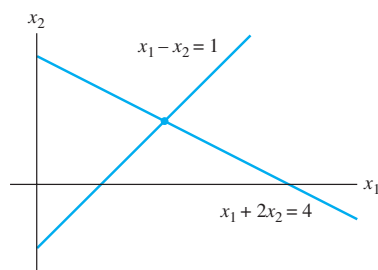


## 1.1 EXERCISES

Solve each system in Exercises 1–4 by using elementary row operations on the equations or on the augmented matrix. Follow the systematic elimination procedure described in this section.

1.  $x_1 + 5x_2 = 7$   
 $-2x_1 - 7x_2 = -5$
2.  $3x_1 + 6x_2 = -3$   
 $5x_1 + 7x_2 = 10$
3. Find the point  $(x_1, x_2)$  that lies on the line  $x_1 + 2x_2 = 4$  and on the line  $x_1 - x_2 = 1$ . See the figure.



4. Find the point of intersection of the lines  $x_1 + 2x_2 = -13$  and  $3x_1 - 2x_2 = 1$

Consider each matrix in Exercises 5 and 6 as the augmented matrix of a linear system. State in words the next two elementary row operations that should be performed in the process of solving the system.

$$5. \begin{bmatrix} 1 & -4 & -3 & 0 & 7 \\ 0 & 1 & 4 & 0 & 6 \\ 0 & 0 & 1 & 0 & 2 \\ 0 & 0 & 0 & 1 & -5 \end{bmatrix}$$

$$6. \begin{bmatrix} 1 & -6 & 4 & 0 & -1 \\ 0 & 2 & -7 & 0 & 4 \\ 0 & 0 & 1 & 2 & -3 \\ 0 & 0 & 4 & 1 & 2 \end{bmatrix}$$

In Exercises 7–10, the augmented matrix of a linear system has been reduced by row operations to the form shown. In each case, continue the appropriate row operations and describe the solution set of the original system.

$$7. \begin{bmatrix} 1 & 7 & 3 & -4 \\ 0 & 1 & -1 & 3 \\ 0 & 0 & 0 & 1 \\ 0 & 0 & 1 & -2 \end{bmatrix}$$

$$8. \begin{bmatrix} 1 & -5 & 4 & 0 & 0 \\ 0 & 1 & 0 & 1 & 0 \\ 0 & 0 & 3 & 0 & 0 \\ 0 & 0 & 0 & 2 & 0 \end{bmatrix}$$

$$9. \begin{bmatrix} 1 & -1 & 0 & 0 & -5 \\ 0 & 1 & -2 & 0 & -7 \\ 0 & 0 & 1 & -3 & 2 \\ 0 & 0 & 0 & 1 & 4 \end{bmatrix}$$

$$10. \begin{bmatrix} 1 & 3 & 0 & -2 & -7 \\ 0 & 1 & 0 & 3 & 6 \\ 0 & 0 & 1 & 0 & 2 \\ 0 & 0 & 0 & 1 & -2 \end{bmatrix}$$

Solve the systems in Exercises 11–14.

$$11. \begin{aligned} x_2 + 5x_3 &= -4 \\ x_1 + 4x_2 + 3x_3 &= -2 \\ 2x_1 + 7x_2 + x_3 &= -2 \end{aligned}$$

$$12. \begin{aligned} x_1 - 5x_2 + 4x_3 &= -3 \\ 2x_1 - 7x_2 + 3x_3 &= -2 \\ -2x_1 + x_2 + 7x_3 &= -1 \end{aligned}$$

$$13. \begin{aligned} x_1 - 3x_3 &= 8 \\ 2x_1 + 2x_2 + 9x_3 &= 7 \\ x_2 + 5x_3 &= -2 \end{aligned}$$

$$14. \begin{aligned} 2x_1 - 6x_3 &= -8 \\ x_2 + 2x_3 &= 3 \\ 3x_1 + 6x_2 - 2x_3 &= -4 \end{aligned}$$

Determine if the systems in Exercises 15 and 16 are consistent. Do not completely solve the systems.

$$15. \begin{aligned} x_1 - 6x_2 &= 5 \\ x_2 - 4x_3 + x_4 &= 0 \\ -x_1 + 6x_2 + x_3 + 5x_4 &= 3 \\ -x_2 + 5x_3 + 4x_4 &= 0 \end{aligned}$$

$$16. \begin{aligned} 2x_1 - 4x_4 &= -10 \\ 3x_2 + 3x_3 &= 0 \\ x_3 + 4x_4 &= -1 \\ -3x_1 + 2x_2 + 3x_3 + x_4 &= 5 \end{aligned}$$

17. Do the three lines  $2x_1 + 3x_2 = -1$ ,  $6x_1 + 5x_2 = 0$ , and  $2x_1 - 5x_2 = 7$  have a common point of intersection? Explain.

18. Do the three planes  $2x_1 + 4x_2 + 4x_3 = 4$ ,  $x_2 - 2x_3 = -2$ , and  $2x_1 + 3x_2 = 0$  have at least one common point of intersection? Explain.

In Exercises 19–22, determine the value(s) of  $h$  such that the matrix is the augmented matrix of a consistent linear system.

$$19. \begin{bmatrix} 1 & h & 4 \\ 3 & 6 & 8 \end{bmatrix}$$

$$20. \begin{bmatrix} 1 & h & -5 \\ 2 & -8 & 6 \end{bmatrix}$$

$$21. \begin{bmatrix} 1 & 4 & -2 \\ 3 & h & -6 \end{bmatrix}$$

$$22. \begin{bmatrix} -4 & 12 & h \\ 2 & -6 & -3 \end{bmatrix}$$

In Exercises 23 and 24, key statements from this section are either quoted directly, restated slightly (but still true), or altered in some way that makes them false in some cases. Mark each statement True or False, and *justify* your answer. (If true, give the

approximate location where a similar statement appears, or refer to a definition or theorem. If false, give the location of a statement that has been quoted or used incorrectly, or cite an example that shows the statement is not true in all cases.) Similar true/false questions will appear in many sections of the text.

23. a. Every elementary row operation is reversible.  
 b. A  $5 \times 6$  matrix has six rows.  
 c. The solution set of a linear system involving variables  $x_1, \dots, x_n$  is a list of numbers  $(s_1, \dots, s_n)$  that makes each equation in the system a true statement when the values  $s_1, \dots, s_n$  are substituted for  $x_1, \dots, x_n$ , respectively.  
 d. Two fundamental questions about a linear system involve existence and uniqueness.
24. a. Two matrices are row equivalent if they have the same number of rows.  
 b. Elementary row operations on an augmented matrix never change the solution set of the associated linear system.  
 c. Two equivalent linear systems can have different solution sets.  
 d. A consistent system of linear equations has one or more solutions.
25. Find an equation involving  $g$ ,  $h$ , and  $k$  that makes this augmented matrix correspond to a consistent system:
- $$\left[ \begin{array}{ccc|c} 1 & -4 & 7 & g \\ 0 & 3 & -5 & h \\ -2 & 5 & -9 & k \end{array} \right]$$
26. Suppose the system below is consistent for all possible values of  $f$  and  $g$ . What can you say about the coefficients  $c$  and  $d$ ? Justify your answer.
- $$2x_1 + 4x_2 = f$$
- $$cx_1 + dx_2 = g$$
27. Suppose  $a$ ,  $b$ ,  $c$ , and  $d$  are constants such that  $a$  is not zero and the system below is consistent for all possible values of  $f$  and  $g$ . What can you say about the numbers  $a$ ,  $b$ ,  $c$ , and  $d$ ? Justify your answer.
- $$ax_1 + bx_2 = f$$
- $$cx_1 + dx_2 = g$$
28. Construct three different augmented matrices for linear systems whose solution set is  $x_1 = 3$ ,  $x_2 = -2$ ,  $x_3 = -1$ .

In Exercises 29–32, find the elementary row operation that transforms the first matrix into the second, and then find the reverse row operation that transforms the second matrix into the first.

29.  $\begin{bmatrix} 0 & -2 & 5 \\ 1 & 3 & -5 \\ 3 & -1 & 6 \end{bmatrix}, \begin{bmatrix} 3 & -1 & 6 \\ 1 & 3 & -5 \\ 0 & -2 & 5 \end{bmatrix}$

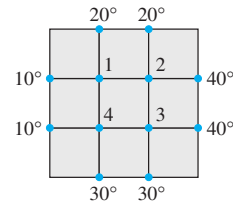
30.  $\begin{bmatrix} 1 & 3 & -4 \\ 0 & -2 & 6 \\ 0 & -5 & 10 \end{bmatrix}, \begin{bmatrix} 1 & 3 & -4 \\ 0 & -2 & 6 \\ 0 & 1 & -2 \end{bmatrix}$

31.  $\begin{bmatrix} 1 & -2 & 1 & 0 \\ 0 & 5 & -2 & 8 \\ 4 & -1 & 3 & -6 \end{bmatrix}, \begin{bmatrix} 1 & -2 & 1 & 0 \\ 0 & 5 & -2 & 8 \\ 0 & 7 & -1 & -6 \end{bmatrix}$

32.  $\begin{bmatrix} 1 & 2 & -5 & 0 \\ 0 & 1 & -3 & -2 \\ 0 & 4 & -12 & 7 \end{bmatrix}, \begin{bmatrix} 1 & 2 & -5 & 0 \\ 0 & 1 & -3 & -2 \\ 0 & 0 & 0 & 15 \end{bmatrix}$

An important concern in the study of heat transfer is to determine the steady-state temperature distribution of a thin plate when the temperature around the boundary is known. Assume the plate shown in the figure represents a cross section of a metal beam, with negligible heat flow in the direction perpendicular to the plate. Let  $T_1, \dots, T_4$  denote the temperatures at the four interior nodes of the mesh in the figure. The temperature at a node is approximately equal to the average of the four nearest nodes—to the left, above, to the right, and below.<sup>3</sup> For instance,

$$T_1 = (10 + 20 + T_2 + T_4)/4, \quad \text{or} \quad 4T_1 - T_2 - T_4 = 30$$



33. Write a system of four equations whose solution gives estimates for the temperatures  $T_1, \dots, T_4$ .
34. Solve the system of equations from Exercise 33. [Hint: To speed up the calculations, interchange rows 1 and 4 before starting “replace” operations.]

<sup>3</sup> See Frank M. White, *Heat and Mass Transfer* (Reading, MA: Addison-Wesley Publishing, 1991), pp. 145–149.

## SOLUTIONS TO PRACTICE PROBLEMS

1. a. For “hand computation,” the best choice is to interchange equations 3 and 4. Another possibility is to multiply equation 3 by  $1/5$ . Or, replace equation 4 by its sum with  $-1/5$  times row 3. (In any case, do not use the  $x_2$  in equation 2 to eliminate the  $4x_2$  in equation 1. Wait until a triangular form has been reached and the  $x_3$  terms and  $x_4$  terms have been eliminated from the first two equations.)

## THEOREM 2

## Existence and Uniqueness Theorem

A linear system is consistent if and only if the rightmost column of the augmented matrix is *not* a pivot column—that is, if and only if an echelon form of the augmented matrix has *no* row of the form

$$[0 \ \cdots \ 0 \ b] \quad \text{with } b \text{ nonzero}$$

If a linear system is consistent, then the solution set contains either (i) a unique solution, when there are no free variables, or (ii) infinitely many solutions, when there is at least one free variable.

The following procedure outlines how to find and describe all solutions of a linear system.

## USING ROW REDUCTION TO SOLVE A LINEAR SYSTEM

1. Write the augmented matrix of the system.
2. Use the row reduction algorithm to obtain an equivalent augmented matrix in echelon form. Decide whether the system is consistent. If there is no solution, stop; otherwise, go to the next step.
3. Continue row reduction to obtain the reduced echelon form.
4. Write the system of equations corresponding to the matrix obtained in step 3.
5. Rewrite each nonzero equation from step 4 so that its one basic variable is expressed in terms of any free variables appearing in the equation.

## PRACTICE PROBLEMS

1. Find the general solution of the linear system whose augmented matrix is

$$\begin{bmatrix} 1 & -3 & -5 & 0 \\ 0 & 1 & 1 & 3 \end{bmatrix}$$

2. Find the general solution of the system

$$\begin{aligned} x_1 - 2x_2 - x_3 + 3x_4 &= 0 \\ -2x_1 + 4x_2 + 5x_3 - 5x_4 &= 3 \\ 3x_1 - 6x_2 - 6x_3 + 8x_4 &= 2 \end{aligned}$$

## 1.2 EXERCISES

In Exercises 1 and 2, determine which matrices are in reduced echelon form and which others are only in echelon form.

1. a.  $\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 1 \end{bmatrix}$       b.  $\begin{bmatrix} 1 & 0 & 1 & 0 \\ 0 & 1 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$

c.  $\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 1 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$       d.  $\begin{bmatrix} 1 & 1 & 0 & 1 & 1 \\ 0 & 2 & 0 & 2 & 2 \\ 0 & 0 & 0 & 3 & 3 \\ 0 & 0 & 0 & 0 & 4 \end{bmatrix}$

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2. a.  $\begin{bmatrix} 1 & 0 & 1 & 1 \\ 0 & 1 & 1 & 1 \\ 0 & 0 & 0 & 0 \end{bmatrix}$  b.  $\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 2 & 0 & 0 \\ 0 & 0 & 1 & 1 \end{bmatrix}$

c.  $\begin{bmatrix} 0 & 0 & 0 & 0 \\ 1 & 2 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$

d.  $\begin{bmatrix} 0 & 1 & 1 & 1 & 1 \\ 0 & 0 & 1 & 1 & 1 \\ 0 & 0 & 0 & 0 & 1 \\ 0 & 0 & 0 & 0 & 0 \end{bmatrix}$

Row reduce the matrices in Exercises 3 and 4 to reduced echelon form. Circle the pivot positions in the final matrix and in the original matrix, and list the pivot columns.

3.  $\begin{bmatrix} 1 & 2 & 4 & 8 \\ 2 & 4 & 6 & 8 \\ 3 & 6 & 9 & 12 \end{bmatrix}$  4.  $\begin{bmatrix} 1 & 2 & 4 & 5 \\ 2 & 4 & 5 & 4 \\ 4 & 5 & 4 & 2 \end{bmatrix}$

5. Describe the possible echelon forms of a nonzero  $2 \times 2$  matrix. Use the symbols  $\blacksquare$ ,  $*$ , and  $0$ , as in the first part of Example 1.

6. Repeat Exercise 5 for a nonzero  $3 \times 2$  matrix.

Find the general solutions of the systems whose augmented matrices are given in Exercises 7–14.

7.  $\begin{bmatrix} 1 & 3 & 4 & 7 \\ 3 & 9 & 7 & 6 \end{bmatrix}$  8.  $\begin{bmatrix} 1 & -3 & 0 & -5 \\ -3 & 7 & 0 & 9 \end{bmatrix}$

9.  $\begin{bmatrix} 0 & 1 & -2 & 3 \\ 1 & -3 & 4 & -6 \end{bmatrix}$  10.  $\begin{bmatrix} 1 & -2 & -1 & 4 \\ -2 & 4 & -5 & 6 \end{bmatrix}$

11.  $\begin{bmatrix} 3 & -2 & 4 & 0 \\ 9 & -6 & 12 & 0 \\ 6 & -4 & 8 & 0 \end{bmatrix}$  12.  $\begin{bmatrix} 1 & 0 & -9 & 0 & 4 \\ 0 & 1 & 3 & 0 & -1 \\ 0 & 0 & 0 & 1 & -7 \\ 0 & 0 & 0 & 0 & 1 \end{bmatrix}$

13.  $\begin{bmatrix} 1 & -3 & 0 & -1 & 0 & -2 \\ 0 & 1 & 0 & 0 & -4 & 1 \\ 0 & 0 & 0 & 1 & 9 & 4 \\ 0 & 0 & 0 & 0 & 0 & 0 \end{bmatrix}$

14.  $\begin{bmatrix} 1 & 0 & -5 & 0 & -8 & 3 \\ 0 & 1 & 4 & -1 & 0 & 6 \\ 0 & 0 & 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 \end{bmatrix}$

Exercises 15 and 16 use the notation of Example 1 for matrices in echelon form. Suppose each matrix represents the augmented matrix for a system of linear equations. In each case, determine if the system is consistent. If the system is consistent, determine if the solution is unique.

15. a.  $\begin{bmatrix} \blacksquare & * & * & * \\ 0 & \blacksquare & * & * \\ 0 & 0 & 0 & 0 \end{bmatrix}$

b.  $\begin{bmatrix} 0 & \blacksquare & * & * & * \\ 0 & 0 & \blacksquare & * & * \\ 0 & 0 & 0 & \blacksquare & 0 \end{bmatrix}$

16. a.  $\begin{bmatrix} \blacksquare & * & * \\ 0 & \blacksquare & * \\ 0 & 0 & \blacksquare \end{bmatrix}$

b.  $\begin{bmatrix} \blacksquare & * & * & * & * \\ 0 & 0 & \blacksquare & * & * \\ 0 & 0 & 0 & \blacksquare & * \end{bmatrix}$

In Exercises 17 and 18, determine the value(s) of  $h$  such that the matrix is the augmented matrix of a consistent linear system.

17.  $\begin{bmatrix} 1 & -1 & 4 \\ -2 & 3 & h \end{bmatrix}$  18.  $\begin{bmatrix} 1 & -3 & 1 \\ h & 6 & -2 \end{bmatrix}$

In Exercises 19 and 20, choose  $h$  and  $k$  such that the system has (a) no solution, (b) a unique solution, and (c) many solutions. Give separate answers for each part.

19.  $\begin{aligned} x_1 + hx_2 &= 2 \\ 4x_1 + 8x_2 &= k \end{aligned}$  20.  $\begin{aligned} x_1 - 3x_2 &= 1 \\ 2x_1 + hx_2 &= k \end{aligned}$

In Exercises 21 and 22, mark each statement True or False. Justify each answer.<sup>4</sup>

21. a. In some cases, a matrix may be row reduced to more than one matrix in reduced echelon form, using different sequences of row operations.  
b. The row reduction algorithm applies only to augmented matrices for a linear system.  
c. A basic variable in a linear system is a variable that corresponds to a pivot column in the coefficient matrix.  
d. Finding a parametric description of the solution set of a linear system is the same as *solving* the system.  
e. If one row in an echelon form of an augmented matrix is  $[0 \ 0 \ 0 \ 5 \ 0]$ , then the associated linear system is inconsistent.
22. a. The reduced echelon form of a matrix is unique.  
b. If every column of an augmented matrix contains a pivot, then the corresponding system is consistent.  
c. The pivot positions in a matrix depend on whether row interchanges are used in the row reduction process.  
d. A general solution of a system is an explicit description of all solutions of the system.  
e. Whenever a system has free variables, the solution set contains many solutions.
23. Suppose the coefficient matrix of a linear system of four equations in four variables has a pivot in each column. Explain why the system has a unique solution.
24. Suppose a system of linear equations has a  $3 \times 5$  augmented matrix whose fifth column is not a pivot column. Is the system consistent? Why (or why not)?

<sup>4</sup> True/false questions of this type will appear in many sections. Methods for justifying your answers were described before Exercises 23 and 24 in Section 1.1.

25. Suppose the coefficient matrix of a system of linear equations has a pivot position in every row. Explain why the system is consistent.
26. Suppose a  $3 \times 5$  coefficient matrix for a system has three pivot columns. Is the system consistent? Why or why not?
27. Restate the last sentence in Theorem 2 using the concept of pivot columns: "If a linear system is consistent, then the solution is unique if and only if \_\_\_\_\_."
28. What would you have to know about the pivot columns in an augmented matrix in order to know that the linear system is consistent and has a unique solution?
29. A system of linear equations with fewer equations than unknowns is sometimes called an *underdetermined system*. Can such a system have a unique solution? Explain.
30. Give an example of an inconsistent underdetermined system of two equations in three unknowns.
31. A system of linear equations with more equations than unknowns is sometimes called an *overdetermined system*. Can such a system be consistent? Illustrate your answer with a specific system of three equations in two unknowns.
32. Suppose an  $n \times (n + 1)$  matrix is row reduced to reduced echelon form. Approximately what fraction of the total number of operations (flops) is involved in the backward phase of the reduction when  $n = 20$ ? when  $n = 200$ ?

Suppose experimental data are represented by a set of points in the plane. An **interpolating polynomial** for the data is a polynomial whose graph passes through every point. In scientific work,

such a polynomial can be used, for example, to estimate values between the known data points. Another use is to create curves for graphical images on a computer screen. One method for finding an interpolating polynomial is to solve a system of linear equations.

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33. Find the interpolating polynomial  $p(t) = a_0 + a_1t + a_2t^2$  for the data  $(1, 6)$ ,  $(2, 15)$ ,  $(3, 28)$ . That is, find  $a_0$ ,  $a_1$ , and  $a_2$  such that

$$a_0 + a_1(1) + a_2(1)^2 = 6$$

$$a_0 + a_1(2) + a_2(2)^2 = 15$$

$$a_0 + a_1(3) + a_2(3)^2 = 28$$

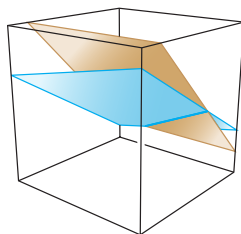
34. [M] In a wind tunnel experiment, the force on a projectile due to air resistance was measured at different velocities:

Velocity (100 ft/sec)	0	2	4	6	8	10
Force (100 lb)	0	2.90	14.8	39.6	74.3	119

Find an interpolating polynomial for these data and estimate the force on the projectile when the projectile is traveling at 750 ft/sec. Use  $p(t) = a_0 + a_1t + a_2t^2 + a_3t^3 + a_4t^4 + a_5t^5$ . What happens if you try to use a polynomial of degree less than 5? (Try a cubic polynomial, for instance.)<sup>5</sup>

<sup>5</sup> Exercises marked with the symbol [M] are designed to be worked with the aid of a "Matrix program" (a computer program, such as MATLAB®, Maple™, Mathematica®, MathCad®, or Derive™, or a programmable calculator with matrix capabilities, such as those manufactured by Texas Instruments or Hewlett-Packard).

## SOLUTIONS TO PRACTICE PROBLEMS



The general solution of the system of equations is the line of intersection of the two planes.

1. The reduced echelon form of the augmented matrix and the corresponding system are

$$\begin{bmatrix} 1 & 0 & -2 & 9 \\ 0 & 1 & 1 & 3 \end{bmatrix} \quad \text{and} \quad \begin{cases} x_1 - 2x_3 = 9 \\ x_2 + x_3 = 3 \end{cases}$$

The basic variables are  $x_1$  and  $x_2$ , and the general solution is

$$\begin{cases} x_1 = 9 + 2x_3 \\ x_2 = 3 - x_3 \\ x_3 \text{ is free} \end{cases}$$

*Note:* It is essential that the general solution describe each variable, with any parameters clearly identified. The following statement does *not* describe the solution:

$$\begin{cases} x_1 = 9 + 2x_3 \\ x_2 = 3 - x_3 \\ x_3 = 3 - x_2 \end{cases} \quad \text{Incorrect solution}$$

This description implies that  $x_2$  and  $x_3$  are *both* free, which certainly is not the case.