Vectors

A matrix with only one column is called a column vector, or simply a vector.

$\langle 5, 9 \rangle$

$$\mathbf{u} = \begin{bmatrix} 3 \\ 2 \end{bmatrix}, \mathbf{v} = \begin{bmatrix} -1 \\ 0 \end{bmatrix}$$

$\vec{u}$ u

The set of all vectors with 2 entries is $\mathbb{R}^2$ (read R-two), since each of the two entries can be any real number.

Two vectors are equal if the corresponding entries are equal.

Ordered pairs in the *xy*-plane, like vectors in $\mathbb{R}^2$, are represented by two numbers.

We can identify the plotted point (3,-1) with the column vector $\begin{bmatrix} 3 \\ -1 \end{bmatrix}$.

Sometimes, it is useful to include a directed line segment (arrow) from the origin to the point, though we are not interested in any of the points on the segment.

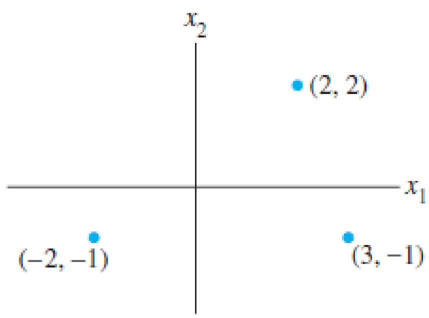


FIGURE 1 Vectors as points.

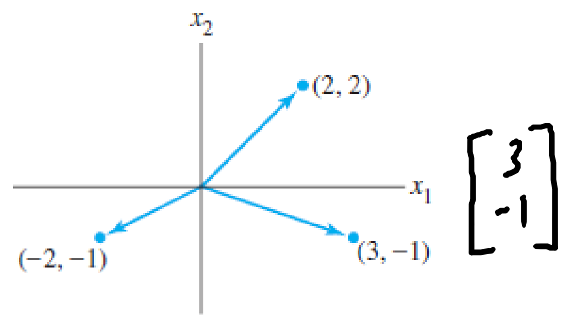


FIGURE 2 Vectors with arrows.

Adding and subtracting vectors means performing the operations on corresponding entries

Scalar multiplication means multiplying a vector by a constant (scalar)

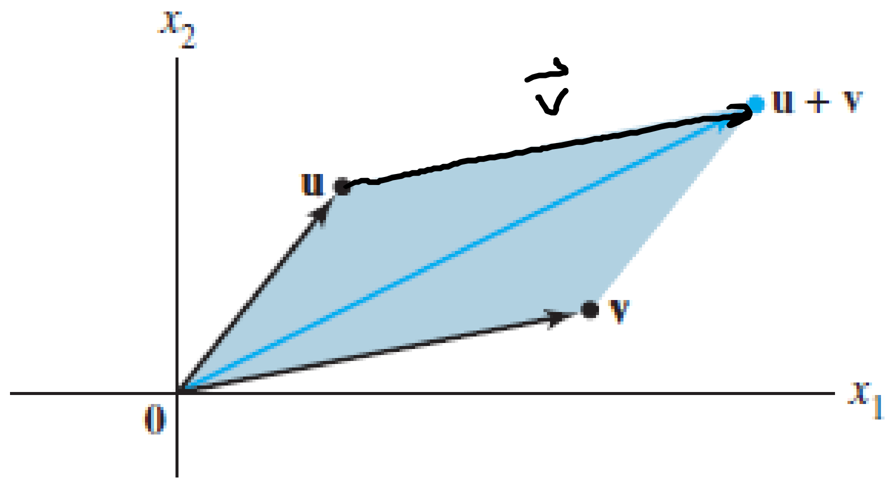
→ We do this by multiplying each entry by the constant

Ex. Let $\mathbf{u} = \begin{bmatrix} 2 \\ -3 \end{bmatrix}$ and $\mathbf{v} = \begin{bmatrix} 4 \\ 1 \end{bmatrix}$

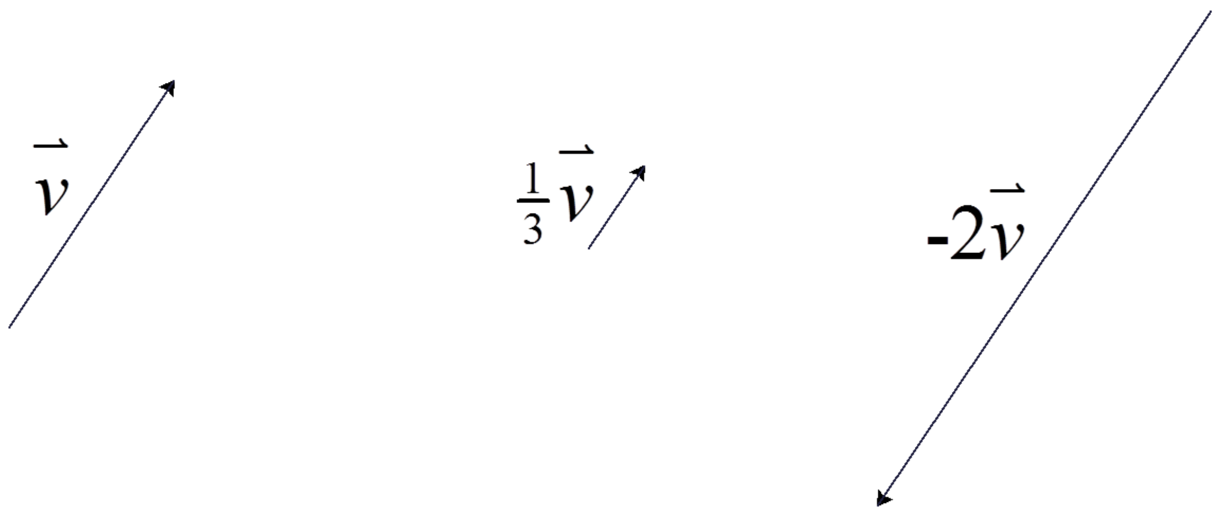
a. $3\mathbf{u} = \begin{bmatrix} 6 \\ -9 \end{bmatrix}$

b. $3\mathbf{u} - \mathbf{v} = \begin{bmatrix} 6 \\ -9 \end{bmatrix} - \begin{bmatrix} 4 \\ 1 \end{bmatrix} = \begin{bmatrix} 2 \\ -10 \end{bmatrix}$

If **u** and **v** in $\mathbb{R}^2$ are represented as points in the *xy*-plane, then **u** + **v** corresponds to the fourth vertex of the parallelogram formed by **u** and **v**.



Def. If c is a scalar and **v** is a vector, then c**v** is the vector with the same direction as **v** that has length c times as long as **v**. If $c < 0$, then c**v** goes in the opposite direction as **v**.



These ideas can be extended to *n*-dimensional space, $\mathbb{R}^n$.

$$\mathbf{u} = \begin{bmatrix} u_1 \\ u_2 \\ \mathrm{M} \\ u_n \end{bmatrix}$$

$\vec{0}$

The <u>zero vector</u>, **0**, is the vector whose entries are all zero.

Algebraic Properties of $\mathbb{R}^n$

For all $\mathbf{u}, \mathbf{v}, \mathbf{w}$ in $\mathbb{R}^n$ and all scalars c and d:

(i) $\mathbf{u} + \mathbf{v} = \mathbf{v} + \mathbf{u}$

(ii) $(\mathbf{u} + \mathbf{v}) + \mathbf{w} = \mathbf{u} + (\mathbf{v} + \mathbf{w})$

(iii) $\mathbf{u} + \mathbf{0} = \mathbf{0} + \mathbf{u} = \mathbf{u}$

(iv) $\mathbf{u} + (-\mathbf{u}) = -\mathbf{u} + \mathbf{u} = \mathbf{0}$, where $-\mathbf{u}$ denotes $(-1)\mathbf{u}$

(v) $c(\mathbf{u} + \mathbf{v}) = c\mathbf{u} + c\mathbf{v}$

(vi) $(c + d)\mathbf{u} = c\mathbf{u} + d\mathbf{u}$

(vii) $c(d\mathbf{u}) = (cd)(\mathbf{u})$

(viii) $1\mathbf{u} = \mathbf{u}$

A linear combination of vectors involves multiplying each vector by a constant coefficient and adding the results.

$$\mathbf{y} = c_1\mathbf{v}_1 + c_2\mathbf{v}_2 + \ldots + c_n\mathbf{v}_n$$

is a linear combination of $\mathbf{v}_1, \mathbf{v}_2, \ldots, \mathbf{v}_n$

$$3\begin{bmatrix} 2 \\ -3 \end{bmatrix} + 2\begin{bmatrix} 4 \\ 1 \end{bmatrix} = \begin{bmatrix} 6 \\ -9 \end{bmatrix} + \begin{bmatrix} 8 \\ 2 \end{bmatrix} = \begin{bmatrix} 14 \\ -7 \end{bmatrix}$$

→ The vector $\mathbf{u} = \begin{bmatrix} 14 \\ -7 \end{bmatrix}$ is a linear combination of $\mathbf{v}_1 = \begin{bmatrix} 2 \\ -3 \end{bmatrix}$ and $\mathbf{v}_2 = \begin{bmatrix} 4 \\ 1 \end{bmatrix}$ because $\mathbf{u} = 3\mathbf{v}_1 + 2\mathbf{v}_2$.

The coefficients are called the weights of the combination

Ex. Determine if **b** can be written as a linear combination of $\mathbf{a}_1$ and $\mathbf{a}_2$.

$$\mathbf{a}_1 = \begin{bmatrix} 1 \\ -2 \\ -5 \end{bmatrix}, \mathbf{a}_2 = \begin{bmatrix} 2 \\ 5 \\ 6 \end{bmatrix}, \mathbf{b} = \begin{bmatrix} 7 \\ 4 \\ -3 \end{bmatrix}$$

$x_1\vec{a}_1 + x_2\vec{a}_2 = \vec{b} \Leftarrow$ Do x_1 and x_2 exist.

$$x_1\begin{bmatrix} 1 \\ -2 \\ -5 \end{bmatrix} + x_2\begin{bmatrix} 2 \\ 5 \\ 6 \end{bmatrix} = \begin{bmatrix} 7 \\ 4 \\ -3 \end{bmatrix}$$

$$\begin{bmatrix} x_1 \\ -2x_1 \\ -5x_1 \end{bmatrix} + \begin{bmatrix} 2x_2 \\ 5x_2 \\ 6x_2 \end{bmatrix} = \begin{bmatrix} 7 \\ 4 \\ -3 \end{bmatrix}$$

$$\begin{bmatrix} x_1 + 2x_2 \\ -2x_1 + 5x_2 \\ -5x_1 + 6x_2 \end{bmatrix} = \begin{bmatrix} 7 \\ 4 \\ -3 \end{bmatrix}$$

$$\begin{cases} x_1 + 2x_2 = 7 \\ -2x_1 + 5x_2 = 4 \\ -5x_1 + 6x_2 = -3 \end{cases} \Longrightarrow \left[\begin{array}{cc|c} 1 & 2 & 7 \\ -2 & 5 & 4 \\ -5 & 6 & -3 \end{array}\right] \xrightarrow[R_3 \to 5R_1 + R_3]{R_2 \to 2R_1 + R_2} \left[\begin{array}{cc|c} 1 & 2 & 7 \\ 0 & 9 & 18 \\ 0 & 16 & 32 \end{array}\right]$$

$$\xrightarrow[R_3 \to \frac{1}{16}R_3]{R_2 \to \frac{1}{9}R_2} \left[\begin{array}{cc|c} 1 & 2 & 7 \\ 0 & 1 & 2 \\ 0 & 1 & 2 \end{array}\right] \xrightarrow[R_3 \to R_2 - R_3]{} \left[\begin{array}{cc|c} 1 & 2 & 7 \\ 0 & 1 & 2 \\ 0 & 0 & 0 \end{array}\right]$$

$\hookrightarrow$ no pivot in right col.

$\therefore$ system is consist.

$\therefore \vec{b}$ is lin. comb.

inconsist. $\to$ pivot in right col. of aug. matrix

consist. $\to$ no pivot in right col.

Notice that the columns of our augmented matrix were $\mathbf{a}_1$, $\mathbf{a}_2$, and $\mathbf{b}$.

→ We can abbreviate by writing $[\mathbf{a}_1 \quad \mathbf{a}_2 \mid \mathbf{b}]$

In general:

A vector equation $x_1\mathbf{a}_1 + x_2\mathbf{a}_2 + \ldots + x_n\mathbf{a}_n = \mathbf{b}$ has the same solution set as the linear system whose augmented matrix is $[\mathbf{a}_1 \quad \mathbf{a}_2 \quad \ldots \quad \mathbf{a}_n \mid \mathbf{b}]$

Ex. Convert $\begin{cases} 3x_1 - 2x_2 + x_3 = 4 \\ -x_1 + 5x_2 + 2x_3 = 6 \\ 2x_1 - x_2 - 5x_3 = 2 \end{cases}$ to a vector equation.

$$x_1 \begin{bmatrix} 3 \\ -1 \\ 2 \end{bmatrix} + x_2 \begin{bmatrix} -2 \\ 5 \\ -1 \end{bmatrix} + x_3 \begin{bmatrix} 1 \\ 2 \\ -5 \end{bmatrix} = \begin{bmatrix} 4 \\ 6 \\ 2 \end{bmatrix}$$

$$\left[\begin{array}{ccc|c} 3 & -2 & 1 & 4 \\ -1 & 5 & 2 & 6 \\ 2 & -1 & -5 & 2 \end{array}\right]$$

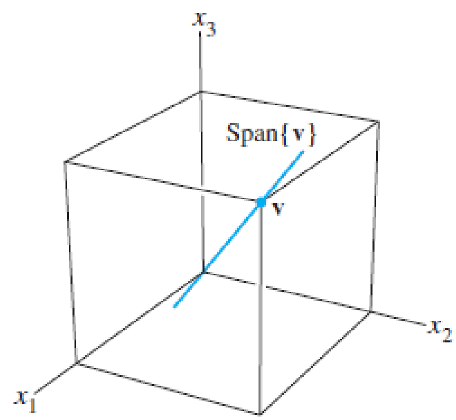
Def. If $\mathbf{v}_1, \ldots, \mathbf{v}_p$ are vectors in $\mathbb{R}^n$, then the set of all linear combinations of $\mathbf{v}_1, \ldots, \mathbf{v}_p$ is denoted $\text{Span}\{\mathbf{v}_1, \ldots, \mathbf{v}_p\}$ and is called the subset of $\mathbb{R}^n$ spanned by $\mathbf{v}_1, \ldots, \mathbf{v}_p$.

That is, $\text{Span}\{\mathbf{v}_1, \ldots, \mathbf{v}_p\}$ is the set of all vectors that can be written $c_1\mathbf{v}_1 + \ldots + c_p\mathbf{v}_p$, where $c_1,\ldots,c_p$ are scalars.

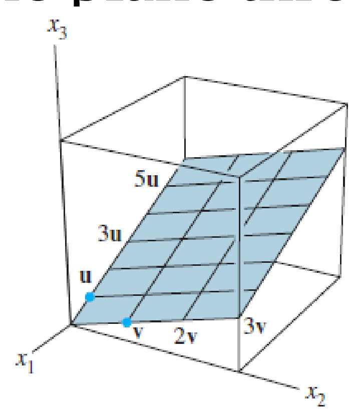
In $\mathbb{R}^3$:

$c\vec{v}$

Span{**v**} is the line through the origin and **v**:



Span{**u**,**v**} is the plane through the origin, **u** and **v**:



Ex. Determine if **b** is in the plane generated by Span{$\mathbf{a}_1, \mathbf{a}_2$}.

Is $\vec{b}$ a lin. comb. of $\vec{a}_1$ and $\vec{a}_2$?

$$\mathbf{a}_1 = \begin{bmatrix} 1 \\ -2 \\ 3 \end{bmatrix}, \mathbf{a}_2 = \begin{bmatrix} 5 \\ -13 \\ -3 \end{bmatrix}, \mathbf{b} = \begin{bmatrix} -3 \\ 8 \\ 1 \end{bmatrix}$$

$$\left[\begin{array}{cc|c} 1 & 5 & -3 \\ -2 & -13 & 8 \\ 3 & -3 & 1 \end{array}\right] \xrightarrow[R_3 \to -3R_1 + R_3]{R_2 \to 2R_1 + R_2} \left[\begin{array}{cc|c} 1 & 5 & -3 \\ 0 & -3 & 2 \\ 0 & -18 & 10 \end{array}\right] \xrightarrow{R_3 \to -6R_2 + R_3} \left[\begin{array}{cc|c} 1 & 5 & -3 \\ 0 & -3 & 2 \\ 0 & 0 & -2 \end{array}\right]$$

pivot in right col.

∴ system is inconsist.

∴ $\vec{b}$ not in span

The Matrix Equation

Let A be the matrix $[\mathbf{a}_1 \quad \mathbf{a}_2 \quad \ldots \quad \mathbf{a}_n]$, where each of the $\mathbf{a}$'s is a vector in $\mathbb{R}^m$, and let $\mathbf{x}$ be a vector in $\mathbb{R}^n$. Then the product $A\mathbf{x}$ is the linear combination of the columns of A using the entries of $\mathbf{x}$ as weights:

$$A\mathbf{x} = [\mathbf{a}_1 \quad \mathbf{a}_2 \quad \ldots \quad \mathbf{a}_n]\begin{bmatrix} x_1 \\ \vdots \\ x_n \end{bmatrix} = x_1\mathbf{a}_1 + x_2\mathbf{a}_2 + \ldots + x_n\mathbf{a}_n$$

Ex. $\begin{bmatrix} 1 & 2 & -1 \\ 0 & -5 & 3 \end{bmatrix} \begin{bmatrix} 4 \\ 3 \\ 7 \end{bmatrix} = 4\begin{bmatrix} 1 \\ 0 \end{bmatrix} + 3\begin{bmatrix} 2 \\ -5 \end{bmatrix} + 7\begin{bmatrix} -1 \\ 3 \end{bmatrix} = \begin{bmatrix} 4 \\ 0 \end{bmatrix} + \begin{bmatrix} 6 \\ -15 \end{bmatrix} + \begin{bmatrix} -7 \\ 21 \end{bmatrix} = \begin{bmatrix} 3 \\ 6 \end{bmatrix}$

Ex. $\begin{bmatrix} 2 & -3 \\ 8 & 0 \\ -5 & 2 \end{bmatrix} \begin{bmatrix} 4 \\ 7 \end{bmatrix} = 4\begin{bmatrix} 2 \\ 8 \\ -5 \end{bmatrix} + 7\begin{bmatrix} -3 \\ 0 \\ 2 \end{bmatrix} = \begin{bmatrix} 8 \\ 32 \\ -20 \end{bmatrix} + \begin{bmatrix} -21 \\ 0 \\ 14 \end{bmatrix} = \begin{bmatrix} -13 \\ 32 \\ -6 \end{bmatrix}$

Ex. $\begin{bmatrix} 2 & -3 \\ 8 & 0 \\ -5 & 2 \end{bmatrix} \begin{bmatrix} 4 \\ 7 \\ 1 \end{bmatrix} = 4\begin{bmatrix} 2 \\ 8 \\ -5 \end{bmatrix} + 7\begin{bmatrix} -3 \\ 0 \\ 2 \end{bmatrix} + 1\ ?$ ✗

Linear system:
$$\begin{aligned} x_1 + 2x_2 - x_3 &= 4 \\ -5x_2 + 3x_3 &= 1 \end{aligned}$$

Vector equation:
$$x_1 \begin{bmatrix} 1 \\ 0 \end{bmatrix} + x_2 \begin{bmatrix} 2 \\ -5 \end{bmatrix} + x_3 \begin{bmatrix} -1 \\ 3 \end{bmatrix} = \begin{bmatrix} 4 \\ 1 \end{bmatrix} \rightarrow \left[\begin{array}{ccc|c} 1 & 2 & -1 & 4 \\ 0 & -5 & 3 & 1 \end{array}\right]$$

Matrix Equation:
$$\underbrace{\begin{bmatrix} 1 & 2 & -1 \\ 0 & -5 & 3 \end{bmatrix}}_{A} \underbrace{\begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix}}_{\vec{x}} = \underbrace{\begin{bmatrix} 4 \\ 1 \end{bmatrix}}_{\vec{b}}$$

$$A\vec{x} = \vec{b}$$

Linear systems can be expressed in 3 different ways, we can pick the one that's most convenient.

Ex. Is the equation $A\mathbf{x} = \mathbf{b}$ consistent for all possible b_1, b_2, and b_3?

$$A = \begin{bmatrix} 1 & 3 & 4 \\ -4 & 2 & -6 \\ -3 & -2 & -7 \end{bmatrix}, \mathbf{b} = \begin{bmatrix} b_1 \\ b_2 \\ b_3 \end{bmatrix}$$

$$\left[\begin{array}{ccc|c} 1 & 3 & 4 & b_1 \\ -4 & 2 & -6 & b_2 \\ -3 & -2 & -7 & b_3 \end{array}\right] \xrightarrow[R_3 \to 3R_1 + R_3]{R_2 \to 4R_1 + R_2} \left[\begin{array}{ccc|c} 1 & 3 & 4 & b_1 \\ 0 & 14 & 10 & 4b_1 + b_2 \\ 0 & 7 & 5 & 3b_1 + b_3 \end{array}\right]$$

$$\xrightarrow{R_3 \to -2R_3 + R_2} \left[\begin{array}{ccc|c} 1 & 3 & 4 & b_1 \\ 0 & 14 & 10 & 4b_1 + b_2 \\ 0 & 0 & 0 & -2b_1 + b_2 - 2b_3 \end{array}\right] \longrightarrow$$

no, some values of b_1, b_2, b_3 result in a pivot in right column.

$$\left[\begin{array}{ccc|c} 1 & 3 & 4 & b_1 \\ 0 & 14 & 10 & 4b_1 + b_2 \\ 0 & 0 & 3 & -2b_1 + b_2 - 2b_3 \end{array}\right] \longrightarrow$$

yes, no pivot in right col. no matter the values of b_1, b_2, b_3

Thm. Let A be an $m \times n$ matrix and $\mathbf{b}$ be a vector in $\mathbb{R}^m$. The following are equivalent (all are true or none are true):

i. The equation $A\mathbf{x} = \mathbf{b}$ has a solution for any $\mathbf{b}$ in $\mathbb{R}^m$.

ii. Every $\mathbf{b}$ in $\mathbb{R}^m$ is a linear combination of the columns of A

iii. The columns of A span $\mathbb{R}^m$ (every vector in $\mathbb{R}^m$ is in the span of the columns of A)

iv. A has a pivot position in every row

Note: This is about the coefficient matrix, A, of a linear system, not the augmented matrix $[A \mid \mathbf{b}]$.

Ex. Can $A\mathbf{x} = \mathbf{b}$ be solved for any $\mathbf{b}$ in $\mathbb{R}^3$?

$$A = \begin{bmatrix} 1 & 0 & -1 & 6 \\ 7 & 1 & -1 & 14 \\ 5 & 1 & 1 & 2 \end{bmatrix}$$

$$\begin{bmatrix} \textcircled{1} & 0 & -1 & 6 \\ 7 & 1 & -1 & 14 \\ 5 & 1 & 1 & 2 \end{bmatrix} \xRightarrow[R_3 \to -5R_1 + R_3]{R_2 \to -7R_1 + R_2} \begin{bmatrix} 1 & 0 & -1 & 6 \\ 0 & 1 & 6 & -28 \\ 0 & 1 & 6 & -28 \end{bmatrix}$$

$$\xRightarrow[R_3 \to R_2 - R_3]{} \begin{bmatrix} \textcircled{1} & 0 & -1 & 6 \\ 0 & \textcircled{1} & 6 & -28 \\ 0 & 0 & 0 & 0 \end{bmatrix}$$

↳ A does not have a pivot in every row

$\therefore A\vec{x} = \vec{b}$ is not consist. for every $\vec{b}$

Ex. Do the columns of A span $\mathbb{R}^3$?

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

$$\begin{bmatrix} 7 & 1 & 2 \\ 5 & -1 & 6 \\ -2 & 0 & 4 \end{bmatrix} \xrightarrow{R_1 \leftrightarrow -\frac{1}{2}R_3} \begin{bmatrix} 1 & 0 & -2 \\ 5 & -1 & 6 \\ 7 & 1 & 2 \end{bmatrix} \xrightarrow[R_3 \to -7R_1 + R_3]{R_2 \to -5R_1 + R_2} \begin{bmatrix} 1 & 0 & -2 \\ 0 & -1 & 16 \\ 0 & 1 & 16 \end{bmatrix} \xrightarrow{R_3 \to R_2 + R_3} \begin{bmatrix} 1 & 0 & -2 \\ 0 & -1 & 16 \\ 0 & 0 & 32 \end{bmatrix}$$

yes, A has pivot in every row

Let's do these again using dot product:

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

Ex. $\begin{bmatrix} 2 & -3 \\ 8 & 0 \\ -5 & 2 \end{bmatrix} \begin{bmatrix} 4 \\ 7 \end{bmatrix}$

The identity matrix is a square matrix that has ones on its main diagonal and zeroes as every other entry

$$I_4 = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Multiplying any vector by I results in the same vector

$$I\mathbf{x} = \mathbf{x}$$

Solution Sets of Linear Systems

The linear system $A\mathbf{x} = \mathbf{0}$ is called homogeneous.

$$x_1\mathbf{a}_1 + x_2\mathbf{a}_2 + \ldots + x_n\mathbf{a}_n = \mathbf{0}$$

This system always has at least 1 solution, where all the x's are 0. This is called the trivial solution.

Thm. The homogeneous equation $A\mathbf{x} = \mathbf{0}$ has a nontrivial solution if and only if the equation has at least one free variable.

→ So the homogeneous system has either one trivial solution or infinitely many solutions.

Ex. Describe the solution set of

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

$$\left[\begin{array}{ccc|c} 3 & 5 & -4 & 0 \\ -3 & -2 & 4 & 0 \\ 6 & 1 & -8 & 0 \end{array}\right] \xrightarrow[R_3 \to -2R_1 + R_3]{R_2 \to R_1 + R_2} \left[\begin{array}{ccc|c} 3 & 5 & -4 & 0 \\ 0 & 3 & 0 & 0 \\ 0 & -9 & 0 & 0 \end{array}\right]$$

$$\xRightarrow{R_3 \to -3R_2 + R_3} \left[\begin{array}{ccc|c} 3 & 5 & -4 & 0 \\ 0 & 3 & 0 & 0 \\ 0 & 0 & 0 & 0 \end{array}\right] \xRightarrow{R_2 \to \frac{1}{3}R_2} \left[\begin{array}{ccc|c} 3 & 5 & -4 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 \end{array}\right] \xRightarrow{R_1 \to -5R_2 + R_1} \left[\begin{array}{ccc|c} 3 & 0 & -4 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 \end{array}\right]$$

$$\xRightarrow{R_1 \to \frac{1}{3}R_1} \left[\begin{array}{ccc|c} x_1 & x_2 & x_3 & \\ 1 & 0 & -4/3 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 \end{array}\right] \Rightarrow \begin{aligned} x_1 - \tfrac{4}{3}x_3 &= 0 \\ x_2 &= 0 \end{aligned} \Rightarrow \begin{aligned} x_1 &= \tfrac{4}{3}x_3 \\ x_2 &= 0 \\ x_3 &= x_3 \end{aligned} \Rightarrow \vec{x} = \begin{bmatrix} \frac{4}{3}x_3 \\ 0 \\ x_3 \end{bmatrix} = x_3 \begin{bmatrix} 4/3 \\ 0 \\ 1 \end{bmatrix}$$

1 free variable resulted in a line in $\mathbb{R}^3$.

Ex. Describe the solution set of $10x_1 - 3x_2 - 2x_3 = 0$

$$\left[\begin{array}{ccc|c} 10 & -3 & -2 & 0 \end{array}\right] \Longrightarrow \begin{array}{c} \\ \end{array}\left[\begin{array}{ccc|c} x_1 & x_2 & x_3 & \\ \textcircled{1} & \frac{-3}{10} & -\frac{1}{5} & 0 \end{array}\right] \Longrightarrow x_1 - \frac{3}{10}x_2 - \frac{1}{5}x_3 = 0$$

$$\Longrightarrow \begin{aligned} x_1 &= \frac{3}{10}x_2 + \frac{1}{5}x_3 \\ x_2 &= x_2 \\ x_3 &= x_3 \end{aligned}$$

$$\vec{X} = \begin{bmatrix} \frac{3}{10}x_2 + \frac{1}{5}x_3 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} \frac{3}{10}x_2 \\ x_2 \\ 0 \end{bmatrix} + \begin{bmatrix} \frac{1}{5}x_3 \\ 0 \\ x_3 \end{bmatrix}$$

$$= x_2 \begin{bmatrix} 3/10 \\ 1 \\ 0 \end{bmatrix} + x_3 \begin{bmatrix} 1/5 \\ 0 \\ 1 \end{bmatrix}$$

2 free variables resulted in a plane in $\mathbb{R}^3$.

If *A* has no free variables:

- Trivial solution
- The point **0** in $\mathbb{R}^3$

If *A* has 1 free variable:

- A line in $\mathbb{R}^3$ that passes through the origin
- Can be described parametrically by $\mathbf{x} = t\mathbf{v}_1$.

If *A* has 2 free variables:

- A plane in $\mathbb{R}^3$ that passes through the origin
- Can be described parametrically by $\mathbf{x} = s\mathbf{v}_1 + t\mathbf{v}_2$.

→ Note this represents Span$\{\mathbf{v}_1, \mathbf{v}_2\}$

When we write our solution sets in this form, it is called the parametric vector form.

If $\mathbf{b} \neq \mathbf{0}$, the linear system $A\mathbf{x} = \mathbf{b}$ is called <u>non-homogeneous</u>.

$$x_1\mathbf{a}_1 + x_2\mathbf{a}_2 + \ldots + x_n\mathbf{a}_n = \mathbf{b}$$

Ex. Describe the solution set of

$$\begin{aligned} 3x_1 + 5x_2 - 4x_3 &= 7 \\ -3x_1 - 2x_2 + 4x_3 &= -1 \\ 6x_1 + x_2 - 8x_3 &= -4 \end{aligned}$$

$$\left[\begin{array}{ccc|c} 3 & 5 & -4 & 7 \\ -3 & -2 & 4 & -1 \\ 6 & 1 & -8 & -4 \end{array}\right] \xrightarrow[R_3 \to -2R_1 + R_3]{R_2 \to R_1 + R_2} \left[\begin{array}{ccc|c} 3 & 5 & -4 & 7 \\ 0 & 3 & 0 & 6 \\ 0 & -9 & 0 & -18 \end{array}\right]$$

$$\xrightarrow[R_3 \to 3R_2 + R_3]{} \left[\begin{array}{ccc|c} x_1 & x_2 & x_3 & \\ \hline \textcircled{3} & 5 & -4 & 7 \\ 0 & \textcircled{3} & 0 & 6 \\ 0 & 0 & 0 & 0 \end{array}\right] \xrightarrow{R_2 \to \frac{1}{3}R_2} \left[\begin{array}{ccc|c} 3 & 5 & -4 & 7 \\ 0 & 1 & 0 & 2 \\ 0 & 0 & 0 & 0 \end{array}\right] \xrightarrow{R_1 \to -5R_2 + R_1} \left[\begin{array}{ccc|c} 3 & 0 & -4 & -3 \\ 0 & 1 & 0 & 2 \\ 0 & 0 & 0 & 0 \end{array}\right]$$

$$\xrightarrow{R_1 \to \frac{1}{3}R_1} \left[\begin{array}{ccc|c} 1 & 0 & -\frac{4}{3} & -1 \\ 0 & 1 & 0 & 2 \\ 0 & 0 & 0 & 0 \end{array}\right] \Longrightarrow \begin{aligned} x_1 - \tfrac{4}{3}x_3 &= -1 \\ x_2 &= 2 \end{aligned} \Rightarrow \begin{aligned} x_1 &= \tfrac{4}{3}x_3 - 1 \\ x_2 &= 2 \\ x_3 &= x_3 \end{aligned} \Rightarrow \vec{x} = \begin{bmatrix} \frac{4}{3}x_3 - 1 \\ 2 \\ x_3 \end{bmatrix}$$

$$= \begin{bmatrix} 4/3\, x_3 \\ 0 \\ x_3 \end{bmatrix} + \begin{bmatrix} -1 \\ 2 \\ 0 \end{bmatrix}$$

$$= x_3 \begin{bmatrix} 4/3 \\ 0 \\ 1 \end{bmatrix} + \begin{bmatrix} -1 \\ 2 \\ 0 \end{bmatrix}$$

$A\mathbf{x} = \mathbf{b}$ has no solutions if:

- $A\mathbf{x} = \mathbf{b}$ is inconsistent

$A\vec{x} = \vec{0}$

$A\mathbf{x} = \mathbf{b}$ has 1 solution if:

- The corresponding homogeneous system had only the trivial solution

$A\mathbf{x} = \mathbf{b}$ has infinitely many solutions if:

- The corresponding homogeneous system had infinitely many solutions
- Solutions would be 1 vector plus a linear combination of vectors that satisfy the corresponding homogeneous system.
- $\mathbf{x} = \mathbf{p} + t\mathbf{v}_1 \rightarrow$ a line not through the origin
- $\mathbf{x} = \mathbf{p} + s\mathbf{v}_1 + t\mathbf{v}_2 \rightarrow$ a plane not through the origin

Prove the previous result:

Assume $\vec{v}_1$ soln. to homog. $\Rightarrow A\vec{v}_1 = \vec{0}$

Assume $\vec{p}$ soln. to non-homog. $\Rightarrow A\vec{p} = \vec{b}$

Show $\vec{x} = \vec{p} + t\vec{v}_1$ soln. to non-homog.

$$A\vec{x} = \vec{b}$$

$$A(\vec{p} + t\vec{v}_1) \stackrel{?}{=} \vec{b}$$

$$A\vec{p} + A(t\vec{v}_1) \stackrel{?}{=} \vec{b}$$

$$A\vec{p} + t(A\vec{v}_1) \stackrel{?}{=} \vec{b}$$

$$\vec{b} + t(\vec{0}) \stackrel{?}{=} \vec{b}$$

$$\vec{b} + \vec{0} \stackrel{?}{=} \vec{b} \quad \checkmark$$

$$\vec{x} = \vec{p} + t\vec{v}_1$$

$3x - 2 = 13$

Show $x = 5$ is soln.

$3(5) - 2 \stackrel{?}{=} 13$