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be the matrix $\begin{pmatrix} 2 & 4 & 0 & -3 \\ -4 & -2 & 6 & 13 \\ -1 & 0 & 2 & -2 \end{pmatrix}$ (4

points) If A is the matrix

for a linear transformation

$T: \mathbb{R}^n \rightarrow \mathbb{R}^m$, what are m

and n? Answer: m = 4, n

= 3. (b) (8 points) Find a

basis for $\text{im}A$. Answer:

Row-reduce A: $\begin{pmatrix} 2 & 4 & 0 & -3 \end{pmatrix}$

$\begin{pmatrix} -4 & -2 & 6 & 13 \\ 1 & 2 & 0 & -3 \\ 2 & -2 & 0 & 2 \end{pmatrix} \Rightarrow \begin{pmatrix} 1 & 2 & 0 & -3 \\ 2 & -2 & 0 & 2 \\ -1 & 0 & 2 & -2 \end{pmatrix}$

Math 313 (Linear Algebra)

Exam 2 - Practice Exam

MATH 2120 - Midterm Exam

#2 (SOLUTIONS) 20

March 2014 /8 Problem 5:

Let $T(x)$ be the linear

transformation on \mathbb{R}^2 that

performs clockwise rota-

tion by 30° followed by

reflection across the y-

axis. (a) Find the matrix A

such that $T(x) = Ax$.

Math 313 (Linear Algebra)

Exam 2 - Practice Exam

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which require a written

answer, show all your work.

Full credit will be given on-

ly if the necessary work is

shown justifying your

answer. Simplify your

answers. Scientific calculators

are allowed.

2. Let A denote the matrix

$A = \begin{pmatrix} -\sqrt{3} & 2 & -1 & 1 \\ 2 & -\sqrt{3} & 2 & \# \end{pmatrix}$. Let $T: \mathbb{R}^2 \rightarrow \mathbb{R}^2$ be

the linear transformation

given by $T(\tilde{x}) = A\tilde{x}$. (a)

(5 points) Describe T

geometrically. Answer: For

any angle θ , the matrix for

counterclockwise rotation-

by θ is $\begin{pmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{pmatrix}$.

Since $\cos(5\pi/6) = -\sqrt{3}/2$

and $\sin(5\pi/6) = 1/2$,

we see that T is rotation

by $5\pi/6 = 150^\circ$.

MATH15a: Linear Algebra

Practice Final Exam, Solu-

tions

Linear Algebra Midterm Exam Solutions

The only solution to 2. this

linear system is $x =$

$(A^{-1})b = A^{-1}(A^{-1}b) = \begin{pmatrix} 2 & 4 & 2 \\ 3 & 3 & 2 \\ 1 & 0 & 1 \\ 1 & 1 & 3 \\ 5 & 0 & 2 \end{pmatrix} @ \begin{pmatrix} 2 \\ 4 \\ 2 \\ 3 & 3 & 2 \\ 0 & 1 & 1 \\ 3 & 5 & 1 \\ 2 & 4 & 2 \\ 3 & 3 & 2 \\ 1 & 0 & 1 \\ 1 & 1 & 3 \\ 5 & 2 & 4 \\ 0 & 1 & 0 \\ 3 & 5 & 2 \\ 4 & 3 & 1 \\ 1 & 1 & 3 \\ 5 & 5 & 5 \end{pmatrix}$.

Suppose A is a 4 x 3 matrix and

that the linear system $Ax = b$

has exactly one solution for

some 4-vector b.

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Algebra I Instructor:

Richard Taylor MIDTERM

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whole exam before begin-

ning. 2. Make sure you

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count. 4. Justify your answers. 5. Clearly show your work. MATH ...

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Let P denote the vector space of all polynomials, and let P_2 be the set of all polynomials of degree at most 2; that is, $P_2 = \{p(t) : p(t) = a_0 + a_1t + a_2t^2; a_0, a_1, a_2 \text{ real}\}$. (a) Show that P_2 is a subspace of P . (b) Using coordinate vectors, show that the set B given by $B = \{f_1 + t^2, 2t + 3t^2, 1 + 2t + 4t^2\}$ is a basis for P_2 .

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$T : \mathbb{R}^n \rightarrow \mathbb{R}^m$, what are m and n ? Answer: $m = 4$, $n = 3$. (b) (8 points) Find a basis for $\text{im}A$. Answer:
 Row-reduce A : $\begin{bmatrix} 2 & 4 & 0 & -3 \\ -4 & -2 & 6 & 13 \\ 1 & 2 & 0 & -3 \\ 2 & -2 & -4 & -2 \end{bmatrix} \xrightarrow{R_1 \leftrightarrow R_3} \begin{bmatrix} 1 & 2 & 0 & -3 \\ -4 & -2 & 6 & 13 \\ 2 & 4 & 0 & -3 \\ 2 & -2 & -4 & -2 \end{bmatrix} \xrightarrow{R_2 + 4R_1, R_3 - 2R_1, R_4 - 2R_1} \begin{bmatrix} 1 & 2 & 0 & -3 \\ 0 & 6 & 6 & 1 \\ 0 & 0 & 0 & 3 \\ 0 & -6 & -4 & 4 \end{bmatrix} \xrightarrow{R_2 \leftrightarrow R_3} \begin{bmatrix} 1 & 2 & 0 & -3 \\ 0 & 6 & 6 & 1 \\ 0 & 0 & 0 & 3 \\ 0 & -6 & -4 & 4 \end{bmatrix} \xrightarrow{R_2 \cdot \frac{1}{6}, R_4 + R_2} \begin{bmatrix} 1 & 2 & 0 & -3 \\ 0 & 1 & 1 & \frac{1}{6} \\ 0 & 0 & 0 & 3 \\ 0 & 0 & -4 & \frac{25}{6} \end{bmatrix} \xrightarrow{R_4 + 4R_2} \begin{bmatrix} 1 & 2 & 0 & -3 \\ 0 & 1 & 1 & \frac{1}{6} \\ 0 & 0 & 0 & 3 \\ 0 & 0 & 0 & \frac{23}{6} \end{bmatrix} \xrightarrow{R_4 - 3R_2} \begin{bmatrix} 1 & 2 & 0 & -3 \\ 0 & 1 & 1 & \frac{1}{6} \\ 0 & 0 & 0 & 3 \\ 0 & 0 & 0 & 0 \end{bmatrix} \xrightarrow{R_1 - 2R_2} \begin{bmatrix} 1 & 0 & -2 & -\frac{5}{3} \\ 0 & 1 & 1 & \frac{1}{6} \\ 0 & 0 & 0 & 3 \\ 0 & 0 & 0 & 0 \end{bmatrix} \xrightarrow{R_1 + 2R_2} \begin{bmatrix} 1 & 0 & 0 & -\frac{1}{3} \\ 0 & 1 & 1 & \frac{1}{6} \\ 0 & 0 & 0 & 3 \\ 0 & 0 & 0 & 0 \end{bmatrix} \xrightarrow{R_1 + \frac{1}{3}R_3} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 1 & \frac{1}{6} \\ 0 & 0 & 0 & 3 \\ 0 & 0 & 0 & 0 \end{bmatrix} \xrightarrow{R_2 - \frac{1}{3}R_3} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 1 & 0 \\ 0 & 0 & 0 & 3 \\ 0 & 0 & 0 & 0 \end{bmatrix} \xrightarrow{R_2 - R_1} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 3 \\ 0 & 0 & 0 & 0 \end{bmatrix}$

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2. Let A denote the matrix $A = \begin{bmatrix} \sqrt{3} & 2 \\ -1 & 1 \end{bmatrix}$. Let $T : \mathbb{R}^2 \rightarrow \mathbb{R}^2$ be the linear transformation given by $T(\sim x) = A\sim x$. (a) (5 points) Describe T geometrically. Answer: For any angle θ , the matrix for counterclockwise rotation by θ is $\begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix}$. Since $\cos(5\pi/6) = -\sqrt{3}/2$ and $\sin(5\pi/6) = 1/2$, we see that T is rotation by $5\pi/6 = 150^\circ$.

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2 Solution: Using the "standard" basis $1, x, x^2$, the vectors of B are the columns of the matrix $A = \begin{pmatrix} 1 & 0 & 0 \\ 2 & 1 & 1 \\ 0 & -1 & 1 \end{pmatrix}$ It thus suffices to check that the three columns of A are lin.

independent. This is equivalent to the matrix having 3 pivots, non-zero determinant, etc. Pick your favorite condition, and check it. 4

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Write the vector $u = (1, -2, 5) \in \mathbb{R}^3$ as a linear combination of the vectors $u_1 = (1, 1, 1)$, $u_2 = (1, 2, 3)$, $u_3 = (2, -1, 1)$ b. Show that the vector $v = (2, -5, 3) \in \mathbb{R}^3$ cannot be expressed as a linear combination of the vectors $v_1 = (1, -3, 2)$, $v_2 = (2, -4, -1)$, $v_3 = (1, -5, 7)$. c.

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ear combination of the vectors $v_1=(1,-3,2)$, $v_2=(2,-4,-1)$, $v_3=(1,-5,7)$. c.

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2 Solution: Using the "standard" basis $1, x, x^2$, the vectors of B are the columns of the matrix $A = \begin{pmatrix} 1 & 0 & 0 \\ 2 & 1 & 1 \\ 0 & -1 & 1 \end{pmatrix}$ It thus suffices to check that the three columns of A are linearly independent. This is equivalent to the matrix having 3 pivots, non-zero determinant, etc. Pick your favorite condition, and check it. 4

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