## 4. Motrix Decompositions

| T. Mostix Lecompositions   | DATE.  |
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| 4.1 Determinant and Trace.   | 4.3 Cholesky Decomposition   |
| · Determinant  | $oldsymbol{A} = oldsymbol{L} oldsymbol{L}^	op$   |
| $ \frac{1}{1-\frac{1}{n}} \det(\mathbf{A}) = \begin{vmatrix} a_{11} & a_{12} & \dots & a_{1n} \\ a_{21} & a_{22} & \dots & a_{2n} \\ \vdots & & \ddots & \vdots \\ a_{n1} & a_{n2} & \dots & a_{nn} \end{vmatrix} \det(\mathbf{T}) = \prod_{i=1}^{n} T_{ii} . $  | $\begin{bmatrix} a_{11} & \cdots & a_{1n} \\ \vdots & \ddots & \vdots \\ a_{n1} & \cdots & a_{nn} \end{bmatrix} = \begin{bmatrix} l_{11} & \cdots & 0 \\ \vdots & \ddots & \vdots \\ l_{n1} & \cdots & l_{nn} \end{bmatrix} \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \ddots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{n1} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{nn} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & l_{nn} \end{bmatrix} - \begin{bmatrix} l_{11} & \cdots & l_{nn} \\ \vdots & \vdots & \vdots \\ 0 & \cdots & \vdots \\ 0 & $ |
| . Expansion along column $j$ $\det({m A}) = \sum^n (-1)^{k+j} a_{kj} \det({m A}_{k,j}) . \tag{4.12}$   | L: Lower-biongular motrix, Cholosky Pactor & A   |
| $\det(\mathbf{A}) = \sum_{k=1}^{\infty} (-1)^{n} d_{kj} \det(\mathbf{A}_{k,j}). \tag{4.12}$ $Expansion along row j$  |  |
| $\det(\mathbf{A}) = \sum_{k=1}^{n} (-1)^{k+j} a_{jk} \det(\mathbf{A}_{j,k}). \tag{4.13}$   |  |
| ·Trace   |  |
| $\operatorname{tr}(\boldsymbol{A}) := \sum_{i=1}^{n} a_{ii} \operatorname{tr}(\boldsymbol{A}) = \sum_{i=1}^{n} \lambda_{i}$  |  |
| <i>i</i> =1 <b>9</b>   | 4.4 Elgendecomposition and Diagonalization   |
| 4.2 Eigenvalues and Eigenvectors  1-2511-1-261: States fols 2523  • $\lambda$ is an eigenvalue of $A \in \mathbb{R}^{n \times n}$ .  • There exists an $x \in \mathbb{R}^n \setminus \{0\}$ with $Ax = \lambda x$ , or equivalently, $(A - \lambda I_n)x = 0$ can be solved non-trivially, i.e., $x \neq 0$ .  • $\operatorname{rk}(A - \lambda I_n) < n$ .  • $\det(A - \lambda I_n) = 0$ . | $D = \begin{bmatrix} c_1 & \cdots & 0 \\ \vdots & \ddots & \vdots \\ 0 & \cdots & c_n \end{bmatrix}$ $Definition 4.19 (Diagonalizable). A matrix A \in \mathbb{R}^{n \times n} is diagonalizable if it is similar to a diagonal matrix, i.e., if there exists an invertible matrix P \in \mathbb{R}^{n \times n} such that D = P^{-1}AP.$  |
|  | Theorem 4.20 (Eigendecomposition). A square matrix $\mathbf{A} \in \mathbb{R}^{n \times n}$ can be factored into $\mathbf{A} = \mathbf{P} \mathbf{D} \mathbf{P}^{-1}, \tag{4.55}$  |
|  | 工. elgenvector, elgenvalue そのわ   |
|  | 2. उत्तर स्थापन देश  |
|  | 3. 교육보다로 P 구성하고 D= PTAP인 D 구하기   |
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