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L-15] Shortcut Method to Find A inverse of a 3x3 Matrix

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Solutions Manual Elementary Linear Algebra B.1 Exercises 1.8 1. Let $z = 5 + 9i$. Find z^{-1} . $(5 + 9i)^{-1} = \frac{5 - 9i}{5^2 + 9^2} = \frac{5 - 9i}{106} = \frac{5}{106} - \frac{9}{106}i$ 2. Let $z = 2 + 7i$ and let $w = 3 + 8i$. Find $zw, z + w, z^2$, and w/z . $62 + 5i, 5 + 45 + 28i$, and $\frac{50 - 53i}{37 + 53i}$ 3. Give the complete solution to $x^4 + 16 = 0$. $x^4 + 16 = 0$, Solution is: $(1 + i)^2, (1 + i)^2, (1 - i)^2, (1 - i)^2$ 4.

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~~Solutions Manual Elementary Linear Algebra B.1 Exercises 1~~

If (a, b, c) is a solution of the system, then $ax_1 + bx_2 + c = y_1$, $ax_2 + bx_3 + c = y_2$, and $ax_3 + bx_1 + c = y_3$ which simply means that the points are on the curve. 17. The solutions of $x_1 + kx_2 = c$ are $x_1 = c - kt$, $x_2 = t$ where t is any real number.

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2. Chapter 1: Systems of Linear Equations and Matrices. 5. (a) 6. (a) 7. (a) 8. (a) 9. The values in (a), (d), and (e) satisfy all three equations; these 3-tuples are solutions ...

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By using (1), the corresponding set of linear equations for the system is We use the method of Gaussian-Jordan elimination to solve this system. The augmented matrix is Multiplying the first row by

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The solutions of $x_1 + kx_2 = c$ are $x_1 = c - kt$, $x_2 = t$ where t is any real number. If these satisfy $x_1 + x_2 = d$, then $c - kt + t = d$, or $(-k)t = d - c$ for all real numbers t .

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Solution 1.5.3. Since every point on $\tilde{\gamma}$ must lie on the given plane, we insert x, y and z , given by the parametric equation for $\tilde{\gamma}$, into the equation of the plane. This leads to $2 + 3(2t+1) + b(2t+1) + 1 - 9(6t+6) = 1$. Simplifying and collecting coefficients of t in the above relation, we obtain $(18 + 18b)t + 9b - 9 = 0$ for all $t \in \mathbb{R}$.

~~Problems, Theory and Solutions in Linear Algebra~~

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Adding the first equation to the second equation produces a new second equation, $7x = 42$ or $x = 6$. Multiplying the first equation by 40 and the second equation by 50 produces new equations. So, 6...

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The elementary matrix E which results from I_n by a type I interchange of the i th and j th row differs from I_n by having 1's in the (i, j) and (j, i) positions and 0's in the (i, i) and (j, j) positions. For that E , EA has as its i th row the j th row of A and for its j th row the i th row of A .

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