Course Name:Linear Algebra

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4.3 Linearly Independent Sets; Bases

- Linearly Independent Sets
  - Definition
  - Facts
  - Examples
- A Basis Set: Definition
- A Basis Set: Examples
  - Nul A: Examples and Theorem
  - Col A: Examples and Theorem
- The Spanning Set Theorem

Linearly Independent Sets

- A set of vectors $\{\mathbf{v}_1, \mathbf{v}_2, \dots, \mathbf{v}_p\}$ in a vector space V is said to be **linearly independent** if the vector equation
$$c_1\mathbf{v}_1 + c_2\mathbf{v}_2 + \cdots + c_p\mathbf{v}_p = \mathbf{0}$$
has only the trivial solution $c_1 = 0, \dots, c_p = 0$.

- The set $\{\mathbf{v}_1, \mathbf{v}_2, \dots, \mathbf{v}_p\}$ is said to be **linearly dependent** if there exists weights $c_1, \dots, c_p$,not all 0, such that
$$c_1\mathbf{v}_1 + c_2\mathbf{v}_2 + \cdots + c_p\mathbf{v}_p = \mathbf{0}.$$

The following results from Section 1.7 are still true for more general vectors spaces.

Fact 1

A set containing the zero vector is linearly dependent.

Fact 2

A set of two vectors is linearly dependent if and only if one is a multiple of the other.

Fact 3

A set containing the zero vector is linearly independent.

Example

$$\left\{ \begin{bmatrix} 1 & 2 \\ 3 & 4 \end{bmatrix}, \begin{bmatrix} 0 & 0 \\ 0 & 0 \end{bmatrix}, \begin{bmatrix} 3 & 2 \\ 3 & 0 \end{bmatrix} \right\}$$ is a linearly ________________ set.

Example

$$\left\{ \begin{bmatrix} 1 & 2 \\ 3 & 4 \end{bmatrix}, \begin{bmatrix} 3 & 6 \\ 9 & 11 \end{bmatrix} \right\}$$ is a linearly ________________ set

since $\begin{bmatrix} 3 & 6 \\ 9 & 11 \end{bmatrix}$ is not a multiple of $\begin{bmatrix} 1 & 2 \\ 3 & 4 \end{bmatrix}$.

Theorem (4)

An indexed set $\{\mathbf{v}_1, \mathbf{v}_2, \ldots, \mathbf{v}_p\}$ of two or more vectors, with $\mathbf{v}_1 \neq \mathbf{0}$, is linearly dependent if and only if some vector $\mathbf{v}_j$ $(j > 1)$ is a linear combination of the preceding vectors $\mathbf{v}_1, \ldots, \mathbf{v}_{j-1}$.

Example

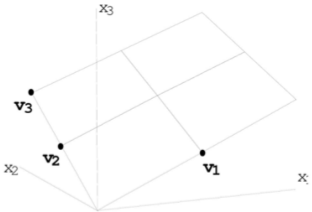
Let $\{\mathbf{p}_1, \mathbf{p}_2, \mathbf{p}_3\}$ be a set of vectors in $\mathbf{P}_2$ where $\mathbf{p}_1(t) = t$, $\mathbf{p}_2(t) = t^2$, and $\mathbf{p}_3(t) = 4t + 2t^2$. Is this a linearly dependent set?

Solution: Since $\mathbf{p}_3 = \_\_\_\_\_\mathbf{p}_1 + \_\_\_\_\_\mathbf{p}_2$, $\{\mathbf{p}_1, \mathbf{p}_2, \mathbf{p}_3\}$ is a linearly _______________________ set.

Let H be the plane illustrated below. Which of the following are valid descriptions of H?

(a) $H =$Span$\{\mathbf{v}_1, \mathbf{v}_2\}$ (b) $H =$Span$\{\mathbf{v}_1, \mathbf{v}_3\}$

(c) $H =$Span$\{\mathbf{v}_2, \mathbf{v}_3\}$ (d) $H =$Span$\{\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3\}$



A *basis set* is an "efficient" spanning set containing no unnecessary vectors. In this case, we would consider the linearly independent sets $\{\mathbf{v}_1, \mathbf{v}_2\}$ and $\{\mathbf{v}_1, \mathbf{v}_3\}$ to both be examples of basis sets or bases (plural for basis) for H.

A Basis Set

Let H be a subspace of a vector space V. An indexed set of vectors $\beta = \{\mathbf{b}_1, \ldots, \mathbf{b}_p\}$ in V is a basis for H if

i. β is a linearly independent set, and

ii. $H = \text{Span}\{\mathbf{b}_1, \ldots, \mathbf{b}_p\}$.

Example

Let $\mathbf{e}_1 = \begin{bmatrix} 1 \\ 0 \\ 0 \end{bmatrix}$, $\mathbf{e}_2 = \begin{bmatrix} 0 \\ 1 \\ 0 \end{bmatrix}$, $\mathbf{e}_3 = \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}$. Show that $\{\mathbf{e}_1, \mathbf{e}_2, \mathbf{e}_3\}$ is a basis for $\mathbf{R}^3$. The set $\{\mathbf{e}_1, \mathbf{e}_2, \mathbf{e}_3\}$ is called a **standard basis** for $\mathbf{R}^3$.

Solutions: (Review the IMT, page 112)

Let $A = \begin{bmatrix} \mathbf{e}_1 & \mathbf{e}_2 & \mathbf{e}_3 \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$.

Since A has 3 pivots,

- the columns of A are linearly _____________________ by the IMT,
- and the columns of A ____________ ________ by IMT;
- therefore, $\{\mathbf{e}_1, \mathbf{e}_2, \mathbf{e}_3\}$ is a basis for $\mathbf{R}^3$.

Example

Let $S = \{1,\ t,\ t^2,\ \ldots, t^n\}$. Show that S is a basis for $\mathbf{P}_n$.

Solution: Any polynomial in $\mathbf{P}_n$ is in span of S.To show that S is linearly independent, assume

$$c_0 \cdot 1 + c_1 \cdot t + \cdots + c_n \cdot t^n = \mathbf{0}.$$

Then $c_0 = c_1 = \cdots = c_n = 0$. Hence S is a basis for $\mathbf{P}_n$.

Example

Let $\mathbf{v}_1 = \begin{bmatrix} 1 \\ 2 \\ 0 \end{bmatrix}$, $\mathbf{v}_2 = \begin{bmatrix} 0 \\ 1 \\ 1 \end{bmatrix}$, $\mathbf{v}_3 = \begin{bmatrix} 1 \\ 0 \\ 3 \end{bmatrix}$.

Is $\{\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3\}$ a **basis** for $\mathbf{R}^3$?

Solution: Let $A = [\mathbf{v}_1 \ \ \mathbf{v}_2 \ \ \mathbf{v}_3] = \begin{bmatrix} 1 & 0 & 1 \\ 2 & 1 & 0 \\ 0 & 1 & 3 \end{bmatrix}$. By row reduction,

$$\begin{bmatrix} 1 & 0 & 1 \\ 2 & 1 & 0 \\ 0 & 1 & 3 \end{bmatrix} \backsim \begin{bmatrix} 1 & 0 & 1 \\ 0 & 1 & -2 \\ 0 & 1 & 3 \end{bmatrix} \backsim \begin{bmatrix} 1 & 0 & 1 \\ 0 & 1 & -2 \\ 0 & 0 & 5 \end{bmatrix}$$

and since there are 3 pivots, the columns of A are linearly independent and they span $\mathbf{R}^3$ by the IMT. Therefore $\{\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3\}$ is a **basis** for $\mathbf{R}^3$.

Example

Explain why each of the following sets is **not** a basis for $\mathbf{R}^3$.

(a) $\left\{ \begin{bmatrix} 1 \\ 2 \\ 3 \end{bmatrix}, \begin{bmatrix} 4 \\ 5 \\ 7 \end{bmatrix}, \begin{bmatrix} 0 \\ 1 \\ 0 \end{bmatrix}, \begin{bmatrix} 1 \\ -3 \\ 7 \end{bmatrix} \right\}$

Example

(b) $\left\{ \begin{bmatrix} 1 \\ 2 \\ 3 \end{bmatrix}, \begin{bmatrix} 4 \\ 5 \\ 6 \end{bmatrix} \right\}$

Example

Find a basis for Nul A where

$$A = \begin{bmatrix} 3 & 6 & 6 & 3 & 9 \\ 6 & 12 & 13 & 0 & 3 \end{bmatrix}.$$

Solution: Row reduce $\begin{bmatrix} A & \mathbf{0} \end{bmatrix}$:

$$\begin{bmatrix} 1 & 2 & 0 & 13 & 33 & 0 \\ 0 & 0 & 1 & -6 & -15 & 0 \end{bmatrix} \implies \begin{array}{l} x_1 = -2x_2 - 13x_4 - 33x_5 \\ x_3 = 6x_4 + 15x_5 \\ x_2,\ x_4 \text{ and } x_5 \text{ are free} \end{array}$$

$$\begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ x_4 \\ x_5 \end{bmatrix} = \begin{bmatrix} -2x_2 - 13x_4 - 33x_5 \\ x_2 \\ 6x_4 + 15x_5 \\ x_4 \\ x_5 \end{bmatrix} =$$

$$x_2 \underset{\substack{\uparrow \\ \mathbf{u}}}{\begin{bmatrix} -2 \\ 1 \\ 0 \\ 0 \\ 0 \end{bmatrix}} + x_4 \underset{\substack{\uparrow \\ \mathbf{v}}}{\begin{bmatrix} -13 \\ 0 \\ 6 \\ 1 \\ 0 \end{bmatrix}} + x_5 \underset{\substack{\uparrow \\ \mathbf{w}}}{\begin{bmatrix} -33 \\ 0 \\ 15 \\ 0 \\ 1 \end{bmatrix}}$$

Therefore $\{\mathbf{u}, \mathbf{v}, \mathbf{w}\}$ is a spanning set for Nul A. In the last section we observed that this set is linearly independent. Therefore $\{\mathbf{u}, \mathbf{v}, \mathbf{w}\}$ is a basis for Nul A. The technique used here always provides a linearly independent set.

A basis can be constructed from a spanning set of vectors by discarding vectors which are linear combinations of preceding vectors in the indexed set.

Example

Suppose $\mathbf{v}_1 = \begin{bmatrix} -1 \\ 0 \end{bmatrix}$, $\mathbf{v}_2 = \begin{bmatrix} 0 \\ -1 \end{bmatrix}$ and $\mathbf{v}_3 = \begin{bmatrix} -2 \\ -3 \end{bmatrix}$.

Solution: If $\mathbf{x}$ is in Span$\{\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3\}$, then

$$\mathbf{x} = c_1\mathbf{v}_1 + c_2\mathbf{v}_2 + c_3\mathbf{v}_3 = c_1\mathbf{v}_1 + c_2\mathbf{v}_2 + c_3\left(\_\_\_\_\_\mathbf{v}_1 + \_\_\_\_\_\mathbf{v}_2\right)$$

$$= \_\_\_\_\_\_\_\_\_\_\_\_\mathbf{v}_1 + \_\_\_\_\_\_\_\_\_\_\_\_\mathbf{v}_2$$

Therefore,

$$\text{Span}\{\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3\} = \text{Span}\{\mathbf{v}_1, \mathbf{v}_2\}.$$

Theorem (5 The Spanning Set Theorem)

Let

$$S = \{\mathbf{v}_1, \ldots, \mathbf{v}_p\}$$

be a set in V and let

$$H = \mathrm{Span}\{\mathbf{v}_1, \ldots, \mathbf{v}_p\}.$$

a. *If one of the vectors in S - say $\mathbf{v}_k$ - is a linear combination of the remaining vectors in S, then the set formed from S by removing $\mathbf{v}_k$ still spans H.*

b. *If $H \neq \{\mathbf{0}\}$, some subset of S is a basis for H.*

Example

Find a basis for Col A, where

$$A = [\mathbf{a}_1 \quad \mathbf{a}_2 \quad \mathbf{a}_3 \quad \mathbf{a}_4] = \begin{bmatrix} 1 & 2 & 0 & 4 \\ 2 & 4 & -1 & 3 \\ 3 & 6 & 2 & 22 \\ 4 & 8 & 0 & 16 \end{bmatrix}.$$

Solution: Row reduce:

$$[\mathbf{a}_1 \quad \mathbf{a}_2 \quad \mathbf{a}_3 \quad \mathbf{a}_4] \sim \cdots \sim \begin{bmatrix} 1 & 2 & 0 & 4 \\ 0 & 0 & 1 & 5 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix} = [\mathbf{b}_1 \quad \mathbf{b}_2 \quad \mathbf{b}_3 \quad \mathbf{b}_4]$$

Note that

$$\mathbf{b}_2 = \_\_\_\_\mathbf{b}_1 \qquad \text{and} \qquad \mathbf{a}_2 = \_\_\_\_\mathbf{a}_1$$

$$\mathbf{b}_4 = 4\mathbf{b}_1 + 5\mathbf{b}_3 \qquad \text{and} \qquad \mathbf{a}_4 = 4\mathbf{a}_1 + 5\mathbf{a}_3$$

$\mathbf{b}_1$ and $\mathbf{b}_3$ are not multiples of each other

$\mathbf{a}_1$ and $\mathbf{a}_3$ are not multiples of each other

Elementary row operations on a matrix do not affect the linear dependence relations among the columns of the matrix.

Therefore

$$\operatorname{Span}\{\mathbf{a}_1, \mathbf{a}_2, \mathbf{a}_3, \mathbf{a}_4\} = \operatorname{Span}\{\mathbf{a}_1, \mathbf{a}_3\}$$

and $\{\mathbf{a}_1, \mathbf{a}_3\}$ is a basis for Col A.

Theorem (6)

The pivot columns of a matrix A form a basis for Col A.

Example

Let $\mathbf{v}_1 = \begin{bmatrix} 1 \\ 2 \\ -3 \end{bmatrix}, \mathbf{v}_2 = \begin{bmatrix} -2 \\ -4 \\ 6 \end{bmatrix}, \mathbf{v}_3 = \begin{bmatrix} 3 \\ 6 \\ 9 \end{bmatrix}$. Find a basis for Span$\{\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3\}$.

Solution: Let

$$A = \begin{bmatrix} 1 & -2 & 3 \\ 2 & -4 & 6 \\ -3 & 6 & 9 \end{bmatrix}$$

and note that

$$\mathrm{Col} A = \mathrm{Span}\{\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3\}.$$

By row reduction, $A \sim \begin{bmatrix} 1 & -2 & 0 \\ 0 & 0 & 1 \\ 0 & 0 & 0 \end{bmatrix}$. Therefore a basis

for Span$\{\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3\}$ is $\left\{ \begin{bmatrix} \\ \\ \\ \end{bmatrix}, \begin{bmatrix} \\ \\ \\ \end{bmatrix} \right\}$.

Review

1. To find a basis for Nul A, use elementary row operations to transform $[A \;\; \mathbf{0}]$ to an equivalent reduced row echelon form $[B \;\; \mathbf{0}]$. Use the reduced row echelon form to find parametric form of the general solution to $A\mathbf{x} = \mathbf{0}$. The vectors found in this parametric form of the general solution form a basis for Nul A.

2. A basis for Col A is formed from the pivot columns of A. **Warning: Use the pivot columns of A, not the pivot columns of B, where B is in reduced echelon form and is row equivalent to A.**

4.4 Coordinate Systems

- Coordinate Systems
    - Definition: Coordinates and Coordinate Vector
    - Examples
- Change-of-Coordinates Matrix
    - Definition
    - Examples
- Parallel Worlds of $\mathbf{R}^3$ and $\mathbf{P}_2$
- Isomorphic

In general, people are more comfortable working with the vector space $\mathbf{R}^n$ and its subspaces than with other types of vectors spaces and subspaces. The goal here is to *impose* coordinate systems on vector spaces, even if they are not in $\mathbf{R}^n$.

Theorem (7)

Let $\beta = \{\mathbf{b}_1, \ldots, \mathbf{b}_n\}$ be a basis for a vector space V. Then for each $\mathbf{x}$ in V, there exists a unique set of scalars $c_1, \ldots, c_n$ such that

$$\mathbf{x} = c_1\mathbf{b}_1 + \cdots + c_n\mathbf{b}_n.$$

Coordinates

Suppose $\beta = \{\mathbf{b}_1, \dots, \mathbf{b}_n\}$ is a basis for a vector space V and $\mathbf{x}$ is in V. The **coordinates of x relative to the basis** β (or the $\beta-$ **coordinates of x**) are the weights $c_1, \dots, c_n$ such that

$$\mathbf{x} = c_1\mathbf{b}_1 + \cdots + c_n\mathbf{b}_n.$$

Coordinate Vector

In this case, the vector in $\mathbf{R}^n$

$$[\mathbf{x}]_\beta = \begin{bmatrix} c_1 \\ \vdots \\ c_n \end{bmatrix}$$

is called the **coordinate vector of x (relative to** β**)**, or the $\beta-$ **coordinate vector of x**.

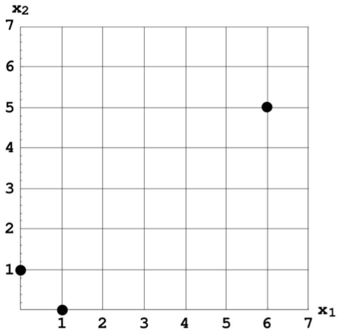
Example

Let $\beta = \{\mathbf{b}_1, \mathbf{b}_2\}$ where $\mathbf{b}_1 = \begin{bmatrix} 3 \\ 1 \end{bmatrix}$ and $\mathbf{b}_2 = \begin{bmatrix} 0 \\ 1 \end{bmatrix}$ and let $E = \{\mathbf{e}_1, \mathbf{e}_2\}$ where $\mathbf{e}_1 = \begin{bmatrix} 1 \\ 0 \end{bmatrix}$ and $\mathbf{e}_2 = \begin{bmatrix} 0 \\ 1 \end{bmatrix}$.

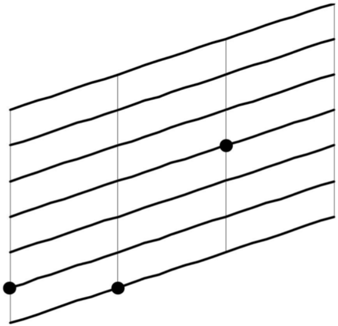
Solution:

If $[\mathbf{x}]_\beta = \begin{bmatrix} 2 \\ 3 \end{bmatrix}$, then $\mathbf{x} = \_\_\_\_ \begin{bmatrix} 3 \\ 1 \end{bmatrix} + \_\_\_\_ \begin{bmatrix} 0 \\ 1 \end{bmatrix} = \begin{bmatrix} \quad \end{bmatrix}$.

If $[\mathbf{x}]_E = \begin{bmatrix} 6 \\ 5 \end{bmatrix}$, then $\mathbf{x} = \_\_\_\_ \begin{bmatrix} 1 \\ 0 \end{bmatrix} + \_\_\_\_ \begin{bmatrix} 0 \\ 1 \end{bmatrix} = \begin{bmatrix} \quad \end{bmatrix}$.



Standard graph paper



$\beta-$ graph paper

From the last example,

$$\begin{bmatrix} 6 \\ 5 \end{bmatrix} = \begin{bmatrix} 3 & 0 \\ 1 & 1 \end{bmatrix} \begin{bmatrix} 2 \\ 3 \end{bmatrix}.$$

For a basis $\beta = \{\mathbf{b}_1, \ldots, \mathbf{b}_n\}$, let

$$P_\beta = [\mathbf{b}_1 \;\; \mathbf{b}_2 \;\; \cdots \;\; \mathbf{b}_n] \quad \text{and} \quad [\mathbf{x}]_\beta = \begin{bmatrix} c_1 \\ c_2 \\ \vdots \\ c_n \end{bmatrix}$$

Then

$$\mathbf{x} = P_\beta \, [\mathbf{x}]_\beta \, .$$

We call P_β the **change-of-coordinates matrix** from β to the standard basis in $\mathbf{R}^n$. Then

$$[\mathbf{x}]_\beta = P_\beta^{-1} \mathbf{x}$$

and therefore P_β^{-1} is a **change-of-coordinates matrix** from the standard basis in $\mathbf{R}^n$ to the basis β.

Example

Let $\mathbf{b}_1 = \begin{bmatrix} 3 \\ 1 \end{bmatrix}$, $\mathbf{b}_2 = \begin{bmatrix} 0 \\ 1 \end{bmatrix}$, $\beta = \{\mathbf{b}_1, \mathbf{b}_2\}$ and $\mathbf{x} = \begin{bmatrix} 6 \\ 8 \end{bmatrix}$. Find the change-of-coordinates matrix P_β from β to the standard basis in $\mathbf{R}^2$ and change-of-coordinates matrix P_β^{-1} from the standard basis in $\mathbf{R}^2$ to β.

Solution :

$$P_\beta = [\mathbf{b}_1 \;\; \mathbf{b}_2] = \begin{bmatrix} \quad & \quad \\ \quad & \quad \end{bmatrix}$$

and so

$$P_\beta^{-1} = \begin{bmatrix} 3 & 0 \\ 1 & 1 \end{bmatrix}^{-1} = \begin{bmatrix} \frac{1}{3} & 0 \\ -\frac{1}{3} & 1 \end{bmatrix}.$$

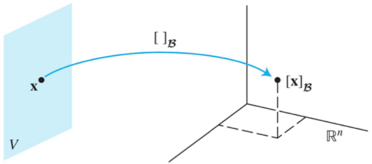
Example

If $\mathbf{x} = \begin{bmatrix} 6 \\ 8 \end{bmatrix}$, then use P_β^{-1} to find $[\mathbf{x}]_\beta = \begin{bmatrix} 2 \\ 6 \end{bmatrix}$.

Solution:

$$[\mathbf{x}]_\beta = P_\beta^{-1}\mathbf{x} = \begin{bmatrix} \frac{1}{3} & 0 \\ -\frac{1}{3} & 1 \end{bmatrix} \begin{bmatrix} 6 \\ 8 \end{bmatrix} = \begin{bmatrix} \quad \end{bmatrix}$$

Coordinate mappings allow us to introduce coordinate systems for unfamiliar vector spaces.



Example

Standard basis for $\mathbf{P}_2$: $\{\mathbf{p}_1, \mathbf{p}_2, \mathbf{p}_3\} = \left\{1, t, t^2\right\}$. Polynomials in $\mathbf{P}_2$ behave like vectors in $\mathbf{R}^3$. Since

$$a + bt + ct^2 = \_\_\_\mathbf{p}_1 + \_\_\_\mathbf{p}_2 + \_\_\_\mathbf{p}_3, \qquad \left[a + bt + ct^2\right]_{\beta} = \begin{bmatrix} a \\ b \\ c \end{bmatrix}$$

We say that the vector space $\mathbf{R}^3$ is *isomorphic* to $\mathbf{P}_2$.

Vector Space $\mathbf{R}^3$

Vector Form: $\begin{bmatrix} a \\ b \\ c \end{bmatrix}$

Vector Addition Example

$$\begin{bmatrix} -1 \\ 2 \\ -3 \end{bmatrix} + \begin{bmatrix} 2 \\ 3 \\ 5 \end{bmatrix} = \begin{bmatrix} 1 \\ 5 \\ 2 \end{bmatrix}$$

Vector Space $\mathbf{P}_2$

Vector Form: $a + bt + bt^2$

Vector Addition Example

$$(-1 + 2t - 3t^2) + (2 + 3t + 5t^2)$$
$$= 1 + 5t + 2t^2$$

Isomorphic

Informally, we say that vector space V is **isomorphic** to W if *every vector space calculation in V is accurately reproduced in W*, and vice versa.

Assume β is a basis set for vector space V. Exercise 25 (page 223) shows that

- a set $\{\mathbf{u}_1, \mathbf{u}_2, \ldots, \mathbf{u}_p\}$ in V is linearly independent if and only if $\left\{[\mathbf{u}_1]_\beta, [\mathbf{u}_2]_\beta, \ldots, [\mathbf{u}_p]_\beta\right\}$ is linearly independent in $\mathbf{R}^n$.

Example

Use coordinate vectors to determine if $\{\mathbf{p}_1, \mathbf{p}_2, \mathbf{p}_3\}$ is a linearly independent set: $\mathbf{p}_1 = 1 - t$, $\mathbf{p}_2 = 2 - t + t^2$, $\mathbf{p}_3 = 2t + 3t^2$.

Solution: The standard basis set for $\mathbf{P}_2$ is $\beta = \{1, t, t^2\}$. So

$$[\mathbf{p}_1]_\beta = \begin{bmatrix} \quad \\ \quad \\ \quad \end{bmatrix}, [\mathbf{p}_2]_\beta = \begin{bmatrix} \quad \\ \quad \\ \quad \end{bmatrix}, [\mathbf{p}_3]_\beta = \begin{bmatrix} \quad \\ \quad \\ \quad \end{bmatrix}$$

Then

$$\begin{bmatrix} 1 & 2 & 0 \\ -1 & -1 & 2 \\ 0 & 1 & 3 \end{bmatrix} \sim \cdots \sim \begin{bmatrix} 1 & 2 & 0 \\ 0 & 1 & 2 \\ 0 & 0 & 1 \end{bmatrix}$$

By the IMT, $\left\{[\mathbf{p}_1]_\beta, [\mathbf{p}_2]_\beta, [\mathbf{p}_3]_\beta\right\}$ is linearly ____________________ and therefore $\{\mathbf{p}_1, \mathbf{p}_2, \mathbf{p}_3\}$ is linearly ____________________.

Coordinate vectors also allow us to associate vector spaces with subspaces of other vectors spaces.

Example

Let $\beta = \{\mathbf{b}_1, \mathbf{b}_2\}$ where $\mathbf{b}_1 = \begin{bmatrix} 3 \\ 3 \\ 1 \end{bmatrix}$ and $\mathbf{b}_2 = \begin{bmatrix} 0 \\ 1 \\ 3 \end{bmatrix}$.

Let H =span$\{\mathbf{b}_1, \mathbf{b}_2\}$. Find $[\mathbf{x}]_\beta$, if $\mathbf{x} = \begin{bmatrix} 9 \\ 13 \\ 15 \end{bmatrix}$.

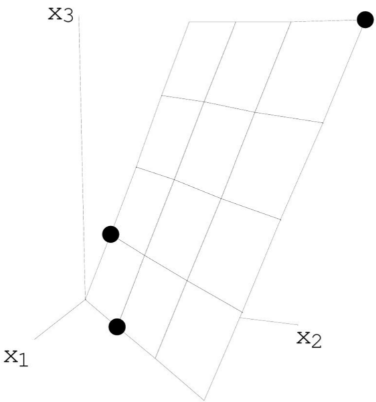
Solution: (a) Find c_1 and c_2 such that

$$c_1 \begin{bmatrix} 3 \\ 3 \\ 1 \end{bmatrix} + c_2 \begin{bmatrix} 0 \\ 1 \\ 3 \end{bmatrix} = \begin{bmatrix} 9 \\ 13 \\ 15 \end{bmatrix}$$

Corresponding augmented matrix:

$$\begin{bmatrix} 3 & 0 & 9 \\ 3 & 1 & 13 \\ 1 & 3 & 15 \end{bmatrix} \backsim \begin{bmatrix} 1 & 0 & 3 \\ 0 & 1 & 4 \\ 0 & 0 & 0 \end{bmatrix}$$

Therefore $c_1 =$ ____ and $c_2 =$ _____ and so $[\mathbf{x}]_\beta = \begin{bmatrix} \quad \\ \quad \end{bmatrix}$.



$$\begin{bmatrix} 9 \\ 13 \\ 15 \end{bmatrix} \text{ in } \mathbf{R}^3 \text{ is associated with the vector } \begin{bmatrix} 3 \\ 4 \end{bmatrix} \text{in } \mathbf{R}^2$$

H is isomorphic to $\mathbf{R}^2$