

Fundamentals of Linear Algebra and Optimization

Jean Gallier

Homework 3

October 25, 2016

Francine Leech, Reffat Manzur, Chen Xiang

Problem B1 (20 pts).

Let us prove this first for two subspaces. $E = U_1 \oplus U_2$ if and only if

$$(1) \ E = U_1 + U_2$$

and

$$(2) \ U_1 \cap U_2 = \{0\}$$

For (1), every vector $e \in E$ can be uniquely written as $e = u_{11} + u_{21}$ with $u_{11} \in U_1$ and $u_{21} \in U_2$.

For (2), let $e \in U_1 \cap U_2$. Since $e \in U_1$ and $e \in U_2$, then we can write,

$$(1) \ e = e + 0 \text{ where } e \in U_1 \text{ and } 0 \in U_2 \text{ and}$$

$$(2) \ e = 0 + 0 \text{ where } 0 \in U_1 \text{ and } e \in U_2.$$

But $e = u_{11} + u_{21}$ is unique, so $e = 0$. Since $E = U_1 + U_2$, we will check uniqueness. Suppose $e = u_{11} + u_{21}$ and $e = u_{12} + u_{22}$ where $u_{11}, u_{12} \in U_1$ and $u_{21}, u_{22} \in U_2$. Then $u_{11} + u_{21} = u_{12} + u_{22}$, so $u_{11} - u_{12} = u_{22} - u_{21}$. Let x be a vector such that $x = u_{11} - u_{12} = u_{22} - u_{21}$. Then $x \in U_1$ and $x \in U_2$, and $u_{11} = u_{12}$ and $u_{22} = u_{21}$, so $x \in U_1 \cap U_2 = \{0\}$.

Now by induction we can extend our logic for any number of $p \geq 2$ subspaces of some vector space E .

Problem B2 (50 pts).

$$(1)$$

By definition an involution is a function f that is its own inverse.

$f : E \rightarrow E$ is in an involution when $\forall x \in E : f(f(x)) = x$. Since $f^{-1} = f$, we just have to check that $f(f(x)) = x$ for all x in the domain of f .

Let us find the inverse of $f(x) = a - x$ where a is any real number. Let,

$$f(x) = a - x$$

$$y = a - x$$

$$f^{-1} = a - y$$

$$x = a - y$$

$$y = a - x$$

so $f(x) = f^{-1}(x)$. So it's an inverse of itself.

(2)

$$\text{Let } u_1 = \frac{u+f(u)}{2} \text{ and } u_{-1} = \frac{u-f(u)}{2}.$$

$$\begin{aligned} \text{Next, we can find that we have something in both the spaces. } f(u_1) &= f\left(\frac{u+f(u)}{2}\right) = \\ \frac{f(u)+f(f(u))}{2} &= \frac{f(u)+u}{2} = u_1 \\ f(u_{-1}) &= f\left(\frac{u-f(u)}{2}\right) = \frac{f(u)-f(f(u))}{2} = \frac{f(u)-u}{2} = u_{-1}. \end{aligned}$$

Next we need to look at uniqueness. Let $v_1 \in E_1$ and $v_{-1} \in E_{-1}$.

$$f(v_1) = v_1$$

$$f(v_1) = -v_1$$

$v_1 = -v_1$ can only have this if $v_1 = -v_1 = 0$.

$$(3) \text{ Let the basis of } E \text{ be } (\xi_i), i = 1, 2, \dots, n, \text{ where } \xi_i = \begin{pmatrix} 0 \\ 0 \\ \vdots \\ 1_i \\ 0 \\ \vdots \\ 0 \end{pmatrix}. \text{ Define}$$

$$f(\xi_i) = \begin{cases} \xi_i & i = 1, 2, \dots, k \\ -\xi_i & i = k+1, k+2, \dots, n \end{cases}. \text{ Then } \forall u \in E, \text{ we can write as } u = \sum_i \lambda_i \xi_i \text{ and}$$

$$f(u) = \begin{pmatrix} \xi_1 \\ \xi_2 \\ \vdots \\ \xi_k \\ -\xi_{k+1} \\ -\xi_{k+2} \\ \vdots \\ -\xi_n \end{pmatrix} = I_{k,n-k} \cdot u. \text{ And } (f \circ f)(u) = I_{k,n-k} I_{k,n-k} I_{k,n-k} u = I u = u. \text{ Thus } f \text{ is an}$$

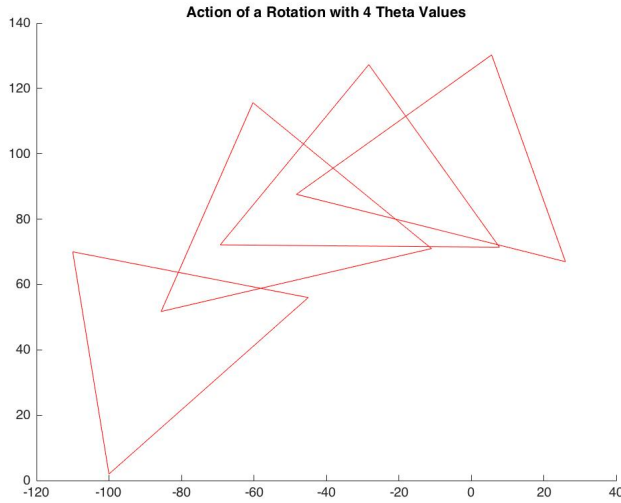
involution.

Geometric interpretation of the action of f is that $f(u)$ is the reflection of u across some axes. When $k = n - 1$, we can easily find that $f(u)$ differs from u only in the last entry $f(u)_i = -u_i$, so it is the reflection across the n^{th} axis.

Problem B3 (50 pts).

(1)

Here we graphed the action of rotation with 4 θ values. The code for the graphic is included in the Appendix.



(2)

$$\begin{aligned} & \begin{pmatrix} \cos \theta & -\sin \theta \\ \sin \theta & \cos \theta \end{pmatrix} \cdot \begin{pmatrix} \cos(-\theta) & -\sin(-\theta) \\ \sin(-\theta) & \cos(-\theta) \end{pmatrix} \\ &= \begin{pmatrix} \cos(\theta) & -\sin(\theta) \\ \sin(\theta) & \cos(\theta) \end{pmatrix} \cdot \begin{pmatrix} \cos(\theta) & \sin(\theta) \\ -\sin(\theta) & \cos(\theta) \end{pmatrix} \\ &= \begin{pmatrix} (\cos \theta \cdot \cos(-\theta))(-\sin \theta \sin(-\theta)) & -\cos(\theta) \sin(\theta) - \sin(\theta) \cos(\theta) \\ \sin(\theta) \cos(-\theta) + \cos \theta \sin(-\theta) & \cos(\theta) \cos(\theta) + \sin(\theta) \sin(\theta) \end{pmatrix} = \begin{pmatrix} 1 & 0 \\ 0 & 1 \end{pmatrix} \end{aligned}$$

(3) Because $\cos(\alpha + \beta) = \cos \alpha \cos \beta - \sin \alpha \sin \beta$, $\sin(\alpha + \beta) = \sin \alpha \cos \beta + \cos \alpha \sin \beta$, we have

$$\begin{aligned} R_\alpha \circ R_\beta &= \begin{pmatrix} \cos \alpha & -\sin \alpha \\ \sin \alpha & \cos \alpha \end{pmatrix} \cdot \begin{pmatrix} \cos \beta & -\sin \beta \\ \sin \beta & \cos \beta \end{pmatrix} \\ &= R_\beta \circ R_\alpha = R_{\alpha+\beta} \end{aligned}$$

We can get

$$\begin{aligned} 1. & (R_\alpha \circ R_\beta) \circ R_\gamma = R_{\alpha+\beta+\gamma} = R_\alpha \circ (R_\beta \circ R_\gamma) \\ 2. & R_\alpha \circ I = I \circ R_\alpha = R_\alpha \\ 3. & R_\alpha \circ R_{-\alpha} = I \\ 4. & R_\alpha \circ R_\beta = R_{\alpha+\beta} = R_\beta \circ R_\alpha \end{aligned}$$

So rotations in the plane form a commutative group.

Problem B4 (110 pts).

(1) We can write $\begin{pmatrix} c_1 \\ c_2 \end{pmatrix} = R_{\theta, (a_1, a_2)} \begin{pmatrix} c_1 \\ c_2 \end{pmatrix}$ as:

$$\begin{pmatrix} c_1 \\ c_2 \end{pmatrix} = \begin{pmatrix} \cos \theta & -\sin \theta \\ \sin \theta & \cos \theta \end{pmatrix} \begin{pmatrix} c_1 \\ c_2 \end{pmatrix} + \begin{pmatrix} a_1 \\ a_2 \end{pmatrix}$$

Then,

$$c_1 = \cos \theta c_1 - \sin \theta c_2 + a_1 \quad (1)$$

$$c_2 = \sin \theta c_1 + \cos \theta c_2 + a_2 \quad (2)$$

Using the result for (c_1, c_2) as given in the problem and by substituting, we will check if the equations are true for when $\theta \neq k2\pi$.

For c_1 , we are given that

$$c_1 = \frac{1}{2 \sin \frac{\theta}{2}} (\cos(\frac{\pi - \theta}{2}) a_1) - \sin(\frac{\pi - \theta}{2}) a_2$$

$\frac{1}{2} \frac{\cos(\frac{\pi - \theta}{2})}{\sin \frac{\theta}{2}}$ simplifies to $\frac{1}{2}$.

$\frac{-1}{2} \frac{\sin(\frac{\pi - \theta}{2})}{\sin \frac{\theta}{2}}$ simplifies to $\frac{1}{2} \cot \frac{\theta}{2}$.

so:

$$c_1 = \frac{1}{2} (a_1 - \cot \frac{\theta}{2} a_2)$$

Similarly, for c_2 , it becomes

$$c_2 = \frac{1}{2} \cot \frac{\theta}{2} a_1 + \frac{1}{2} a_2$$

Now by substitution into equation (1), we get :

$$\begin{aligned}
& \frac{1}{2}(a_1 - \cot \frac{\theta}{2} a_2) \\
&= \cos \theta (\frac{1}{2}(a_1 - \cot \frac{\theta}{2} a_2)) - \sin \theta (\frac{1}{2} \cot \frac{\theta}{2} a_1 + \frac{1}{2} a_2) + a_1 \\
&= (\frac{\cos \theta}{2} - \frac{\sin \theta}{2} \cot \frac{\theta}{2} + 1) a_1 - \frac{1}{2} (\cos \theta \cot \frac{\theta}{2} + \sin \theta) a_2
\end{aligned}$$

Then, $\cos \theta - \sin \theta \cot \frac{\theta}{2} = -1$ and $\cos \theta \cot \frac{\theta}{2} + \sin \theta = \cot \frac{\theta}{2}$ so equation (1) on the right hand side simplifies to $c_1 = \frac{1}{2}(a_1 - \cot \frac{\theta}{2} a_2)$ and matches the left hand side of equation (1).

For equation (2), we get:

$$\begin{aligned}
& \frac{1}{2} \cot \frac{\theta}{2} a_1 + \frac{1}{2} a_2 \\
&= \sin \theta (\frac{1}{2}(a_1 - \cot \frac{\theta}{2} a_2)) + \cos \theta (\frac{1}{2} \cot \frac{\theta}{2} a_1 + \frac{1}{2} a_2) + a_2 \\
&= (\frac{\sin \theta}{2} + (\frac{1}{2} \cos \theta \cot \frac{\theta}{2})) a_1 + ((\frac{-1}{2} \sin \theta \cot \frac{\theta}{2} + \frac{\cos \theta}{2} + 1) a_2
\end{aligned}$$

Thus, the right hand side of equation (2) simplifies and $c_2 = \frac{1}{2} \cot \frac{\theta}{2} a_1 + \frac{1}{2} a_2$.

It is then clear that the unique fixed point is (c_1, c_2) where $\theta \neq k2\pi$ because $\cot \frac{\theta}{2}$ is undefined for where θ is a multiple of 2π .

(2)

$$\begin{pmatrix} y'_1 + c_1 \\ y'_2 + c_2 \end{pmatrix} = \begin{pmatrix} \cos \theta & -\sin \theta \\ \sin \theta & \cos \theta \end{pmatrix} \begin{pmatrix} x'_1 + c_1 \\ x'_2 + c_2 \end{pmatrix} + \begin{pmatrix} a_1 \\ a_2 \end{pmatrix}$$

$$y'_1 + \frac{1}{2}(a_1 - \cot \frac{\theta}{2} a_2) = \cos \theta x'_1 + \cos \theta (\frac{1}{2}(a_1 - \cot \frac{\theta}{2} a_2)) - \sin \theta x'_2 - \sin \theta (\frac{1}{2}(\cot \frac{\theta}{2} a_1 + a_2)) + a_1$$

$$= \cos \theta x'_1 - \sin \theta x'_2 + (\frac{\cos \theta}{2} + 1 - (\frac{\sin \theta \cot \frac{\theta}{2}}{2})) a_1 - \frac{1}{2} (\cos \theta \cot \frac{\theta}{2} + \sin \theta) a_2$$

Using $\cos \theta - \sin \theta \cot \frac{\theta}{2} = -1$ and $\cos \theta \cot \frac{\theta}{2} + \sin \theta = \cot \frac{\theta}{2}$, the $\frac{1}{2}(a_1 - \cot \frac{\theta}{2} a_2)$ cancel out from both sides of the equation and then

$$y'_1 = \cos \theta x'_1 - \sin \theta x'_2$$

$$y'_2 + c_2 = \sin \theta (x'_1 + c_1) + \cos \theta (x'_2 + c_2) + a_2$$

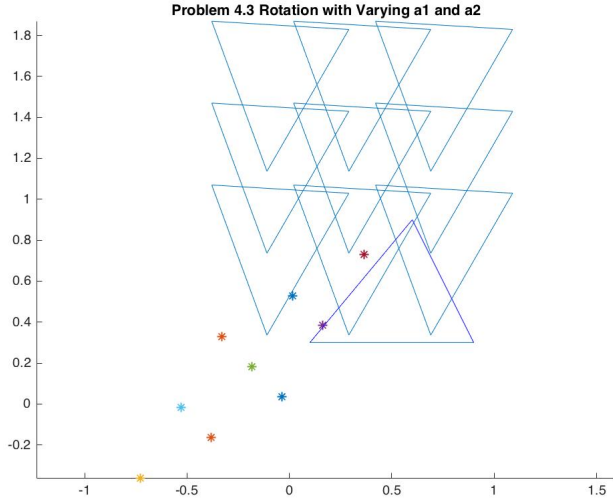
By substituting $\frac{1}{2}(\cot\frac{\theta}{2}a_1 + a_2)$ for c_2 and $\frac{1}{2}(-\cot\frac{\theta}{2}a_2 + a_1)$ for c_1 , we get

$$y'_2 = \sin\theta x'_1 + \cos\theta x'_2$$

Thus, the original affine map becomes

$$\begin{pmatrix} y'_1 \\ y'_2 \end{pmatrix} = R_\theta \begin{pmatrix} x'_1 \\ x'_2 \end{pmatrix}$$

(3) We showed the action of the affine map $R_{\theta,(a_1,a_2)}$ on a triangle for $\theta = \pi/3$ and various values of (a_1, a_2) . The code is included in our Appendix.



The 9 centers of rotation in the figure are represented by *.

When $\theta = k2\pi$, we have $\cos\theta = 1$ and $\sin\theta = 0$, so $y_1 = x_1 + a_1$ and $y_2 = x_2 + a_2$ and this indicates the transformation is a translation.

(4)

$$R_{\theta,(a_1,a_2)}$$

$$\begin{pmatrix} y_1 \\ y_2 \\ 1 \end{pmatrix} = \begin{pmatrix} \cos\theta & -\sin\theta & a_1 \\ \sin\theta & \cos\theta & a_2 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ 1 \end{pmatrix}$$

$$R_{-\theta,(b_1,b_2)}$$

$$\begin{pmatrix} y_1 \\ y_2 \\ 1 \end{pmatrix} = \begin{pmatrix} \cos(-\theta) & -\sin(-\theta) & b_1 \\ \sin(-\theta) & \cos(-\theta) & b_2 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ 1 \end{pmatrix} = \begin{pmatrix} \cos(\theta) & \sin(\theta) & b_1 \\ -\sin(\theta) & \cos(\theta) & b_2 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ 1 \end{pmatrix}$$

$$\begin{aligned}
R_{\theta,(a_1,a_2)} \cdot R_{-\theta,(b_1,b_2)} &= \begin{pmatrix} \cos \theta & -\sin \theta & a_1 \\ \sin \theta & \cos \theta & a_2 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} \cos(\theta) & \sin(\theta) & b_1 \\ -\sin(\theta) & \cos(\theta) & b_2 \\ 0 & 0 & 1 \end{pmatrix} \\
&= \begin{pmatrix} \cos^2 \theta + \sin^2 \theta & \cos \theta \sin \theta - \cos \theta \sin \theta & \cos \theta b_1 - \sin \theta b_2 + a_1 \\ \cos \theta \sin \theta - \cos \theta \sin \theta & \sin^2 \theta + \cos^2 \theta & \sin \theta b_1 + \cos \theta b_2 + a_2 \\ 0 & 0 & 1 \end{pmatrix} \\
&= \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{pmatrix}
\end{aligned}$$

So $\cos \theta b_1 - \sin \theta b_2 + a_1 = 0$ and $\sin \theta b_1 + \cos \theta b_2 + a_2 = 0$.

Solve for b_1 ,

$$\begin{aligned}
b_1 &= \frac{-a_1 + \sin \theta b_2}{\cos \theta} \\
b_1 &= \frac{-a_1}{\cos \theta} + \frac{\sin \theta b_2}{\cos \theta} \\
b_1 &= -\sec \theta a_1 + \tan \theta b_2
\end{aligned}$$

Solve for b_2 ,

$$\begin{aligned}
b_2 &= \frac{-a_2 + \sin \theta b_1}{\cos \theta} \\
b_2 &= \frac{-a_2}{\cos \theta} + \frac{\sin \theta b_1}{\cos \theta} \\
b_2 &= \sec \theta a_2 - \tan \theta b_1
\end{aligned}$$

Now plug in b_2 into b_1 .

$$\begin{aligned}
b_1 &= -\sec \theta a_1 + \tan \theta (\sec \theta a_2 - \tan \theta b_1) \\
b_1 &= \sec \theta a_1 - \tan \theta \sec \theta a_2 - \tan^2 \theta b_1 \\
(1 - \tan^2 \theta) b_1 &= \sec \theta a_1 - \tan \theta \sec \theta a_2 \\
b_1 &= \frac{-\tan \theta}{\sec \theta} a_2 - \cos \theta a_1 \\
b_1 &= -\sin \theta a_2 - \cos \theta a_1
\end{aligned}$$

Now plug b_1 into b_2 we get, $b_2 = \sin \theta a_1 - \cos \theta a_1$.

The final answer for b_1 and b_2 in terms of θ , a_1 , and a_2 is,

$$b_1 = -\sin \theta a_2 - \cos \theta a_1$$

$$b_2 = \sin \theta a_1 - \cos \theta a_1$$

(5) $R_{\beta,(b_1,b_2)} :$

$$\begin{pmatrix} y_1 \\ y_2 \\ 1 \end{pmatrix} = \begin{pmatrix} \cos \beta & -\sin \beta & b_1 \\ \sin \beta & \cos \beta & b_2 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ 1 \end{pmatrix}$$

$R_{\alpha,(a_1,a_2)} :$

$$\begin{pmatrix} y_1 \\ y_2 \\ 1 \end{pmatrix} = \begin{pmatrix} \cos\alpha & -\sin\alpha & a_1 \\ \sin\alpha & \cos\alpha & a_2 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ 1 \end{pmatrix}$$

$$\begin{aligned} & R_{\beta,(b_1,b_2)} \circ R_{\alpha,(a_1,a_2)} \rightarrow \\ & \begin{pmatrix} \cos\beta & -\sin\beta & b_1 \\ \sin\beta & \cos\beta & b_2 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} \cos\alpha & -\sin\alpha & a_1 \\ \sin\alpha & \cos\alpha & a_2 \\ 0 & 0 & 1 \end{pmatrix} \\ & = \begin{pmatrix} \cos\beta\cos\alpha - \sin\beta\sin\alpha & -\cos\beta\sin\alpha - \sin\beta\cos\alpha & \cos\beta a_1 - \sin\beta a_2 + b_1 \\ \sin\beta\cos\alpha + \cos\beta\sin\alpha & -\sin\beta\sin\alpha + \cos\beta\cos\alpha & \sin\beta a_1 + \cos\beta a_2 + b_2 \\ 0 & 0 & 1 \end{pmatrix} \end{aligned}$$

Using the trig identities from part 4, we get:

$$\begin{pmatrix} \cos(\alpha + \beta) & -\sin(\alpha + \beta) & t_1 \\ \sin(\alpha + \beta) & \cos(\alpha + \beta) & t_2 \\ 0 & 0 & 1 \end{pmatrix}$$

Indeed, this matrix represents $R_{\alpha+\beta,(t_1,t_2)}$ where $t_1 = \cos\beta a_1 - \sin\beta a_2 + b_1$ and $t_2 = \sin\beta a_1 + \cos\beta a_2 + b_2$.

Furthermore,

$$\begin{aligned} & R_{\beta,(b_1,b_2)} \circ R_{\alpha} \rightarrow \\ & \begin{pmatrix} \cos\beta & -\sin\beta & b_1 \\ \sin\beta & \cos\beta & b_2 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} \cos\alpha & -\sin\alpha & 0 \\ \sin\alpha & \cos\alpha & 0 \\ 0 & 0 & 1 \end{pmatrix} \\ & = \begin{pmatrix} \cos(\alpha + \beta) & -\sin(\alpha + \beta) & b_1 \\ \sin(\alpha + \beta) & \cos(\alpha + \beta) & b_2 \\ 0 & 0 & 1 \end{pmatrix} \end{aligned}$$

However, $R_{\alpha} \circ R_{\beta,(b_1,b_2)} \rightarrow$

$$\begin{aligned} & \begin{pmatrix} \cos\alpha & -\sin\alpha & 0 \\ \sin\alpha & \cos\alpha & 0 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} \cos\beta & -\sin\beta & b_1 \\ \sin\beta & \cos\beta & b_2 \\ 0 & 0 & 1 \end{pmatrix} \\ & = \begin{pmatrix} \cos(\alpha + \beta) & -\sin(\alpha + \beta) & \cos\alpha b_1 - \sin\alpha b_2 \\ \sin(\alpha + \beta) & \cos(\alpha + \beta) & \sin\alpha b_1 + \cos\alpha b_2 \\ 0 & 0 & 1 \end{pmatrix} \end{aligned}$$

so generally,

$$R_{\beta,(b_1,b_2)} \circ R_{\alpha} \neq R_{\alpha} \circ R_{\beta,(b_1,b_2)}$$

Since we show that $R_{\beta,(b_1,b_2)} \circ R_{\alpha} \neq R_{\alpha} \circ R_{\beta,(b_1,b_2)}$, the commutative property does not hold so the maps form a nonabelian group.

When $\alpha + \beta = k2\pi$, $R_{\beta,(b_1,b_2)} \circ R_{\alpha,(a_1,a_2)}$ is a translation since $\cos(\alpha + \beta) = 1$ and $\sin(\alpha + \beta) = 0$ so the map corresponding to $R_{\beta,(b_1,b_2)} \circ R_{\alpha,(a_1,a_2)}$ becomes:

$$\begin{pmatrix} 1 & 0 & t_1 \\ 0 & 1 & t_2 \\ 0 & 0 & 1 \end{pmatrix}$$

which represents a translation when applied to a vector. In any other case where $\alpha + \beta \neq k2\pi$, the map will not be a translation.

When $(a_1, a_2) = (0, 0)$, we can substitute into the equation for the center of rotation and find that $(c_1, c_2) = (0, 0)$.

When $\alpha + \beta = k2\pi$, the translation vector (t_1, t_2) is defined above where $t_1 = \cos\beta a_1 - \sin\beta a_2 + b_1$ and $t_2 = \sin\beta a_1 + \cos\beta a_2 + b_2$.

Problem B5 (80 pts).

(1) Because U is a subspace of \mathbb{R}^n , then $0 \in U$, we have $a = a + 0 \in \mathcal{A}$

Affine subspace of dimension 0 are points.

Affine subspace of dimension 1 are lines.

Affine subspace of dimension 2 are planes.

Any $a + u \in \mathcal{A}$, $a + v \in \mathcal{A}$, then the affine combination is $\lambda(a + u) + (1 - \lambda)(a + v) = a + \lambda u + (1 - \lambda)v$, because U is subspace of \mathbb{R}^n , $\lambda u + (1 - \lambda)v \in U$, then $a + \lambda u + (1 - \lambda)v \in \mathcal{A} \Rightarrow \lambda(a + u) + (1 - \lambda)(a + v) \in \mathcal{A}$. Affine subspace is closed under affine combinations.

(2) At least from (1) we know $a \in \mathcal{A}$, \mathcal{A} is not empty. For any $b \in \mathcal{A}$, we can find u , write as $b = a + u$. Then $b - a \in U$, $a + U = a + b - a + U = b + U$.

(3) Choose $x - a \in U_a$, $y - a \in U_a$, $\lambda, \mu \in \mathbb{R}$, then compute $\lambda(x - a) + \mu(y - a) = \frac{1}{\lambda + \mu}(\frac{\lambda}{\lambda + \mu}(x - a) + \frac{\mu}{\lambda + \mu}(y - a)) = \frac{\lambda}{\lambda + \mu}x + \frac{\mu}{\lambda + \mu}y - a$. Because \mathcal{A} is closed under affine combinations, we have $\frac{\lambda}{\lambda + \mu}x + \frac{\mu}{\lambda + \mu}y \in \mathcal{A}$, then $\lambda(x - a) + \mu(y - a) = \frac{\lambda}{\lambda + \mu}x + \frac{\mu}{\lambda + \mu}y - a \in \mathbb{R}^n$, U_a is a subspace of \mathbb{R}^n .

For any $u \in U_a$, we can write as $u = x - a = x + (b - a) - b$. The sum of coefficients of x, b, a is $1 - 1 + 1 = 1$, and \mathcal{A} is closed under affine combinations, then $u = x + (b - a) - b \in \mathcal{A} - b \Rightarrow u \in U_b$. U_a does not depend on the choice of $a \in \mathcal{A}$, $U_a = U_b$ for all $a, b \in \mathcal{A}$. So $U_a = U = \{y - x \in \mathbb{R}^n \mid x, y \in \mathcal{A}\}$ and $\mathcal{A} = a + U$, for any $a \in \mathcal{A}$.

(4) If $\mathcal{A} \cap \mathcal{B} = (x)$, then we can find $x = a + u = b + v$ where $a \in \mathcal{A}, b \in \mathcal{B}, u, v \in U$. Write $b = a + u - v$, thus $b \in \mathcal{A} \Rightarrow \mathcal{A} = \mathcal{B}$, which is against $\mathcal{A} \neq \mathcal{B}$. We have $\mathcal{A} \cap \mathcal{B} = \emptyset$ if $\mathcal{A} \neq \mathcal{B}$ and \mathcal{A}, \mathcal{B} are parallel.

Problem B6 (120 pts). (Affine frames and affine maps)
(1)

We can write the λ 's and u 's as a unique linear combination such that,

$$\lambda_0 u_0 + \dots + \lambda_n u_n = 0$$

Since this is true, the only value for $\sum_i \lambda_i$ is 0. We can rewrite this unique linear combination by subtracting u_0 from each u_i to get

$$\lambda_1(u_1 - u_0) + \dots + \lambda_n(u_n - u_0) + \sum_i^n (u_i + u_0) = 0$$

Since $\sum_i \lambda_i = 0$, the linear combination of the difference between $(u_i - u_0)$ is also linearly independent.

The subset of a linearly independent set of vectors is also a linearly independent set, so

$$\lambda_1(u_1 - u_0) + \dots + \lambda_m(u_m - u_0) + \sum_i^m (u_i + u_0) = 0$$

where $m \leq n$ is linearly independent. Since the difference between the subset of vectors are linearly independent, then $\sum_i \lambda_i = 0$ must be true. So u_0 can be added to

$$\lambda_1(u_1 - u_0) + \dots + \lambda_m(u_m - u_0) + \sum_i^m (u_i + u_0) = 0$$

to get the linear combination,

$$\lambda_0 \hat{u}_0 + \lambda_1 \hat{u}_1 + \dots + \lambda_m \hat{u}_m = 0$$

Since $\sum_i \lambda_i = 0$ is still true, then $\hat{u}_0, \dots, \hat{u}_m$ are linearly independent.

(2)

We proved in 6.1 that the linear combination

$$\lambda_0 \hat{u}_0 + \lambda_1 \hat{u}_1 + \dots + \lambda_m \hat{u}_m = 0$$

is linearly independent and $\sum_i \lambda_i = 0$.

We can rewrite the linear combination by subtracting some u_i from each u to get

$$\lambda_0(\hat{u}_0 - \hat{u}_i) + \lambda_1(\hat{u}_1 - \hat{u}_i) + \dots + \lambda_m(\hat{u}_m - \hat{u}_i) = 0$$

The linear combination can be written by factoring out the u_i to get

$$\lambda_0 \hat{u}_0 + \lambda_1 \hat{u}_1 + \dots + \lambda_m \hat{u}_m - \sum_i \lambda_i \hat{u}_i = 0$$

The first set of terms of $m - 1$ terms in the equations are a subset of the original m terms from where we started. Since a subset of a linearly independent set is linearly independent, then the $m - 1$ terms are linearly independent and $\sum_i^{m-1} \lambda_i = 0$. This leaves the last term in the equation, $\sum_i \lambda_i \hat{u}_i$. We know that the u 's are unique, so they cannot equal 0, this means that the λ_i 's = 0. So, the m vectors $u_j - u_i$ for $j \in \{0, \dots, m\}$ with $j - i \neq 0$ are linearly independent.

Any $m + 1$ vectors (u_0, u_1, \dots, u_m) such that the $m + 1$ vectors $(\hat{u}_0, \dots, \hat{u}_m)$ are linearly independent are said to be *affinely independent*.

From (1) and (2), the vector (u_0, u_1, \dots, u_m) are affinely independent iff for any any choice of i , with $0 \leq i \leq m$, the m vectors $u_j - u_i$ for $j \in \{0, \dots, m\}$ with $j - i \neq 0$ are linearly independent. If $m = n$, we say that $n + 1$ affinely independent vectors (u_0, u_1, \dots, u_n) form an *affine frame* of \mathbb{R}^n .

(3)

(3.1)

Because (u_0, u_1, \dots, u_n) is an affine frame of \mathbb{R}^n , then from above we can get a basis in \mathbb{R}^{n+1} , which is $\hat{u}_0, \dots, \hat{u}_n$. For any $v \in \mathbb{R}^n$, we denote $\hat{v} = (v, 1)$, then it can be uniquely written as the combination of (\hat{u}_i) , such that $\hat{v} = \sum_i \lambda_i \hat{u}_i$. From the last row of equation, we know there should be $\sum_i \lambda_i = 1$. Along with $v = \sum_i \lambda_i u_i$, we can get the conclusion.

From $e_i = u_i - u_0$, for $i = 1, \dots, n$, substitute u_i with e_i , we get $v = \sum_{i=1}^n \lambda_i (e_i + u_0) + \lambda_0 u_0 = \sum_i \lambda_i u_0 + \sum_{i=1}^n \lambda_i e_i = u_0 + \sum_{i=1}^n \lambda_i e_i$. When $u_i = u_0 + e_i$ for $i = 1, \dots, n$, denote the vector $\hat{u}_i = (u_0 + e_i, 1)$.

(3.2)

Suppose $\sum_i \lambda_i \hat{u}_i = 0$, such that

$$\begin{aligned} \sum_i \lambda_i u_0 + \sum_i \lambda_i e_i &= 0 \\ \sum_i \lambda_i &= 0 \\ \Rightarrow \sum_i \lambda_i e_i &= 0 \\ \Rightarrow \lambda_i &= 0, \quad i = 1, 2, \dots, n \end{aligned}$$

So $\hat{u}_0, \dots, \hat{u}_n$ are linearly independent, thus (u_0, u_1, \dots, u_n) is an affine frame of \mathbb{R}^n . From above, for any $v \in \mathbb{R}^n$, there is $v = u_0 + x_1 e_1 + \dots + x_n e_n$, substitute e_i with u_i get

$$v = (1 - (x_1 + \dots + x_n))u_0 + x_1 u_1 + \dots + x_n u_n,$$

Conversely, for any vector $u_0 \in \mathbb{R}^n$ and for any basis (e_1, \dots, e_n) of \mathbb{R}^n , let $u_i = u_0 + e_i$ for $i = 1, \dots, n$. Prove that (u_0, u_1, \dots, u_n) is an affine frame of \mathbb{R}^n , and for any $v \in \mathbb{R}^n$, if

$$v = u_0 + x_1 e_1 + \dots + x_n e_n,$$

with $(x_1, \dots, x_n) \in \mathbb{R}^n$ (unique), then

$$v = (1 - (x_1 + \dots + x_n))u_0 + x_1u_1 + \dots + x_nu_n,$$

so that $(1 - (x_1 + \dots + x_n), x_1, \dots, x_n)$, are the barycentric coordinates of v w.r.t. the affine frame (u_0, u_1, \dots, u_n) .

(3.3)

The above shows that there is a one-to-one correspondence between affine frames (u_0, \dots, u_n) and pairs $(u_0, (e_1, \dots, e_n))$, with (e_1, \dots, e_n) a basis. Given an affine frame (u_0, \dots, u_n) , we obtain the basis (e_1, \dots, e_n) with $e_i = u_i - u_0$, for $i = 1, \dots, n$; given the pair $(u_0, (e_1, \dots, e_n))$ where (e_1, \dots, e_n) is a basis, we obtain the affine frame (u_0, \dots, u_n) , with $u_i = u_0 + e_i$, for $i = 1, \dots, n$. There is also a one-to-one correspondence between barycentric coordinates w.r.t. the affine frame (u_0, \dots, u_n) and standard coordinates w.r.t. the basis (e_1, \dots, e_n) . The barycentric coordinates $(\lambda_0, \lambda_1, \dots, \lambda_n)$ of v (with $\lambda_0 + \lambda_1 + \dots + \lambda_n = 1$) yield the standard coordinates $(\lambda_1, \dots, \lambda_n)$ of $v - u_0$; the standard coordinates (x_1, \dots, x_n) of $v - u_0$ yield the barycentric coordinates $(1 - (x_1 + \dots + x_n), x_1, \dots, x_n)$ of v .

(4)

We can write $f(u) = f(u_0\lambda_0 + u_1\lambda_1 + \dots + u_n\lambda_n) = \lambda_0f(u_0) + \lambda_1f(u_1) + \dots + \lambda_nf(u_n) = \lambda_0v_0 + \lambda_1v_1 + \dots + \lambda_nv_n$. So we can define a function $f : \mathbb{R}^n \rightarrow \mathbb{R}^m$ as above, such that $f(\lambda_0u_0 + \lambda_1u_1 + \dots + \lambda_nu_n) = \lambda_0v_0 + \lambda_1v_1 + \dots + \lambda_nv_n$. The function is unique, however we have to check if it is affine.

To check if it is affine, we first pick $w_1, \dots, w_p \in \mathbb{R}^n$ and a set of $\mu_1 + \dots + \mu_p = 1$. We can write linear combination of μ and w , such that, $f(\mu_1w_1 + \dots + \mu_pw_p) = \mu_1f(w_1) + \dots + \mu_pf(w_p)$. Now we can rewrite all the w 's as the affine frame, such that,

$$w_1 = \sum_{i=0}^n \lambda_i^1 \mu_i, \dots, w_p = \sum_{i=0}^n \lambda_i^p \mu_i$$

Now we can expand and regroup in terms of the frame vectors.

$$f(u_1(\sum_{i=0}^n \lambda_i^1 \mu_i)) + \dots + f(u_p(\sum_{i=0}^n \lambda_i^p \mu_i)) = f((\sum_{j=1}^p \mu_j \lambda_0^j)u_0, \dots, (\sum_{j=1}^p \mu_j \lambda_n^j)u_n)$$

Now we take the coefficient out and set equal to 1, this works out because $\sum_i \lambda_i = 1$ and $\sum_i \mu_i = 1$.

$$1 = (\sum_{j=1}^p \mu_j \lambda_0^j)v_0 + \dots + (\sum_{j=1}^p \mu_j \lambda_n^j)v_n$$

Now regroup,

$$1 = \mu_1(\sum_{i=1}^n \lambda_i^1 v_i) + \dots + \mu_p(\sum_{i=1}^n \lambda_i^p v_i)$$

Because of our original definition,

$$w_1 = \sum_{i=0}^n \lambda_i^0 \mu_i, \dots, w_p = \sum_{i=0}^n \lambda_i^p \mu_i$$

we can conclude that

$$1 = \mu_1 f(w_1) + \dots + \mu_p f(w_p)$$

so f is an affine combination.

(5) Let (a_0, \dots, a_n) be any affine frame in \mathbb{R}^n and let (b_0, \dots, b_n) be any $n+1$ points in \mathbb{R}^n . From (4), we know there is a unique affine map f such that $f(a_i) = b_i$, $i = 0, \dots, n$. From (3), we know for any b_i , we can write as the affine combination of (a_i) , such that $b_i = \sum_j \lambda_j^i a_j$, $\sum_j \lambda_j^i = 1$. Thus we can write those equations as

$$\begin{pmatrix} b_0 & b_1 & \dots & b_n \\ 1 & 1 & \dots & 1 \end{pmatrix} = \begin{pmatrix} a_0 & a_1 & \dots & a_n \\ 1 & 1 & \dots & 1 \end{pmatrix} \begin{pmatrix} \lambda_0^0 & \lambda_0^1 & \dots & \lambda_0^n \\ \lambda_1^0 & \lambda_1^1 & \dots & \lambda_1^n \\ \lambda_2^0 & \lambda_2^1 & \dots & \lambda_2^n \\ \vdots & \dots & \dots & \vdots \\ \lambda_n^0 & \lambda_n^1 & \dots & \lambda_n^n \end{pmatrix}$$

$$\Rightarrow A = (\hat{a}_0 \quad \hat{a}_1 \quad \dots \quad \hat{a}_n)^{-1} \cdot (\hat{b}_0 \quad \hat{b}_1 \quad \dots \quad \hat{b}_n)$$

the $(n+1) \times (n+1)$ matrix A corresponding to the unique affine map f such that

$$f(a_i) = b_i, \quad i = 0, \dots, n,$$

is given by

$$A = (\hat{b}_0 \quad \hat{b}_1 \quad \dots \quad \hat{b}_n) (\hat{a}_0 \quad \hat{a}_1 \quad \dots \quad \hat{a}_n)^{-1}.$$

When (a_0, \dots, a_n) is the canonical affine frame with $a_i = e_{i+1}$ for $i = 0, \dots, n-1$ and $a_n = (0, \dots, 0)$ there is

$$(\hat{a}_0 \quad \hat{a}_1 \quad \dots \quad \hat{a}_n) = \begin{pmatrix} a_0 & a_1 & \dots & a_n \\ 1 & 1 & \dots & 1 \end{pmatrix} = \begin{pmatrix} 1 & 0 & \dots & 0 & 0 \\ 0 & 1 & \dots & 0 & 0 \\ \vdots & \vdots & \ddots & 0 & 0 \\ 0 & 0 & \dots & 1 & 0 \\ 1 & 1 & \dots & 1 & 1 \end{pmatrix}$$

$$\begin{aligned}
(\hat{a}_0 \quad \hat{a}_1 \quad \cdots \quad \hat{a}_n) \cdot \begin{pmatrix} 1 & 0 & \cdots & 0 & 0 \\ 0 & 1 & \cdots & 0 & 0 \\ \vdots & \vdots & \ddots & 0 & 0 \\ 0 & 0 & \cdots & 1 & 0 \\ -1 & -1 & \cdots & -1 & 1 \end{pmatrix} &= \begin{pmatrix} 1 & 0 & \cdots & 0 & 0 \\ 0 & 1 & \cdots & 0 & 0 \\ \vdots & \vdots & \ddots & 0 & 0 \\ 0 & 0 & \cdots & 1 & 0 \\ 1 & 1 & \cdots & 1 & 1 \end{pmatrix} \cdot \begin{pmatrix} 1 & 0 & \cdots & 0 & 0 \\ 0 & 1 & \cdots & 0 & 0 \\ \vdots & \vdots & \ddots & 0 & 0 \\ 0 & 0 & \cdots & 1 & 0 \\ -1 & -1 & \cdots & -1 & 1 \end{pmatrix} \\
&= I \\
\Rightarrow (\hat{a}_0 \quad \hat{a}_1 \quad \cdots \quad \hat{a}_n)^{-1} &= \begin{pmatrix} 1 & 0 & \cdots & 0 & 0 \\ 0 & 1 & \cdots & 0 & 0 \\ \vdots & \vdots & \ddots & 0 & 0 \\ 0 & 0 & \cdots & 1 & 0 \\ -1 & -1 & \cdots & -1 & 1 \end{pmatrix}.
\end{aligned}$$

(6) Choose $u_i \in f(\mathcal{A})$, $u_i = f(a_i)$, $a_i \in \mathcal{A}$ and $\lambda_i \in \mathbb{R}$, $\sum_i \lambda_i = 1$. The affine combination of u_i is $\sum_i \lambda_i u_i = f(\sum_i \lambda_i a_i)$. Because \mathcal{A} is affine subspace then $\sum_i \lambda_i a_i \in \mathcal{A}$, which means $\sum_i \lambda_i u_i \in f(\mathcal{A})$, then $f(\mathcal{A})$ is affine subspace too. To do the same thing, $v_i \in f^{-1}(\mathcal{B})$, $v_i = f^{-1}(b_i)$, $b_i \in \mathcal{B}$ and $\mu_i \in \mathbb{R}$, $\sum_i \mu_i = 1$. The affine combination of v_i is $\sum_i \mu_i v_i = f^{-1}(\sum_i \mu_i b_i)$. Because \mathcal{B} is affine subspace then $\sum_i \mu_i b_i \in \mathcal{B}$, which means $\sum_i \mu_i v_i \in f^{-1}(\mathcal{B})$, then $f^{-1}(\mathcal{B})$ is affine subspace too.

Problem B7 (30 pts). Let A be any $n \times k$ matrix

(1) If choose $u \in \ker(A)$, $Au = 0$ then

$$\begin{aligned}
&\Rightarrow (A^\top A)u = A^\top(Au) = 0 \\
&\Rightarrow u \in \ker(A^\top A) \\
&\Rightarrow \ker(A) \subseteq \ker(A^\top A)
\end{aligned}$$

For the opposite, choose $v \in \ker(A^\top A)$ then

$$\begin{aligned}
&\Rightarrow (A^\top A)v = A^\top(Av) = 0 \\
&\Rightarrow Av \in \ker(A^\top)
\end{aligned}$$

We need to prove $u \in \ker(A)$, if not suppose $Au = x \neq 0$, then $(A^\top x)^\top = x^\top A = 0$, multiply u on both sides, we have $x^\top Au = x^\top x = 0 \Rightarrow x = 0$, which is against the assumption, thus $u \in \ker(A) \Rightarrow \ker(A^\top A) \subseteq \ker(A)$. From $\ker(A) \subseteq \ker(A^\top A)$, $\ker(A^\top A) \subseteq \ker(A)$, get $\ker(A^\top A) = \ker(A)$. From the equation $\dim(\ker(A))\text{rank}(A) = \dim(E) = k$, we can easily find $\text{rank}(A^\top A) = \text{rank}(A) = k - \dim(\ker(A)) = k - \dim(\ker(A^\top A))$. We can use the same way to prove $\ker(AA^\top) = \ker(A^\top)$ and $\text{rank}(AA^\top) = \text{rank}(A^\top)$.

(2) From above, we know $\text{rank}(A^\top A) = \text{rank}(A)$. $\text{rank}(A) \leq \min\{k, n\} = k$, because A has independent column vectors (a_i) $i = 1, 2, \dots, k$, then $\text{rank}(A) = k \Rightarrow \text{rank}(A^\top A) = k$. $A^\top A$ has full rank, it is invertible.

First we need to prove two things:

$$\begin{aligned}(AB)^\top &= B^\top A^\top \\ (A^{-1})^\top &= (A^\top)^{-1}\end{aligned}$$

Here is the simple proof:

$$\begin{aligned}(AB)_{ij}^\top &= \sum_k a_{jk} b_{ki} = \sum_k b_{ki} a_{jk} = (B^\top A^\top)_{ij} \\ (A^{-1})^\top A^\top &= (AA^{-1})^\top = I \\ \Rightarrow (A^{-1})^\top &= (A^\top)^{-1}\end{aligned}$$

Then

$$\begin{aligned}P^2 &= A(A^\top A)^{-1} A^\top \cdot A(A^\top A)^{-1} A^\top \\ &= A(A^\top A)^{-1} (A^\top A) (A^\top A)^{-1} \\ &= A(A^\top A)^{-1} A^\top \\ &= P \\ P^\top &= (A(A^\top A)^{-1} A^\top)^\top \\ &= A(A^\top A)^{-1} A^\top \\ &= A((A^\top A)^\top)^{-1} A^\top \\ &= A(A^\top A)^{-1} A^\top \\ &= P\end{aligned}$$

When $k = 1$, P is symmetric matrix with $\text{trace}(P) = 1$. If $A = \begin{pmatrix} a_1 \\ a_2 \\ \vdots \\ a_n \end{pmatrix}$ then P looks like

$$P = \frac{1}{\sum_i a_i^2} \begin{pmatrix} a_1^2 & a_1 a_2 & a_1 a_3 & \cdots & a_1 a_n \\ a_1 a_2 & a_2^2 & a_2 a_3 & \cdots & a_2 a_n \\ \vdots & \cdots & \cdots & \cdots & \vdots \\ a_1 a_n & a_2 a_n & a_3 a_n & \cdots & a_n^2 \end{pmatrix}.$$

(3) Choose any $x \in \mathbb{R}^n$, the image of P is $Px = A(A^\top A)^{-1} A^\top x = A[(A^\top A)^{-1} A^\top x]$, there is $y \in \mathbb{R}^k$ makes $Px = Ay$, so the image of P is the subspace V spanned by a_1, a_2, \dots, a_n . When $u \in U$, $u \in \ker(P)$, we can get $Pu = A(A^\top A)^{-1} A^\top u = 0$, multiply A^\top on both sides, $A^\top A(A^\top A)^{-1} A^\top u = A^\top u = 0 \Rightarrow \ker(P) \subseteq \ker(A^\top)$. So the nullspace U of P is the set of vectors such that $A^\top u = 0$. Geometric interpretation of U is that U contains vectors that are orthogonal to the image of A .

First we need to prove that for any $x \in \mathbb{R}^n$, Px is the closest vector in V . Because $(Px -$

$x)^\top(Px) = (x^\top P^\top - x^\top)Px = 0$, so $Px - x$ is perpendicular to Px , which means P is a projection of \mathbb{R}^n onto subspace spanned by $(a_i) \ i = 1, 2, \dots k$.

Then what we only need to do is to prove $V^0 = U$. Choose $u \in U$, from above we know $A^\top u = 0$, thus any $Ax \in V$ we have $(Ax)^\top y = x^\top A^\top y = 0 \Rightarrow U \subseteq V^0$. For any $v \in V^0$, we have $(Ax)^\top v = x^\top A^\top v = 0$, because we can choose any $x \in \mathbb{R}^n$, then must have the result $A^\top v = 0 \Rightarrow V^0 \subseteq U$. (Otherwise we can construct $(e_i) \ i = 1, 2, \dots n$ and then $(e_1, e_2, \dots e_n)^\top A^\top v = I \cdot A^\top v = 0$). As a conclusion $U = V^0 \Rightarrow \mathbb{R}^n = V^0 \oplus V = U \oplus V$.

TOTAL: 460 points.

APPENDIX

Problem 3.3 Code

```

1 %Theta = pi/6
2 theta = pi/6;
3 R = [cos(theta) -sin(theta);
4      sin(theta) cos(theta)];
5
6 x = [2;70;56];
7 y = [100;110;45];
8 xy = [x y];
9 Rxy = R*xy';
10 Rxy = Rxy';
11 x = Rxy(:,1);
12 y = Rxy(:,2);
13 line([x(1),x(2)], [y(1), y(2)], 'Color', 'r');
14 hold on;
15 line([x(2),x(3)], [y(2), y(3)], 'Color', 'r');
16 line([x(3),x(1)], [y(3), y(1)], 'Color', 'r');
17 hold off;
18
19 %Theta = pi/4
20 theta = pi/4;
21 R = [cos(theta) -sin(theta);
22      sin(theta) cos(theta)];
23
24 x = [2;70;56];
25 y = [100;110;45];
26 xy = [x y];
27 Rxy = R*xy';
28 Rxy = Rxy';
29 x = Rxy(:,1);

```



```

30 y = Rxy(:,2);
31 line([x(1),x(2)], [y(1), y(2)], 'Color', 'r');
32 hold on;
33 line([x(2),x(3)], [y(2), y(3)], 'Color', 'r');
34 line([x(3),x(1)], [y(3), y(1)], 'Color', 'r');
35 hold off;
36
37 %Theta = pi/3
38 theta = pi/3;
39 R = [cos(theta) -sin(theta);
40      sin(theta) cos(theta)];
41
42 x = [2;70;56];
43 y = [100;110;45];
44 xy = [x y];
45 Rxy = R*xy';
46 Rxy = Rxy';
47 x = Rxy(:,1);
48 y = Rxy(:,2);
49 line([x(1),x(2)], [y(1), y(2)], 'Color', 'r');
50 hold on;
51 line([x(2),x(3)], [y(2), y(3)], 'Color', 'r');
52 line([x(3),x(1)], [y(3), y(1)], 'Color', 'r');
53 hold off;
54
55 %Theta = pi/2
56 theta = pi/2;
57 R = [cos(theta) -sin(theta);
58      sin(theta) cos(theta)];
59
60 x = [2;70;56];
61 y = [100;110;45];
62 xy = [x y];
63 Rxy = R*xy';
64 Rxy = Rxy';
65 x = Rxy(:,1);
66 y = Rxy(:,2);
67 line([x(1),x(2)], [y(1), y(2)], 'Color', 'r');
68 hold on;
69 line([x(2),x(3)], [y(2), y(3)], 'Color', 'r');
70 line([x(3),x(1)], [y(3), y(1)], 'Color', 'r');
71 hold off;

```

Problem 4.3 Code

```

1  x = [.1;.6;.9];
2  y = [.3;.9;.3];
3  xy = [x y];
4
5  for a1= .1:.4:1
6      for a2 = .1:.4:1
7          hold on;
8          plot (x,y, 'b');
9          line ([x(1),x(3)], [y(1),y(3)]);
10
11  t = pi/3;
12
13
14  R = [cos(t) -sin(t); sin(t) cos(t)];
15
16  y1 = R*[x(1);y(1)]+ [a1;a2];
17  y2 = R*[x(2);y(2)]+ [a1;a2];
18  y3 = R*[x(3);y(3)]+ [a1;a2];
19  hold on;
20  line ([y1(1,:),y2(1,:)],[y1(2,:),y2(2,)]);
21  line ([y1(1,:),y3(1,:)],[y1(2,:),y3(2,)]);
22  line ([y2(1,:),y3(1,:)],[y2(2,:),y3(2,)]);
23  hold off;
24
25  e = (1/2)*(1/(sin(t/2)));
26  c1= e*(cos((pi/2)-(t/2))*a1 -sin((pi/2)-(t/2))*a2);
27  c2= e*(sin((pi/2)-(t/2))*a1 -cos((pi/2)-(t/2))*a2);
28  hold on;
29  plot (c1,c2, '*');
30
31  hold off;
32  axis equal
33  end
34 end

```