

①

4.1 #19 kernel, range ( $\mathbb{P}_3$ )

a)  $L[p(x)] = xp'(x)$

kernel  $L[p(x)] = 0 \Rightarrow xp'(x) = 0$  for all  $x \Rightarrow p'(x) = 0$  for all  $x$ .

$\Rightarrow p(x) = c$

kernel =  $\{c\} = \text{span}\{1\}$  kernel = dim 1

$p(x) = a + bx + cx^2 \in \mathbb{P}_3$

$\Rightarrow p' = b + 2cx$

$x p'(x) = x(b + 2cx)$

$= bx + 2cx^2 = \text{span}\{x, x^2\} \Rightarrow \text{range} = \text{dim } 2$

b)  $L[p(x)] = p(x) - p'(x)$  ( $\mathbb{P}_3 \rightarrow \mathbb{P}_3$ )

$L[p] = 0 \Rightarrow p(x) - p'(x) = 0$  for all  $x$

$p'(x) = p(x) \Rightarrow p(x) = e^x$

No poly'l sol'n except for 0.

kernel =  $\{0\}$  dim = 0

$p = a + bx + cx^2$

$p' = b + 2cx$

$a + bx + cx^2 = b + 2cx$

$\left. \begin{array}{l} a = b \\ b = 2c \\ c = 0 \end{array} \right\} \Rightarrow a = 0, b = 0, c = 0$

$L[a + bx + cx^2] = a + bx + cx^2 - (b + 2cx)$

$= (a - b) + (b - 2c)x + cx^2$

$= \text{span}\{1, x, x^2\} = \mathbb{P}_3$  (dim = 3)

6.2 sample question (set up)

$$y'' + 3y' - 2y = 0$$

write as a 2x2 system

$$\begin{aligned} y_1 &= y \\ y_2 &= y' \end{aligned} \Rightarrow \dots$$

6.3 Diagonalization = Similarity using basis of e-vectors

198 #14d)

$$L: \mathbb{P}_2 \rightarrow \mathbb{P}_2 \quad L[p(x)] = p'(x) + p(0)$$
  
$$\{x^2, x, 1\} \quad \{2, 1-x\}$$

$$L[x^2] = (x^2)' + (x^2)|_{x=0} = 2x + 0 = 2x = -2(1-x) + 2 \cdot 1 \cdot \frac{1}{2}$$

$$\rightarrow \begin{bmatrix} 1 \\ -2 \end{bmatrix}$$

$$L[x] = (x)' + x|_{x=0} = 1 + 0 = 1$$

$$= \frac{1}{2} \cdot 2 + 0 \cdot (1-x)$$

$$\rightarrow \begin{bmatrix} 1/2 \\ 0 \end{bmatrix}$$

$$L[1] = 1' + 1|_{x=0} = 1$$

$$= \frac{1}{2} \cdot 2 + 0$$

$$= \begin{bmatrix} 1/2 \\ 0 \end{bmatrix}$$

$$2x = a \cdot 2 + b(1-x)$$
  
$$= 2a + b - bx$$

$$\begin{aligned} b &= -2 & 2a + b &= 0 \\ & & 2a - 2 &= 0 \\ & & a &= 1 \end{aligned}$$

$$\begin{bmatrix} 1 & 1/2 & 1/2 \\ -2 & 0 & 0 \end{bmatrix}$$

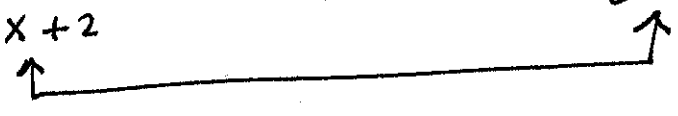
d)  $4x^2 + 2x = \begin{bmatrix} 4 \\ 2 \\ 0 \end{bmatrix}$

$$\begin{bmatrix} 1 & 1/2 & 1/2 \\ -2 & 0 & 0 \end{bmatrix} \begin{bmatrix} 4 \\ 2 \\ 0 \end{bmatrix} = \begin{bmatrix} 5 \\ -8 \end{bmatrix}$$

$$L[4x^2 + 2x]$$

$$= (4x^2 + 2x)' + (4x^2 + 2x)|_{x=0}$$
  
$$= 8x + 2$$

$$\begin{aligned} &= 5 \cdot 2 + (-8)(1-x) \\ &= 10 - 8 + 8x \\ &= 2 + 8x \end{aligned}$$



NOTE:  $\langle u(x), v(x) \rangle = \int_0^1 u(x)v(x) dx \leftarrow$

$$\begin{aligned}
 p &= 1+x & \Rightarrow \langle p, q \rangle &= \int_0^1 (1+x)(2x+3) dx \\
 q &= 2x+3 & &= \int_0^1 (2x + 2x^2 + 3 + 3x) dx \\
 & & &= \int_0^1 (3 + 5x + 2x^2) dx
 \end{aligned}$$

$$\begin{aligned}
 p &\rightarrow [1, 1] \\
 q &\rightarrow [3, 2]
 \end{aligned}$$

$$= 3 + 5/2 + 2/3$$

$$[1, 1] \cdot \begin{bmatrix} 3 \\ 2 \end{bmatrix} = 3 + 2 = 5$$

$$\|u\| = \langle u, u \rangle^{1/2}$$

208 #2  $v_1 = \begin{bmatrix} 1 \\ 1 \end{bmatrix}, v_2 = \begin{bmatrix} -1 \\ 2 \end{bmatrix}, v_3 = \begin{bmatrix} 1 \\ 7 \end{bmatrix}$

$$L[v_1] = \begin{bmatrix} 2 \\ 5 \end{bmatrix}, L[v_2] = \begin{bmatrix} -3 \\ 1 \end{bmatrix}$$

$L[v_3]?$

$$\begin{bmatrix} 1 \\ 7 \end{bmatrix} = v_3 = a \begin{bmatrix} 1 \\ 1 \end{bmatrix} + b \begin{bmatrix} -1 \\ 2 \end{bmatrix} = \begin{bmatrix} a-b \\ a+2b \end{bmatrix}$$

$$\begin{bmatrix} 1 \\ 7 \end{bmatrix} = 3 \begin{bmatrix} 1 \\ 1 \end{bmatrix} + 2 \begin{bmatrix} -1 \\ 2 \end{bmatrix}$$

$$\begin{aligned}
 a-b &= 1 \\
 a+2b &= 7
 \end{aligned}$$

$$\begin{aligned}
 -a+b &= -1 \\
 a+2b &= 7
 \end{aligned}$$

$$a = 1+b = 3 \quad (a=3)$$

$$\begin{aligned}
 3b &= 6 \\
 b &= 2
 \end{aligned}$$

$$\begin{aligned}
 L\begin{bmatrix} 1 \\ 7 \end{bmatrix} &= 3L\begin{bmatrix} 1 \\ 1 \end{bmatrix} + 2L\begin{bmatrix} -1 \\ 2 \end{bmatrix} \\
 &= 3 \begin{bmatrix} 2 \\ 5 \end{bmatrix} + 2 \begin{bmatrix} -3 \\ 1 \end{bmatrix} = \dots
 \end{aligned}$$

296 #5

$$Q^T Q = I$$

$$z = Qx$$

$$w = Qy$$

Show angles are preserved

i: angle between  $x, y$  ?

$$\cos \theta_1 = \frac{\langle x, y \rangle}{\|x\| \|y\|}$$

ii: angle between  $z, w$

$$\cos \theta_2 = \frac{\langle z, w \rangle}{\|z\| \|w\|} = \frac{\langle Qx, Qy \rangle}{\|Qx\| \|Qy\|} = \frac{\langle x, y \rangle}{\|x\| \|y\|}$$

$$\begin{aligned} \|Qx\|^2 &= (Qx)^T (Qx) \\ &= x^T \underbrace{Q^T Q}_{I} x = x^T x = \|x\|^2 \end{aligned}$$

$$\begin{aligned} \langle Qx, Qy \rangle &= (Qx)^T Qy = x^T \underbrace{Q^T Q}_{I} y \\ &= x^T y = \langle x, y \rangle \end{aligned}$$

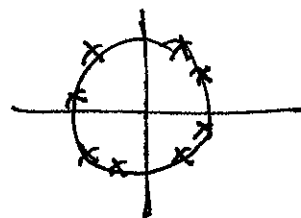
$$\cos \theta_1 = \cos \theta_2$$

$$\theta_1 = \theta_2 !$$

$Q$  orthog.

$\Rightarrow Q$  preserves angles + lengths.

$\Rightarrow$  pure rotation  $|\lambda(Q)| = 1$

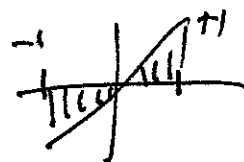


297 #12

$$\langle f, g \rangle = \int_{-1}^{+1} f(x)g(x)dx$$

$\left\{ \frac{1}{\sqrt{2}}, \frac{\sqrt{6}}{2}x \right\}$  are orthonormal

$$0 = \left\langle \frac{1}{\sqrt{2}}, \frac{\sqrt{6}}{2}x \right\rangle = \int_{-1}^{+1} \left( \frac{1}{\sqrt{2}} \right) \left( \frac{\sqrt{6}}{2}x \right) dx$$



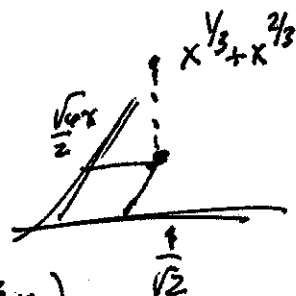
$$0 = \langle 1, x \rangle = \left( \frac{\sqrt{3}}{2} \right) \int_{-1}^{+1} x dx = 0!$$

$$1 = \left\| \frac{1}{\sqrt{2}} \right\|^2 = \int_{-1}^{+1} \left( \frac{1}{\sqrt{2}} \right) \left( \frac{1}{\sqrt{2}} \right) dx = \int_{-1}^{+1} \frac{1}{2} dx = \frac{1}{2} \int_{-1}^{+1} dx = \frac{1}{2} \cdot 2 = 1 \checkmark$$

$$1 = \left\| \frac{\sqrt{6}}{2}x \right\|^2 = \int_{-1}^{+1} \left( \left( \frac{\sqrt{6}}{2}x \right) \left( \frac{\sqrt{6}}{2}x \right) \right) dx = \frac{6}{4} \int_{-1}^{+1} x^2 dx = \frac{6}{4} \left. \frac{x^3}{3} \right|_{-1}^{+1} = \frac{6}{4} \cdot \frac{2}{3} = 1$$

b)  $x^{1/3} + x^{2/3} \approx a + bx$

$$= a \cdot \left( \frac{1}{\sqrt{2}} \right) + b \left( \frac{\sqrt{6}}{2}x \right)$$



$$\langle x^{1/3} + x^{2/3}, \frac{1}{\sqrt{2}} \rangle = a \left\langle \frac{1}{\sqrt{2}}, \frac{1}{\sqrt{2}} \right\rangle + b \left\langle \frac{1}{\sqrt{2}}, \frac{\sqrt{6}}{2}x \right\rangle$$

$$= a \cdot 1 = a$$

$$\langle x^{1/3} + x^{2/3}, \frac{\sqrt{6}}{2}x \rangle = b$$

$$a = \int_{-1}^{+1} (x^{1/3} + x^{2/3}) \cdot \frac{1}{\sqrt{2}} dx =$$

$$b = \int_{-1}^{+1} (x^{1/3} + x^{2/3}) \left( \frac{\sqrt{6}}{2}x \right) dx$$

$$f(x) \approx \sum_{k=1}^N c_k u_k(x)$$

$\{u_k\}$  ortho-normal

$$\Rightarrow c_k = \langle f(x), u_k(x) \rangle$$