ have opposite signs.
- **Midpoint:** $x = \frac{a+b}{2}$
- **Procedure:** Binary search for the root.
- **Error:** Guaranteed quadratic convergence
- **Error Formula:** $\frac{b-a}{2^n}$

Newton's Method

- Faster than bisection, quadratic. We follow the tangent line at p_{n-1} to its $x-$intercept.
- Requires $f'(p)$ to exist.
- Requires $f''(p)$ for quadratic convergence.
  1. Start with initial guess p_0 and p_1
  2. $p_n = p_{n-1} - \dfrac{f(p_{n-1})(p_{n-1} - p_{n-2})}{f'(p_{n-1})f(p_{n-2})}$

Secant Method

- Does not require $f'(p)$ to exist.
- Faster than Bisection, order $\phi \approx 1.618$
  1. Start with initial guess p_0 and p_1
  2. $p_n = p_{n-1} - \dfrac{f(p_{n-1})(p_{n-1}p_{n-2})}{f(p_{n-1})f(p_{n-2})}$

False Position Method

- Linear or sublinear guaranteed convergence.
- Convergence can stall if the function has poor behaviour near the root.
  1. Start with initial guess p_0 and p_1
  2. $p_n = p_{n-1} f(p_{n-1}) \cdot \dfrac{p_{n-1} - p_{n-2}}{f(p_{n-1}) - f(p_{n-2})}$

Fixed Points

1. Start with initial guess p_0
2. Generate a sequence $p_n = g(p_{n-1})$
3. Stop when $|p_n - p_{n-1}| < \mathcal{E}$

- A fixed point of f is a point p such that $f(p) = p$.
- Converges if:
  1. $g : [a,b] \to [a,b]$ is continuous
  2. $\forall x \in [a,b] : |g'(x)| \leq k < 1$
  3. $f(x) = 0$ can be rewritten as $g(x) = x$
- **Error**: $\mathcal{O}(q^n)$, for some q, faster when q is small

Norms

Vector Norms

- $l_1 : \|x\|_1 = \sum x_i$
- $l_2 : \|x\|_2 = \sqrt{x_1^2 + \cdots + x_n^2}$ (Euclidean)
- $l_\infty : \|x\|_\infty = \max\{|x_1|, \cdots, |x_n|\}$ (∞)

Properties

- Scalability: $\|\alpha x\| = |\alpha|\|x\|$
- Triangle Inequality: $\|x+y\| \leq \|x\| + \|y\|$

Vector Distances

- l_α distance: $\|x-y\|_\alpha$

Matrix Norms

- The Natural Norm $\|\cdot\|_*$ for $A, B \in \mathbb{R}^{n\times n}; \alpha \in \mathbb{R}$ is defined as a function that satisfies:
  1. $\|A\| \geq 0$
  2. $\|A\| = 0 \iff A = 0$
  3. $\|\alpha A\| = |\alpha|\|A\|$
  4. $\|A+B\| \leq \|A\| + \|B\|$
- **Def.** $\|A\|_* = \max\limits_{\|x\|=1} \|Ax\|_*$ where $\|Ax\|$ is any vector norm.
- $l_\infty : \|A\|_\infty = \max\limits_{1\leq i\leq n} \sum_{j=1}^{n} |a_{ij}|$ (row sum)

Special Properties

1. For any natural norm $\|\cdot\|_\alpha : \rho(A) \leq \|A\|_\alpha$
2. For $l_2 : \|A\|_2 = \sqrt{\rho(A^T A)}$

Vector Sequence Convergence

- $\left\{x^{(k)}\right\}$ converges to x for any small $\mathcal{E} > 0$ eventually every $x^{(k)}$ is within $\mathcal{E}$ of x

Eigenvalues and Eigenvectors

E.value (λ): Scalar s.t. $A\vec{x} = \lambda\vec{x}$
E.vector ($\vec{x}$): Nonzero vector only scaled by A
Spectral Radius: $\rho(A) = \max\{|\lambda_i|\}$

Properties

1. $\det(A - \lambda I) = 0 \iff \lambda$ is an eigenvalue. Solve the characteristic polynomial for λ.
2. $\forall\lambda[(A-\lambda I)\vec{x} = 0 \iff \vec{x}$ is an eigenvector$]$
3. If $\rho A < 1$, A is <u>convergent</u> $\implies \lim\limits_{k\to\infty} A^k = 0$

Linear Systems - Pivoting Strategies

If the pivot is small, large errors can occur. Pivoting helps maintain numerical stability.

Partial Pivoting

Choose the largest element in the **current column** (below or at the pivot) to avoid dividing by a small number.

1. For $k = 1 \dots n-1$:
   - Find $r = \arg\max\limits_{k\leq i\leq n}\{|a_{ik}|\}$
   - If $r \neq k$, swap rows: $E_k \leftrightarrow E_r$
   - Continue Gaussian Elimination as usual

Scaled Partial Pivoting

Handles rows with vastly different magnitudes by normalizing.

1. For each row $i = 1 \dots n$, compute the scale factor: $s_i = \max_j |a_{ij}|$
2. For pivot column k, choose the row r such that $\frac{|a_{rk}|}{s_r}$ is maximal for $r \geq k$
3. If $r \neq k$, swap rows: $E_k \leftrightarrow E_r$
4. Proceed with Gaussian Elimination

Full Pivoting

Most stable but most expensive. Swap both rows and columns.

1. At step k, find the largest element $|a_{ij}|$ in the submatrix $A_{k:n,k:n}$
2. Swap row k with row i, and column k with column j
3. Update row and column permutations
4. Continue Gaussian Elimination

Linear Algebra

- To multiply $A \cdot B$, dot-product the rows of A by the columns of B.
- $AA^{-1} = A^{-1}A = I$
- To find A^{-1}, row reduce the aug. matrix $[A|I]$.
- A^T is A flipped over the main diagonal.

Determinant

- $\det(A) \neq 0 \implies \begin{cases} A^{-1} & \text{exists} \\ Ax = b & \text{has a unique solution} \end{cases}$
- **Cofactor Expansion (Laplace Expansion)**: $\det(A) = \sum_{j=1}^{n} a_{ij}(-1)^{i+j}\det(A_{ij})$

Matrix Factorization

LU Decomposition

Row Swaps

Special Matrices

Permutation Matrices

Singular

Banded Matrices

Tridiagonal Matrices

Diagonally Dominant Matrices

Positive Definite Matrices

Iterative Methods for Linear Systems

Jacobi Method

Gauss-Seidel Method