

Do Suggested HW for Section 1.1

List of HW Problems and Full Solutions  
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Problems on D2L

Vectors are sometimes written in bold font.

**b** is a vector

$\vec{b}$  is a vector

$b$  is a real number

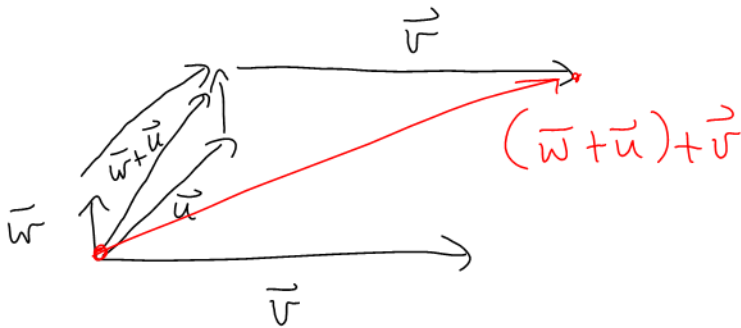
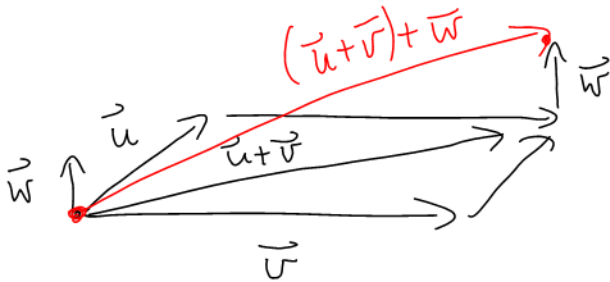
**Fact:** Order doesn't matter when adding vectors. For any vectors  $\vec{u}, \vec{v}$  and  $\vec{w}$ :

$$\vec{u} + \vec{v} = \vec{v} + \vec{u}$$

$$(\vec{u} + \vec{v}) + \vec{w} = (\vec{w} + \vec{u}) + \vec{v}$$

**Example:** Let  $\vec{u}, \vec{v}$  and  $\vec{w}$  be positioned tail to tail to tail. Show geometrically that

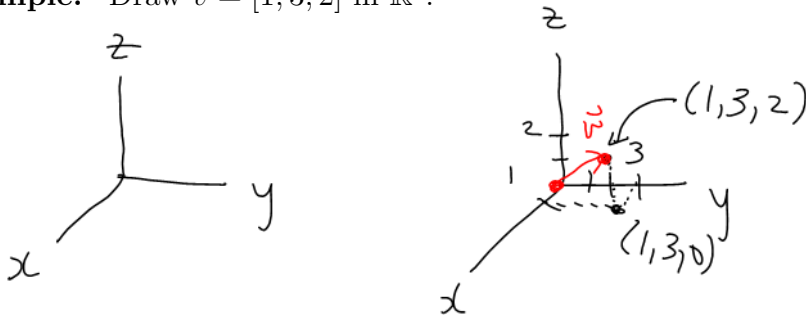
$$(\vec{u} + \vec{v}) + \vec{w} = (\vec{w} + \vec{u}) + \vec{v}$$



**Fact:** The above example illustrates that we can write  $\vec{u} + \vec{v} + \vec{w}$  without any bracketing.

**Definition:** Consider the expression:  $\vec{v}$  in  $\mathbb{R}^n$ . This means that  $\vec{v}$  has  $n$  components, and each component is a real number.

**Example:** Draw  $\vec{v} = [1, 3, 2]$  in  $\mathbb{R}^3$ .



**Definition:** The **zero vector** is written  $\vec{0}$ . Each of its components is zero. The zero vector is useful for algebra.

**Example:** Write the zero vector in  $\mathbb{R}^2$  and  $\mathbb{R}^3$ .

$$\text{In } \mathbb{R}^2: \vec{0} = [0, 0]$$

$$\text{In } \mathbb{R}^3: \vec{0} = [0, 0, 0]$$

**Example:** Let  $\vec{u}$  be in  $\mathbb{R}^2$ . Show (prove) that  $\vec{u} + (-\vec{u}) = \vec{0}$ .

$$\text{Let } \vec{u} = [u_1, u_2]$$

$$\begin{aligned} \vec{u} + (-\vec{u}) &= [u_1, u_2] + [-u_1, -u_2] \\ &= [0, 0] \\ &= \vec{0} \end{aligned}$$

**Example:** Solve for  $\vec{x}$  given that  $7\vec{x} - \vec{a} = 3(\vec{a} + 4\vec{x})$ .

$$\begin{aligned} 7\vec{x} - \vec{a} &= 3\vec{a} + 12\vec{x} \\ -5\vec{x} - \vec{a} &= 3\vec{a} \\ -5\vec{x} &= 4\vec{a} \\ \vec{x} &= -\frac{4}{5}\vec{a} \end{aligned}$$

**Definition:** Consider the statement:

$\vec{w}$  is a **linear combination** of  $\begin{bmatrix} 1 \\ 1 \end{bmatrix}$  and  $\begin{bmatrix} 0 \\ 2 \end{bmatrix}$  with coefficients  $-3$  and  $2$ .

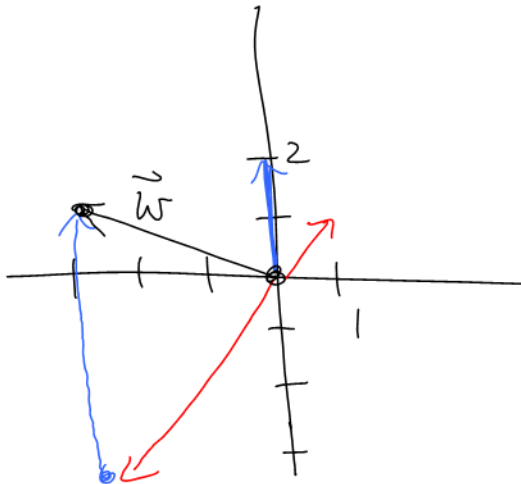
This means that  $\vec{w} = -3 \begin{bmatrix} 1 \\ 1 \end{bmatrix} + 2 \begin{bmatrix} 0 \\ 2 \end{bmatrix}$ .

**Example:** Let  $\vec{w} = -3 \begin{bmatrix} 1 \\ 1 \end{bmatrix} + 2 \begin{bmatrix} 0 \\ 2 \end{bmatrix}$ .

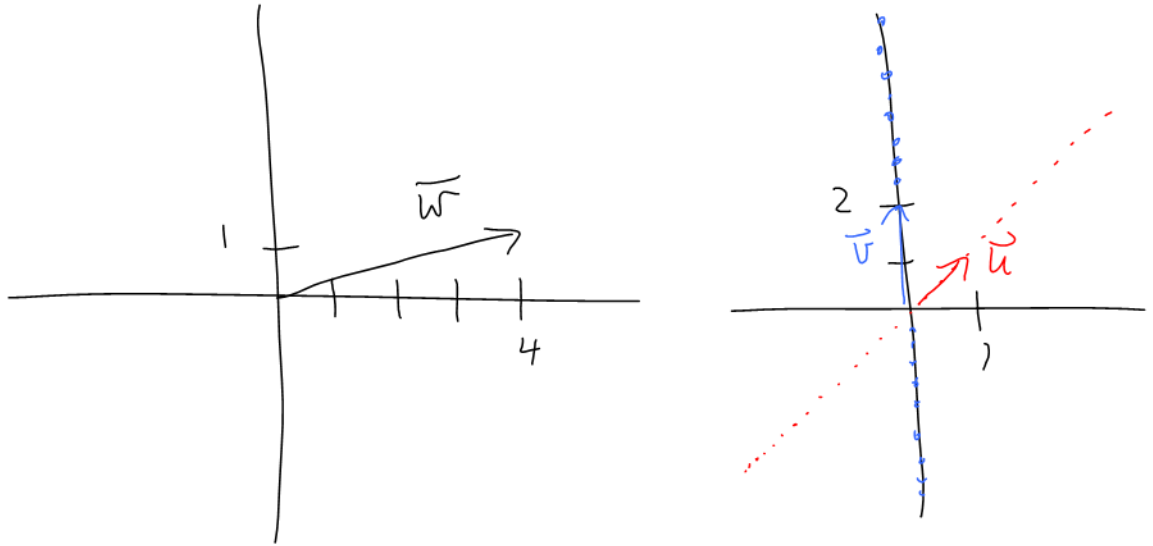
a) Find  $\vec{w}$  algebraically.

$$\begin{aligned} \vec{w} &= \begin{bmatrix} -3 \\ -3 \end{bmatrix} + \begin{bmatrix} 0 \\ 4 \end{bmatrix} \\ &= \begin{bmatrix} -3 \\ 1 \end{bmatrix} \end{aligned}$$

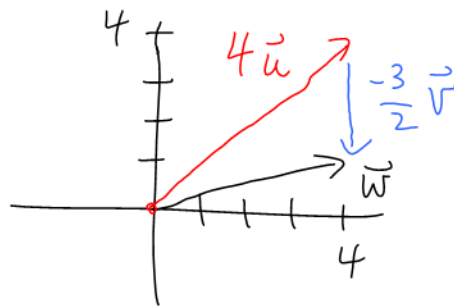
b) Find  $\vec{w}$  geometrically.



**Example:** Write  $\vec{w} = \begin{bmatrix} 4 \\ 1 \end{bmatrix}$  as a linear combination of  $\vec{u} = \begin{bmatrix} 1 \\ 1 \end{bmatrix}$  and  $\vec{v} = \begin{bmatrix} 0 \\ 2 \end{bmatrix}$  by graphing.



Think of  $\vec{u}$  and  $\vec{v}$  as the axes.



$$\begin{bmatrix} 0 \\ -3 \end{bmatrix} = k \begin{bmatrix} 0 \\ 2 \end{bmatrix}$$

$$-3 = k(2)$$

$$k = -\frac{3}{2}$$

$$\vec{w} = 4\vec{u} - \frac{3}{2}\vec{v} \quad \checkmark$$

$$\vec{w} = 4 \begin{bmatrix} 1 \\ 1 \end{bmatrix} - \frac{3}{2} \begin{bmatrix} 0 \\ 2 \end{bmatrix} \quad \checkmark$$

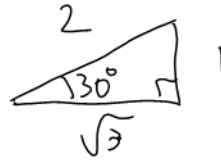
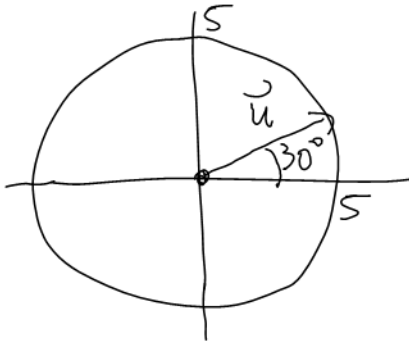
We'll do this algebraically in Ch 2.

$$\begin{bmatrix} 4 \\ 1 \end{bmatrix} = c_1 \begin{bmatrix} 1 \\ 1 \end{bmatrix} + c_2 \begin{bmatrix} 0 \\ 2 \end{bmatrix}$$

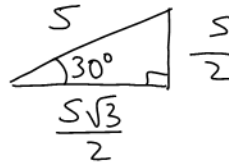
system of equations ...

1.1 The Geometry and Algebra of Vectors

**Example:** a) Let  $\vec{u}$  be a vector of length 5, in standard position, rotated  $30^\circ$  from the positive  $x$ -axis. Find  $\vec{u}$  algebraically.

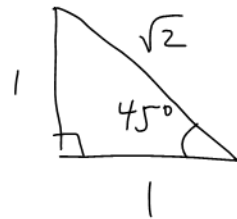
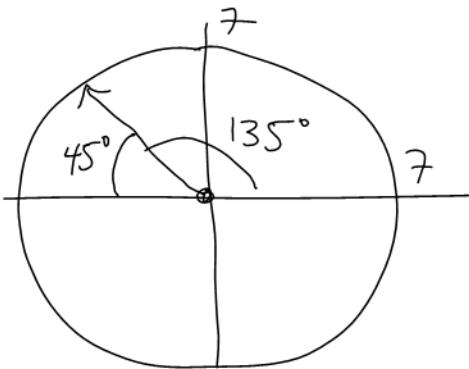


Multiply by  $\frac{5}{2}$  :

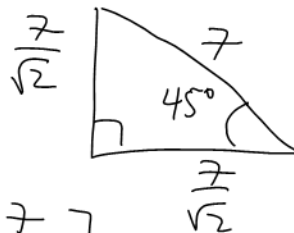


$$\vec{u} = \left[ \frac{5\sqrt{3}}{2}, \frac{5}{2} \right]$$

b) Let  $\vec{v}$  be a vector of length 7, in standard position, rotated  $135^\circ$  from the positive  $x$ -axis. Find  $\vec{v}$  algebraically.



Multiply by  $\frac{7}{\sqrt{2}}$  :



Watch signs!

$$\vec{v} = \left[ -\frac{7}{\sqrt{2}}, \frac{7}{\sqrt{2}} \right]$$

**Comment:** Vectors are often used to represent velocity, acceleration or forces. The vector's direction represents the direction of the velocity/acceleration/force. The vector's length represents the magnitude of the velocity/acceleration/force.

## 1.2 Length and Angle

**Example:** Let  $\vec{u} = [1, 4, 2, -9]$  and  $\vec{v} = [2, 3, -2, -1]$ . Calculate the dot product  $\vec{u} \cdot \vec{v}$

$$\begin{aligned}\vec{u} \cdot \vec{v} &= 1(2) + 4(3) + 2(-2) + (-9)(-1) \\ &= 19\end{aligned}$$

**Example:** Calculate:

a)  $[1, 5] \cdot [2, -3]$

$$\begin{aligned}&= 1(2) + 5(-3) \\ &= -13\end{aligned}$$

b)  $[1, 5] \cdot [2, -3, 0]$

undefined

c)  $[u_1, u_2] \cdot [u_1, u_2]$

$$\begin{aligned}&= u_1(u_1) + u_2(u_2) \\ &= u_1^2 + u_2^2\end{aligned}$$

**Fact:** Three Properties of the Dot Product

Let  $\vec{u}, \vec{v}$  be in  $\mathbb{R}^n$ . Then:

1)  $\vec{u} \cdot \vec{u} \geq 0$

2)  $\vec{u} \cdot \vec{v} = \vec{v} \cdot \vec{u}$

3)  $\vec{u} \cdot \vec{u} = 0$  if and only if  $\vec{u} = \vec{0}$

**Example:** Break Property 3 into two statements, and decide which is more obvious.