# Lecture 9 - UM 102 (Spring 2021)

Vamsi Pritham Pingali

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# Recap

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- Discussed the Gauss-Jordan method to compute inverses and illustrated it with an example.

#### A general simple linear system

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- By our criterion for invertibility, the coefficient matrix is invertible if and only if  $ad bc \neq 0$ .

# A geometric viewpoint

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$$\vec{v} \times \vec{w} = (ad - bc)\hat{k}$$
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  - Additivity:

$$F(\ldots,v_k+w,\ldots)=F(\ldots,v_k,\ldots)+F(\ldots,w,\ldots).$$

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 $F(\ldots, v_k + w, \ldots) = F(\ldots, v_k, \ldots) + F(\ldots, w, \ldots)$ . A function that satisfies the first two properties is said to be *multilinear*.

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- Normalisation:  $F(e_1, \ldots, e_n) = 1$ .

$$F(\ldots, v_k + c_1 w_1 + c_2 w_2 + \ldots + c_m w_m, \ldots) = F(\ldots, v_k, \ldots) + c_1 F(\ldots, w_1, \ldots) + \ldots$$
(HW).

• Linearity with more than one vector:

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- Using the above result we see that  $d(e_{j_1}, \dots, e_{j_n}) = (-1)^K d(e_1, \dots, e_n) = (-1)^K$  and  $f(e_{j_1}, \dots, e_{j_n}) = (-1)^K f(e_1, \dots, e_n) =$   $d(e_{j_1}, \dots, e_{j_n}) f(e_1, \dots, e_n).$ • Thus  $f(v_1, \dots, v_n) = \sum c_{1j_1} \dots d(e_{j_1}, \dots, e_{j_n}) f(e_1, \dots, e_n) =$  $d(v_1, \dots, v_n) f(e_1, \dots, e_n).$