The definition of a vector space $(V, +, \cdot)$

1. For any $\vec{u}$ and $\vec{v}$ in V, $\vec{u} + \vec{v}$ is also in V.
2. For any $\vec{u}$ and $\vec{v}$ in V, $\vec{u} + \vec{v} = \vec{v} + \vec{u}$.
3. For any $\vec{u}$, $\vec{v}$, $\vec{w}$ in V, $\vec{u} + (\vec{v} + \vec{w}) = (\vec{u} + \vec{v}) + \vec{w}$.
4. There is an element in V called the *zero* or *null* vector, which we denote by $\vec{0}$, such that for all $\vec{u}$ in V we have $\vec{0} + \vec{u} = \vec{u}$.
5. For every $\vec{u}$ in V, there is a vector called the *negative* of $\vec{u}$ and denoted $-\vec{u}$, such that $-\vec{u} + \vec{u} = \vec{0}$.
6. If k is any scalar in $\mathbb{R}$ and $\vec{u}$ is any vector in V, then $k \cdot \vec{u}$ is a vector in V.
7. For any scalar k in $\mathbb{R}$ and any vectors $\vec{u}$ and $\vec{v}$ in V, $k \cdot (\vec{u} + \vec{v}) = k \cdot \vec{u} + k \cdot \vec{v}$.
8. For any scalars k and m in $\mathbb{R}$ and any vector $\vec{u}$ in V, $(k + m) \cdot \vec{u} = k \cdot \vec{u} + m \cdot \vec{u}$.
9. For any scalars k and m in $\mathbb{R}$ and any vector $\vec{u}$ in V, $k \cdot (m \cdot \vec{u}) = (k\,m) \cdot \vec{u}$.
10. For any vector $\vec{u}$ in V, $1 \cdot \vec{u} = \vec{u}$.

What determines a vector space?

- A nonempty set V whose elements are called *vectors*.
- An operation $+$ called vectors addition, such that

  $$\text{vector} \ + \ \text{vector} \ = \ \text{vector}$$

  In other words, we have *closure* under vector addition.
- An operation $\cdot$ called scalar multiplication, such that

  $$\text{scalar} \ \cdot \ \text{vector} \ = \ \text{vector}$$

  In other words, we have *closure* under scalar multiplication.
- The remaining 8 axioms are all satisfied.

Some basic identities in a vector space

Theorem: Let V be a vector space. The following statements are always true.

a) $0 \cdot \vec{u} = \vec{0}$
b) $k \cdot \vec{0} = \vec{0}$
c) $(-1) \cdot \vec{u} = -\vec{u}$
d) If $k \cdot \vec{u} = \vec{0}$ then $k = 0$ or $\vec{u} = \vec{0}$.

Vector subspace

Let $(V, +, \cdot)$ be a vector space.

Definition: A subset W of V is called a *subspace* if W is itself a vector space with the operations $+$ and $\cdot$ defined on V.

Theorem: Let W be a nonempty subset of V. Then W is a subspace of V if and only if it is *closed* under addition and scalar multiplication, in other words, if:

i.) For any $\vec{u}, \vec{v}$ in W, we have $\vec{u} + \vec{v}$ is in W.

ii.) For any scalar k and any vector $\vec{u}$ in W we have $k \cdot \vec{u}$ is in W.

Linear combinations and the span of a set of vectors

Let $(V, +, \cdot)$ be a vector space.

Definition: Let $\vec{v}$ be a vector in V. We say that $\vec{v}$ is a *linear combination* of the vectors $\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}$ if there are scalars $k_1, k_2, \ldots, k_r$ such that

$$\vec{v} = k_1 \cdot \vec{v_1} + k_2 \cdot \vec{v_2} + \ldots + k_r \cdot \vec{v_r}$$

The scalars $k_1, k_2, \ldots, k_r$ are called the *coefficients* of the linear combination.

Definition: Let $S = \{\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}\}$ be a set of vectors in V.
Let W be the set of all linear combinations of $\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}$:

$$W = \{k_1 \cdot \vec{v_1} + k_2 \cdot \vec{v_2} + \ldots + k_r \cdot \vec{v_r} \ : \ \text{for all choices of scalars } k_1, k_2, \ldots, k_r\}$$

Then W is called the *span* of the set S.
We write:

$$W = \text{ span } S \quad \text{or} \quad W = \text{ span } \{\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}\}$$

Linear combinations and the span of a set of vectors

Let $(V, +, \cdot)$ be a vector space and let $S = \{\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}\}$ be a set of vectors in V.

$$\text{span}S = \{k_1 \cdot \vec{v_1} + k_2 \cdot \vec{v_2} + \ldots + k_r \cdot \vec{v_r} \ : \ \text{for all scalars } k_1, k_2, \ldots, k_r\}$$

(all linear combinations of $\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}$).

Theorem: span $\{\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}\}$ is a subspace of V.
It is in fact the *smallest* subspace of V that contains all vectors $\{\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}\}$.

Linear independence in a vector space V

Let V be a vector space and let $S = \{\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}\}$ be a set of vectors in V.

Definition: The set S is called *linearly independent* if the vector equation

$$(*) \quad c_1 \cdot \vec{v_1} + c_2 \cdot \vec{v_2} + \ldots + c_r \cdot \vec{v_r} = \vec{0}$$

has only one solution, the trivial one:

$$c_1 = 0,\ c_2 = 0,\ \ldots, c_r = 0$$

The set is called linearly dependent otherwise, if equation (*) has other solutions besides the trivial one.

Theorem: The set of vectors S is linearly independent if and only if no vector in the set is a linear combination of the other vectors in the set.

The set of vectors S is linearly dependent if and only if one of the vectors in the set is a linear combination of the other vectors in the set.

The solutions to a homogeneous system of equations $A \cdot \vec{x} = \vec{0}$

Consider a *homogeneous* system of m equations with n unknowns.

In other words,

- let A be an $m \times n$ matrix
- let $\vec{x}$ be an $n \times 1$ matrix (or vector) whose entries are the unknowns $x_1, x_2, \ldots, x_n$
- let $\vec{0}$ denote the $n \times 1$ matrix (vector) whose entries are all 0.

The system can then be written as

$$A \cdot \vec{x} = \vec{0}$$

Theorem: The set of solutions to a *homogeneous* system of m equations with n unknowns is a subspace of $\mathbb{R}^n$.

Reminder from MA1201 on systems of equations

The case when $\boxed{\# \text{ of equations} = \# \text{ of unknowns}}$

Theorem: Let A be a square matrix in $\mathbf{M}_{n\,n}$.
The following statements are equivalent:

1. A is invertible
2. $\det(A) \neq 0$
3. The homogeneous system $A \cdot \vec{x} = \vec{0}$ has only the trivial solution
4. The system of equations $A \cdot \vec{x} = \vec{b}$ has exactly one solution for every vector $\vec{b}$ in $\mathbb{R}^n$.

The case when $\boxed{\# \text{ of unknowns} > \# \text{ of equations}}$

Theorem: Let A be a matrix in $\mathbf{M}_{m\,n}$, where $n > m$.
Then the homogeneous system $A \cdot \vec{x} = \vec{0}$ has infinitely many solutions.

Basis in a vector space V

Definition: A set $S = \{\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}\}$ of vectors is called a *basis* for V if

1. S is linearly independent
2. $\text{span}\,(S) = V$.

In other words, the set $S = \{\vec{v_1}, \vec{v_2}, \ldots, \vec{v_r}\}$ is a basis for V if

1. The equation $c_1 \cdot \vec{v_1} + c_2 \cdot \vec{v_2} + \ldots + c_r \cdot \vec{v_r} = \vec{0}$ has only the trivial solution.
2. The equation $c_1 \cdot \vec{v_1} + c_2 \cdot \vec{v_2} + \ldots + c_r \cdot \vec{v_r} = \vec{b}$ has a solution for every $\vec{b}$ in $\mathbb{R}^n$.

Standard bases for the most popular vector spaces

- In $\mathbb{R}^2$: $\{\vec{i}, \vec{j}\}$.
- In $\mathbb{R}^3$: $\{\vec{i}, \vec{j}, \vec{k}\}$.
- In $\mathbb{R}^n$: $\{e_1, e_2, \ldots, e_n\}$.
- In P_n: $1, X, X^2, \ldots, X^n$.
- In $\mathbf{M}_{2\,2}$: all matrices with all entries 0 except for one entry, which is 1. There are 4 such matrices.
- In $\mathbf{M}_{m\,n}$: all matrices with all entries 0 except for one entry, which is 1. There are $m \cdot n$ such matrices.