

MATH115 Summary Note

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Contents

1	Chapter 1	1
1.1	Vectors	1
1.2	Vector Arithmetic	1
1.3	Directed Line Segment	2
1.4	Equation of a Line	2
1.5	Subspaces	2
1.5.1	Subspace Example 1	3
1.5.2	Subspace Example 2	4
1.6	Linear Dependency	4
1.6.1	Linearly Dependent	4
1.6.2	Linearly Independent	5
1.6.3	Examples	5
1.7	Norm of a Vector	5
1.8	Dot Product	5
1.8.1	Unit Vector	6
1.9	Projection	6
1.10	Equation of a Plane	7
2	Chapter 2	7
2.1	System of Linear Equations	7
2.2	System of Equation in Matrix Form	8
2.2.1	Homogeneous System	8
2.3	Elementary Row Operations	8
2.4	REF and RREF	9
2.4.1	Solution Set	9
2.4.2	Rank	10
3	Chapter 3	10
3.1	Matrix Operations	11
3.1.1	Matrix Multiplication	11
3.2	Transpose of Matrix	11
3.3	Matrix Inverse	11
3.3.1	Process of Finding Inverse	12
3.4	Important Properties	13
3.5	Matrix Mapping	13
3.6	Linear Mapping	13
3.6.1	Example:Proving Linear Mapping	14
3.7	Standard Matrix of a Linear Mapping	14
3.7.1	Example of Standard Matrix	15

List of Figures

This is a summary note about Math115 written for the first year engineering students that takes the course. This is by no means affiliated with the course directly, but is meant to be used as a supplementary guideline for the students to use if they need it. This summary was written by the General WEEF TA, Chad Paik.

The table of content shows the different sections, so feel free to look only in the section that one desires.

1 Chapter 1

Chapter 1 will cover Vectors, Equation of a Line, Subspaces, Linear Dependence/Independence, Dot Product, Projections/Perpendicular, Cross Product, Equation of a Plane, and Minimum Distances.

1.1 Vectors

Vectors are mathematical entities that have different meanings, but all connect together one way or the other.

The most common definition of a vector is that it has direction and magnitude in space. In linear algebra, the magnitude and direction represents the direction between points.

Vectors can also represent a group of numbers, just like how one would use in programming. This set of number can be geometrically interpreted as a set of point in space.

In this course, vector is represented as a vertical column consisted of numbers. The vector has to have an **arrow** on top, indicating that it is a vector

$$\vec{a} = \begin{bmatrix} a_1 \\ a_2 \end{bmatrix}$$

Where the numbers inside the vectors are called the **components** of the vector. These components represent the position that it has on each axis in space. Although only up to 3rd dimension can be visualized, dimension above 3 has axis as well.

1.2 Vector Arithmetic

Vectors, just like real numbers can be added and subtracted.

To add vectors, each coordinates are added, and same with subtraction.

$$\vec{x} = \begin{bmatrix} x_1 \\ x_2 \\ \cdot \\ \cdot \\ \cdot \\ x_n \end{bmatrix}, \vec{y} = \begin{bmatrix} y_1 \\ y_2 \\ \cdot \\ \cdot \\ \cdot \\ y_n \end{bmatrix}. \text{ Then, } \vec{x} + \vec{y} = \begin{bmatrix} x_1 + y_1 \\ x_2 + y_2 \\ \cdot \\ \cdot \\ \cdot \\ x_n + y_n \end{bmatrix} \text{ and } \vec{x} - \vec{y} = \begin{bmatrix} x_1 - y_1 \\ x_2 - y_2 \\ \cdot \\ \cdot \\ \cdot \\ x_n - y_n \end{bmatrix}.$$

Also, you can multiply a scalar value to a vector.

$$t\vec{x} = \begin{bmatrix} tx_1 \\ tx_2 \\ \cdot \\ \cdot \\ tx_n \end{bmatrix} \quad t \in \mathbb{R}$$

1.3 Directed Line Segment

To find the vector that forms between two points, you subtract two points. For example, if we have point $p = (P_1, P_2, P_3)$ and $q = (Q_1, Q_2, Q_3)$, then the vector that is going to form that connects from P to Q is:

$$\begin{aligned} \vec{PQ} &= q - p \\ \vec{PQ} &= \begin{bmatrix} Q_1 - P_1 \\ Q_2 - P_2 \\ Q_3 - P_3 \end{bmatrix} \end{aligned} \tag{1}$$

Same procedure extends to \mathbb{R}^n

1.4 Equation of a Line

With the knowledge of vectors, it is possible to find equation of a line.

Line consists of a point that it starts at, \vec{p} and the direction vector, \vec{d} , as well as a scalar t that determines the "length" of the direction vector. The general equation of a line is

$$\vec{x} = \vec{p} + t\vec{d} \tag{2}$$

1.5 Subspaces

One of the most confusing concept in Math115: Subspaces. **Subspaces are certain space that is within another space that satisfies certain conditions.** Space can be anything from a line, a plane, or a hyperplane.

The conditions that must be satisfied are:

1. $\vec{0}$ must exist in the space
2. When vectors in the space are added, then that resulting vector must still be in the original space (Closed Under Addition)
3. When a vector in the space is multiplied by a scalar, then the resulting vector must still be in the original space (Closed Under Scalar Multiplication)

When you are proving that a space is a subspace, it must be done generally, but to disprove that it is a subspace, then a counterexample is completely fine.

I will do two examples, one that is a subspace, and other one that is not a subspace.

1.5.1 Subspace Example 1

Prove or disprove that $S = \left\{ \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} \mid x_2 = 2x_1 \right\}$ is a subspace of \mathbb{R}^2 .

This is an equation of a line (you might recognize that if i express it as $y=2x$).

The general rule of thumb for approaching the subspace proof is to use LHS=RHS approach, where you go through LHS and RHS of a equation that you are trying to prove separately, and see if they are equal to each there at the end.

1.Zero Vector

$$\vec{0} = \begin{bmatrix} 0 \\ 0 \end{bmatrix}$$

LHS

$$0$$

RHS

$$2(0)$$

$$=0$$

Since LHS = RHS, $\vec{0}$ exists in the space.

2.C.U.S.

We define two vectors **that are part of the space** \vec{x} and \vec{y} .

$\vec{x} = \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}, \vec{y} = \begin{bmatrix} y_1 \\ y_2 \end{bmatrix}$ We already established that the two vectors are already part of the space, therefore it is possible to rewrite the vectors as following:

$\vec{x} = \begin{bmatrix} x_1 \\ 2x_1 \end{bmatrix}, \vec{y} = \begin{bmatrix} y_1 \\ 2y_1 \end{bmatrix}$ Now, we add the two vectors, to produce a new vector, $\vec{x} + \vec{y} = \begin{bmatrix} x_1 + y_1 \\ 2x_1 + 2y_1 \end{bmatrix}$. To prove that the new vector is part of the space again, we need to see if it still satisfies the condition, $x_2 = 2x_1$

LHS

$$2x_1 + 2y_1$$

RHS

$$2(x_1 + y_1)$$

$$= 2x_1 + 2y_1$$

Since second coordinate of the new vector is 2 times the first coordinate, we proved that the vector formed by addition is still part of the space.

3.C.U.S.M. Again, we define a vector that is part of the space, $\vec{x} = \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$

Again, we already defined that \vec{x} is part of the space, so we can rewrite the vector like before.

$$\vec{x} = \begin{bmatrix} x_1 \\ 2x_1 \end{bmatrix}$$

Additionally, we define a scalar value, $t, \in \mathbb{R}$.

The resulting vector formed after scalar multiplying the vector is

$$t\vec{x} = \begin{bmatrix} tx_1 \\ t2x_1 \end{bmatrix}$$

Again, we have to see if this resulting vector is still part of the space that satisfies that the condition, $x_2 = 2x_1$.

LHS

$$t2x_1 \\ = 2tx_1$$

RHS

$$2(tx_1) \\ = 2tx_1$$

Since $LHS = RHS$, we know that the space is closed under scalar multiplication.

In conclusion, since the space has zero vector included, closed under addition, and closed under scalar multiplication, we know that space S is a subspace of \mathbb{R}^2 .

1.5.2 Subspace Example 2

Prove or disprove that $S = \left\{ \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} \mid x_2 = x_1^2 \right\}$ is a subspace of \mathbb{R}^2 .

This is an equation of a parabola (you might recognize that if i express it as $y = x^2$). The general rule of thumb is, that if there is multiplication, division or power of variables, the space is not a subspace. **Counter Example** I am going to choose two vectors that are part of the space,

$$\vec{x} = \begin{bmatrix} 1 \\ 1 \end{bmatrix} \quad \vec{y} = \begin{bmatrix} 2 \\ 4 \end{bmatrix}$$

When these two vectors are added, the resulting vector is $\vec{x} + \vec{y} = \begin{bmatrix} 1+2 \\ 1+4 \end{bmatrix}$

$$\vec{x} + \vec{y} = \begin{bmatrix} 3 \\ 5 \end{bmatrix}$$

Since $5 \neq 3^2$, it is not closed under addition.

The space does not satisfy one of the condition, therefore the space is not a subspace.

1.6 Linear Dependency

For a set of vector, $S = \{\vec{v}_1, \vec{v}_2, \dots, \vec{v}_n\}$, linear dependency is determined by the behaviour of this equation:

$$\vec{0} = t_1\vec{v}_1 + t_2\vec{v}_2 + \dots + t_n\vec{v}_n \quad (3)$$

1.6.1 Linearly Dependent

Set of vector, $S = \{\vec{v}_1, \vec{v}_2, \dots, \vec{v}_n\}$ is **Linearly Dependent** if there exists a solution to (3) where t_1, \dots, t_n are **not all zeros**.

This also translates to this expression:

If a vector in the set can be expressed as a linear combination as other vector,

then that set of vector is linearly dependent.

1.6.2 Linearly Independent

Opposite of linearly dependent, Set of vector, $S = \{\vec{v}_1, \vec{v}_2, \dots, \vec{v}_n\}$ is **Linearly Independent** if the only solution to (3) is if t_1, \dots, t_n are **all zeros**.

This also translates to this expression:

If any vector in the set is not possible to be expressed as a linear combination of other vectors in the set, then the set of vectors is linearly independent.

1.6.3 Examples

$S = \left\{ \begin{bmatrix} 2 \\ 2 \end{bmatrix}, \begin{bmatrix} 1 \\ 0 \end{bmatrix}, \begin{bmatrix} 0 \\ 2 \end{bmatrix} \right\}$ is a set of **Linearly Dependent** vector.

The solution to the expression

$$\vec{0} = t_1 \begin{bmatrix} 2 \\ 2 \end{bmatrix} + t_2 \begin{bmatrix} 1 \\ 0 \end{bmatrix} + t_3 \begin{bmatrix} 0 \\ 2 \end{bmatrix} \quad (4)$$

can be solved by $t_1 = 1, t_2 = -2, t_3 = -1$. Since t_i values are not all zeros, this set of vector is linearly dependent.

Consider $T = \left\{ \begin{bmatrix} 1 \\ 0 \end{bmatrix}, \begin{bmatrix} 0 \\ 2 \end{bmatrix} \right\}$. The solution to the expression

$$\vec{0} = t_1 \begin{bmatrix} 1 \\ 0 \end{bmatrix} + t_2 \begin{bmatrix} 0 \\ 1 \end{bmatrix} \quad (5)$$

is only the trivial solution, where all the t_i values must be zero in order for the equation to be satisfied. Therefore, set of vector T is linearly independent.

1.7 Norm of a Vector

Norm of a vector is the magnitude of that vector (length of the vector). The famous Pythagoras Theorem can be expanded to find out the norm of a vector in \mathbb{R}^n . Norm of a vector is indicated with two vertical lines.

$$||\vec{v}|| = \sqrt{v_1^2 + v_2^2 + \dots + v_n^2} \quad (6)$$

1.8 Dot Product

Dot product is very difficult to describe with words exactly what it is. However, it will help if you understand that the dot product between Force and Displacement is Work.

Dot product has two definitions. They both yields the same result, but each of them are used in different situations.

1.8.1 Unit Vector

With the knowledge of norm of a vector, it is possible to find the unit vector. Unit vector is a vector that has the same direction, but has magnitude of 1.

Unit vector is calculated by dividing the vector by the norm. It is indicated with a hat on top of the vector.

$$\hat{\mathbf{x}} = \frac{\vec{x}}{||\vec{x}||} \quad (7)$$

$$1. \vec{x} \cdot \vec{y} = ||\vec{x}|| ||\vec{y}|| \cos \theta$$

$$2. \vec{x} \cdot \vec{y} = x_1 y_1 + x_2 y_2 + \dots + x_n y_n$$

The first equation is generally used more for physics problem, where the angle between the vectors, and magnitudes of the vectors are usually given. The second definition is more used for mathematics, where the components of the vectors is usually given.

With the second expression for dot product, the length of a vector can be expressed as

$$||\vec{x}|| = \sqrt{\vec{x} \cdot \vec{x}} \quad (8)$$

1.9 Projection

Projection is used to find the component of one vector in the direction of the vector that you are projecting onto.// The formula for projection is as follows:

$$proj_{\vec{x}} \vec{y} = \frac{\vec{x} \cdot \vec{y}}{||\vec{x}||^2} \vec{x} \quad (9)$$

The above equation takes in vectors and outputs a vector. Some questions require purely just the distance, and there is a shortcut formula for getting purely the magnitude.

$$||proj_{\vec{x}} \vec{y}|| = \left| \frac{\vec{y} \cdot \vec{x}}{||\vec{x}||} \right| \quad (10)$$

There is another component that can be found is the perpendicular part. Perpendicular part is perpendicular to the projection. When projection and perpendicular is added, the original vector that was projected is formed.

$$\begin{aligned} proj_{\vec{x}} \vec{y} + perp_{\vec{x}} \vec{y} &= \vec{y} \\ perp_{\vec{x}} \vec{y} &= \vec{y} - proj_{\vec{x}} \vec{y} \end{aligned} \quad (11)$$

1.10 Equation of a Plane

Scalar equation of a plane in \mathbb{R}^3 is described by the general equation,

$$n_1x_1 + n_2x_2 + n_3x_3 = d \quad (12)$$

where (n_1, n_2, n_3) are the coordinates of the vector that is normal to the plane.

This equation can be derived if we know the normal vector, and a known point on the plane, $P(p_1, p_2, p_3)$. Then, we define any general point on plane, $Q(x_1, x_2, x_3)$. First, we create \vec{PQ} .

$$\vec{PQ} = \begin{bmatrix} x_1 - p_1 \\ x_2 - p_2 \\ x_3 - p_3 \end{bmatrix} \quad (13)$$

We know that \vec{PQ} is on the plane, and will be orthogonal to the normal vector. Which means,

$$\vec{n} \cdot \vec{PQ} = 0$$

Expanding it out,

$$\begin{aligned} n_1(x_1 - p_1) + n_2(x_2 - p_2) + n_3(x_3 - p_3) &= 0 \\ n_1x_1 + n_2x_2 + n_3x_3 - (p_1 + p_2 + p_3) &= 0 \end{aligned} \quad (14)$$

Since $p_1, p_2, \text{ and } p_3$ are given numbers, it is possible to group it as another real number, d .

$$\begin{aligned} n_1x_1 + n_2x_2 + n_3x_3 - d &= 0 \\ n_1x_1 + n_2x_2 + n_3x_3 &= d \end{aligned} \quad (15)$$

Expanding this same concept to \mathbb{R}^n ,

$$n_1x_1 + n_2x_2 + n_3x_3 \dots n_nx_n = d \quad (16)$$

In this case, it is not called scalar equation of a plane, but scalar equation of a hyperplane.

2 Chapter 2

Chapter 2 was introduction to matrices and system of linear equations. In this section, System of Linear Equations, Elimination, Matrices, REF and RREF, and Rank.

(To be honest, explaining this chapter is really hard to do, so if my explanation is not as good as you want it to be, any feedback would be appreciated.)

2.1 System of Linear Equations

There are system of equations with certain solution.// For example, if we have a system of equation as following:

$$\begin{cases} 3x + 5y + z = 2 \\ 7x + 2y + 4z = 9 \\ -6x + 3y + 2z = 1 \end{cases} \quad \text{If you look at it carefully, these equations look like scalar equation}$$

of planes. The solution to this system of equation can be interpreted as the point that is in all three planes, or rather the intersection of the planes. The textbook explains system of equation and elimination a lot better than I can paraphrase. Therefore, if you want to learn more about these, please refer to the textbook.

2.2 System of Equation in Matrix Form

System of equation can be expressed as an augmented matrix. This matrix is in the form of $[A|\vec{b}]$ where A is a matrix formed by the coefficients of the linear equations, and \vec{b} is the vector made with the "answers" of each equations. Putting the above linear equation

into an augmented matrix, we get $\left(\begin{array}{ccc|c} 3 & 5 & 1 & 2 \\ 7 & -2 & 4 & 9 \\ -6 & 3 & 2 & 1 \end{array} \right)$ (Sorry, I didn't know how to make an augmented matrix with square bracket).

2.2.1 Homogeneous System

If the system all equals to zero, meaning \vec{b} is the zero vector, then the system is called **Homogeneous System**. $[A|\vec{0}]$.

2.3 Elementary Row Operations

Elementary Row Operations is a process that is used to eliminate rows in order to solve the system of equation. There are three type or ERO:

1. Multiply one row by a scalar that is not zero
2. Swapping Rows
3. Add a multiple of one row to another

It is possible to scalar multiply a row and subtract that from another row. For example,

$$R_1 - 3R_2 \tag{17}$$

In this case, Row1(R_1), is the row that is going to be changed and Row2(R_2) stays as is. However, operation such as

$$3R_1 - 2R_2 \tag{18}$$

is not allowed as you should not scalar multiply both rows. Additionally, another illegal operation is doing certain operations together.

$$\begin{array}{l} R_2 - 2R_3 \\ R_1 - R_2 \end{array} \quad (19)$$

Above is not allowed since the row that is being changed (R_2) is being used to change other row (R_1). However, there are legal combination of ERO, such as,

$$\begin{array}{l} R_2 - 2R_1 \\ R_3 + 6R_1 \end{array} \quad (20)$$

This is allowed since R_2 and R_3 are being changed independently with R_1 which is not being changed.

Please refer to the document about EROs on MATH115 Learn for more detail.

2.4 REF and RREF

After you perform the row reductions, the matrix can be expressed as REF or RREF. The definitions are as follows. [?] **REF**:

1. Row that is all zero must appear under rows that have numbers
2. When two non zero-rows are compared, the first non-zero entry (leading entry) in the upper row must be left of the row under it.

What this means is that below a leading entry, the numbers must be all zeros.

RREF goes one step further: **RREF**

1. All leading entries must be a 1, called leading 1
2. In a column with a leading 1, all the other entries are zeros.

2.4.1 Solution Set

System of equations has three possibilities:

1. **Inconsistent, No Solution:** If a row is all zeros, but the augmented side is non zero.
[00|6]
2. **Consistent, Infinitely Many Solutions:** If a row is all zeros and the augmented side is zero. Another way of interpreting this is **if there are any variables that does not have a leading entry in REF**
3. **Consistent, Unique Solutions:** If a row is not all zeros, and the augmented side is any real number. Another way of interpreting is **if all of the variables have a leading entry in REF**

When tackling one of those questions where there are variables in matrix and ask for conditions on the variables for each situation, start row reducing first to put into REF.

When there is a system of equation where there are going to be infinite solutions, **the variables without a leading entry are the free variables.**

For example, consider this system

$$\left(\begin{array}{cccc|c} 1 & 2 & 3 & 4 & 5 \\ 2 & 3 & 1 & 2 & 2 \\ 1 & 1 & 4 & 5 & 3 \end{array}\right)$$

The RREF of this matrix is

$$\left(\begin{array}{cccc|c} 1 & 0 & 0 & \frac{1}{6} & -4 \\ 0 & 1 & 0 & \frac{1}{6} & 3 \\ 0 & 0 & 1 & \frac{7}{6} & 1 \end{array}\right) \text{ The terms without leading entry is } x_4, \text{ therefore that will be the free variable. } x_4 = t. \text{ Then, express all the variables in terms of } t.$$

$$\begin{aligned} x_1 &= -4 - \frac{1}{6}t \\ x_2 &= 3 - \frac{1}{6}t \\ x_3 &= 1 - \frac{7}{6}t \\ x_4 &= 0 + t \end{aligned} \tag{21}$$

Putting this into a vector form, or the **standard form**, we get

$$\vec{x} = \begin{bmatrix} -4 \\ 3 \\ 1 \\ 0 \end{bmatrix} + t \begin{bmatrix} \frac{1}{6} \\ \frac{1}{6} \\ \frac{7}{6} \\ 1 \end{bmatrix} \tag{22}$$

This is the general solution for the system of equation above.

2.4.2 Rank

If the matrix is in RREF, then the **Number of leading 1s is called the Rank of the matrix.**

With rank, it is possible to know the number of free variables using this relationship:

$$\#freevariables = n - rank(A) \tag{23}$$

where n represents the number of variables.

3 Chapter 3

Chapter 3 introduces operations on matrices, and the concept of **Mapping**. These two are "essentially" the same thing. You can think of them like functions that were taught in

calculus, where you input a number that is within the domain, and get a output that is within the range.

In the case of linear mapping and matrix mapping, the domain is the **dimension of the vector that can be inputted**, and codomain is analogous to range, as it **represents the dimension of the output vector**. Usually, mapping is associated with use of equations to indicate the components of the output, and matrix mapping is associated with multiplying a matrix to a vector to perform the mapping.

IMPORTANT: All linear mappings are matrix mappings, but not all matrix mappings are linear mappings. However, they are usually the same thing in this course.

3.1 Matrix Operations

I am going to briefly explain matrix multiplications, and important properties that **I highly recommend** you memorizing for any examinations.

3.1.1 Matrix Multiplication

In order for matrix multiplication to work, the inner dimension must match up. That means that the number of columns of the first matrix must equal to number of rows of the second matrix. The definition of matrix multiplication that I used a lot in my help session is the following:

If we have two matrices $A_{n \times m}$ and $B_{m \times p}$, the product is defined as

$$(AB)_{ij} = \vec{a}_i \cdot \vec{b}_j \quad (24)$$

where \vec{a}_i represents the i th row of matrix A, and \vec{b}_j represents the j th row of matrix B, and $(AB)_{ij}$ represents the ij -th entry of the resulting matrix.

Important: Matrix multiplication is not commutative. $AB \neq BA$

3.2 Transpose of Matrix

Transpose of matrix has a very simple definition

$$A_{ij} = A_{ji}^T \quad (25)$$

Meaning the ij -th entry is now the ji -th entry of the transpose matrix. This means that the diagonal elements, $\text{ex}(A_{11}, A_{22})$ stay where they are.

3.3 Matrix Inverse

Although Matrix Inverses are chapter 3.5, I decided to include them here as I believe they are easier to understand grouped with matrix properties. Inverse of a matrix is defined as a matrix that produces the Identity Matrix when multiplied.

$$AB = I = BA \quad (26)$$

then B is an inverse of A. It is important to note that inverses does not exist for all matrices. This is summed up by Invertible Matrix Theorem.

Let A be an $n \times n$ matrix, then the following statements are equivalent, meaning that if one statement is true, then other statements are true.

1. A is invertible
2. $\text{rank}(A) = n$
3. RREF of A is Identity Matrix
4. For all $\vec{b} \in \mathbb{R}^n$, the system $A\vec{x} = \vec{b}$ is consistent and has a unique solution
5. The columns of A are linearly independent
6. The column space of A is \mathbb{R}^n

(If I recall correctly, the last two items are not taught in the course anymore, but still is true).

3.3.1 Process of Finding Inverse

The process of finding inverse is fairly long and tedious, but is very straight forward. To find the inverse of A, an $n \times n$ matrix, we need to set up an augmented matrix like following:

$$(A \mid I) \quad (27)$$

and then, row reduction must be done to make the previous system into following system:

$$(I \mid A^{-1}) \quad (28)$$

The matrix that gets formed after the original matrix turns into the identity matrix (RREF) is the inverse of A. If the original matrix does not turn into the Identity matrix when put into RREF, that means that there is not inverse for that specific matrix as per inverse matrix theorem.

For 2×2 matrix, there is a simple formula that can be applied:

$$\begin{aligned} \text{If } A &= \begin{bmatrix} a & b \\ c & d \end{bmatrix} \\ A^{-1} &= \frac{1}{ad - bc} \begin{bmatrix} d & -b \\ -c & a \end{bmatrix} \end{aligned} \quad (29)$$

If $ad - bc = 0$ then the inverse does not exist for that matrix.

3.4 Important Properties

There are four properties of matrix that is not intuitive, and should be memorized.

1. $(AB)^T = B^T A^T$
2. $(A + B)^T = A^T + B^T$
3. $(tA)^{-1} = \frac{1}{t} A^{-1}$
4. $(AB)^{-1} = B^{-1} A^{-1}$

3.5 Matrix Mapping

Matrix is not just used to solve system of equations, but also is used to map vectors into another vector in space. A function that performs matrix mapping is simply the input vector multiplied by the transformation matrix that describes the mapping.

The **domain** of the mapping is correspondent to **number of columns** and the **codomain** of the mapping is correspondent to **number of rows**. This makes sense if you go back to the definition of matrix mapping. The **Image** is the output vector created by a inputting a certain vector to the mapping.

Matrix mappings satisfies these conditions:

1. $f_A(\vec{x} + \vec{y}) = f_A(\vec{x}) + f_A(\vec{y})$
2. $f_A(t\vec{x}) = t f_A(\vec{x})$

These are proven through the properties of matrix multiplication.

3.6 Linear Mapping

The textbook defines linear mapping as function $L: \mathbb{R}^n \rightarrow \mathbb{R}^m$ if for every $\vec{x}, \vec{y} \in \mathbb{R}^n, t \in \mathbb{R}$ it satisfies following properties:

1. $(L1)L(\vec{x} + \vec{y}) = L(\vec{x}) + L(\vec{y})$
2. $(L2)L(t\vec{x}) = tL(\vec{x})$

However, when proving for whether a mapping is linear or not, it is possible to just only use this property:

$$L(t\vec{x} + \vec{y}) = tL(\vec{x}) + L(\vec{y}) \quad (30)$$

So if a questions asks to prove whether a mapping is linear or not, you just have to use the above and prevent having to do two things. Just like subspace, counter example is sufficient if you want to disprove that mapping is linear.

3.6.1 Example: Proving Linear Mapping

Consider $g(x_1, x_2) = (2x_1 + 3x_2, x_1)$. First identify the Domain, Codomain, and prove whether this mapping is linear or not. **Domain and Codomain**

Domain is the dimension of the input vector: \mathbb{R}^2

Codomain is the dimension of the output vector: \mathbb{R}^2

Linearity

We see that there are only addition, and scalar multiplication, therefore it has a good chance of being linear mapping.

We must prove that $L(t\vec{x} + \vec{y}) = tL(\vec{x}) + L(\vec{y})$.

Note that $t\vec{x} + \vec{y} = \begin{bmatrix} tx_1 + y_1 \\ tx_2 + y_2 \end{bmatrix}$

LHS

$$\begin{aligned} L(t\vec{x} + \vec{y}) &= \begin{bmatrix} 2(tx_1 + y_1) + 3(tx_2 + y_2) \\ tx_1 + y_1 \end{bmatrix} \\ &= \begin{bmatrix} 2tx_1 + 2y_1 + 3tx_2 + 3y_2 \\ tx_1 + y_1 \end{bmatrix} \\ &= \begin{bmatrix} 2tx_1 + 3tx_2 \\ tx_1 \end{bmatrix} + \begin{bmatrix} 2y_1 + 3y_2 \\ y_1 \end{bmatrix} \end{aligned} \tag{31}$$

(32)

Since **LHS** = **RHS**, the mapping $g(x_1, x_2)$ is a linear mapping.

3.7 Standard Matrix of a Linear Mapping

All linear mappings can be represented as a matrix mapping. This is done by forming a standard transformation matrix by compiling the images of the basis vectors.

We are introduced to this important concept on how only standard basis vectors of the domain is needed to describe the transformation of any vector in that domain. This is because any vector in \mathbb{R}^n can be described as linear combination of the standard basis vectors. Since linear mappings are linear, that means that if the vector can be represented as linear combination, then all we need is the behaviour of the standard basis vectors to characterize the mapping.

If there exists L that maps from \mathbb{R}^n to \mathbb{R}^m . The standard matrix that describes the mapping is described by

$$[L] = [L(\vec{e}_1) L(\vec{e}_2) \dots L(\vec{e}_n)] \tag{33}$$

3.7.1 Example of Standard Matrix

Consider the same linear mapping as before, $g(x_1, x_2) = (2x_1 + 3x_2, x_1)$. We will try to find the standard matrix that describes the linear mapping.

Like mentioned previously, the matrix is the compilation of the images of the standard basis vectors of the domain. Since the domain of the mapping is \mathbb{R}^2 , we consider

$$\vec{e}_1 = \begin{bmatrix} 1 \\ 0 \end{bmatrix} \quad \vec{e}_2 = \begin{bmatrix} 0 \\ 1 \end{bmatrix}$$

Carrying out the mapping,

$$g(\vec{e}_1) = \begin{bmatrix} 2 \\ 1 \end{bmatrix} \quad g(\vec{e}_2) = \begin{bmatrix} 3 \\ 0 \end{bmatrix}$$

Therefore, the standard matrix for g is

$$[g] = \begin{bmatrix} 2 & 3 \\ 1 & 0 \end{bmatrix}$$

We can confirm this by using a vector $\vec{x} = \begin{bmatrix} 2 & 3 \end{bmatrix}$. Using linear mapping, $g(\vec{x}) = \begin{bmatrix} 13 & 2 \end{bmatrix}$.

If we use matrix multiplication,

$$\begin{bmatrix} 2 & 3 \\ 1 & 0 \end{bmatrix} \begin{bmatrix} 2 \\ 3 \end{bmatrix} = \begin{bmatrix} 13 \\ 2 \end{bmatrix} \tag{34}$$