

Notes for ECE269 - Linear Algebra

Chapter 4

Sam Cowin

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1 Linear Equations in Linear Algebra

2 Matrix Algebra

3 Determinants

4 Vector Spaces

The point of this chapter is to tie in theory from the initial chapters in order to demonstrate the utility in input/output systems being understood as vector spaces. Through geometry and linear algebra, many concepts can be understood from the foundations of the first few chapters.

4.1 Vector Spaces and Subspaces

A vector space is a nonempty set V of objects, called vectors, on which are defined two operations, called addition and multiplication by scalars (real numbers), subject to the ten axioms on page 192 of the textbook, which must hold for vectors \mathbf{u} , \mathbf{v} , and \mathbf{w} in V and for all scalars c and d . The parallelogram rule from the earlier chapters is useful here to prove the axioms for generic vectors within any space. Doubly infinite sequences of numbers are equivalent to discrete time measured signals that are common within the field of engineering and especially for signal processing. In the same way that discrete time signals can be understood as vector spaces, so can polynomials of degree n as well as functions and their compositions.

A subspace of V , H , has the following three properties from the axiom list mentioned previously:

- The zero vector of V is in H
- H is closed under vector addition. That is, for each \mathbf{u} and \mathbf{v} , in H , the sum $\mathbf{u} + \mathbf{v}$ is in H .
- H is closed under multiplication by scalars. That is, for each \mathbf{u} in H and each scalar c , the vector multiple $c\mathbf{u}$ is in H .

The zero subspace is a unique identification denoted $\mathbf{0}$. 2D is not a subspace of 3D as it is not even a subset. There needs to be equal dimensionality. A vector acting like 2D that is in fact a subspace of 3D, is the 2D vector with a third dimension that is 0. Sets need to be through the origin in order to be a subspace. Every subspace for the 3D set is either a plane through the origin or a line through the origin except for the set itself. Is a group of vectors is in the vector space V , then the span of those vectors is also in the subspace of V . Rewriting a set as the vector equation can demonstrate the dimensionality for which that set is a subspace.

4.2 Null Spaces, Column Spaces, and Linear Transformations

The null space of a matrix is the set of all solutions for the homogeneous equation. Another way to visualize this is the set of all solutions that are mapped into the zero vector through the linear transformation matrix A . The null space of a matrix for a certain dimension set is the subspace of that set. For the null space to be a subspace, it must include the zero vector, which is why it is important that the equations are homogeneous. For review, the spanning set of the null space for a matrix is found by row reducing the matrix to solve for the free variables. The not free variables are explicitly described with these other variables, and a vector equation is written with the free variables as the vectors and the dimensionality described by the number of columns of the original matrix. This is implicitly linearly independent. A column space is a subspace for the dimensionality of the rows of the matrix for which the column space is defined. Unless the matrix under question is square, the null space and the column space are recognized for different dimensions. Any column of the matrix is in the column space, and to find a vector for the null space all you need to do is row reduce and solve, substituting for the free variables. A table outlining the differences between Nul and Col is on page 206 in the text to be modified later.

The kernel of a linear transformation T is the set of all \mathbf{u} in V (vector space) such that $T(\mathbf{u})=\mathbf{0}$. The range of T is the set of all vectors in W (vector space) of the form $T(\mathbf{x})$ for some \mathbf{x} in V . If this T is a matrix transformation, then the null space and column space from before apply. Derivatives are linear transformations as they can be proven to hold the attributes of linear transformations from chapter 2. Differential equations are just the kernel or the range for the particular equation.

4.3 Linearly Independent Sets; Bases

To restate, linear independence is when the linear combination of vectors with scalars is the zero vector only with the trivial solution of every scalar being zero. Any set containing the zero vector is linearly dependent as well as any set of multiple vectors where the vectors are linear combinations of multiples of each other. The basis in V for H has the following properties:

- β is a linearly independent set
- the subspace spanned by β coincides with H or H is a span of the components of β

The columns of invertible matrices have to be linearly independent and thus for the basis for the dimensionality they describe. The identity matrix is a specific form of this

in that it is called the standard basis for the dimensionality it describes. Increasing power polynomial sets are only equal to zero when the zero polynomial is introduced and thus are a basis for that dimensionality. If a set describes the vectors for which the span describes H , H is still described by this set if there is a linear combination of vectors that describe another vector in the set - and this vector is then removed. As long as H is not the zero vector, then this new set can form a basis for H . Discarding the free variables from a reduced echelon form matrix yields the basis for the matrix. In other words, the pivot columns of a matrix form the basis for the column space. The pivot columns of the reduced matrix do not form the basis, however, of the original matrix. The pivot columns will need to be applied to the original matrix in order to find its basis.

4.4 Coordinate Systems