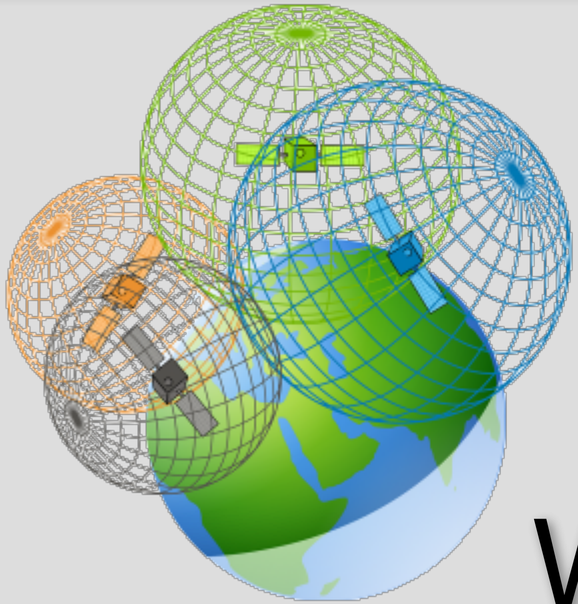
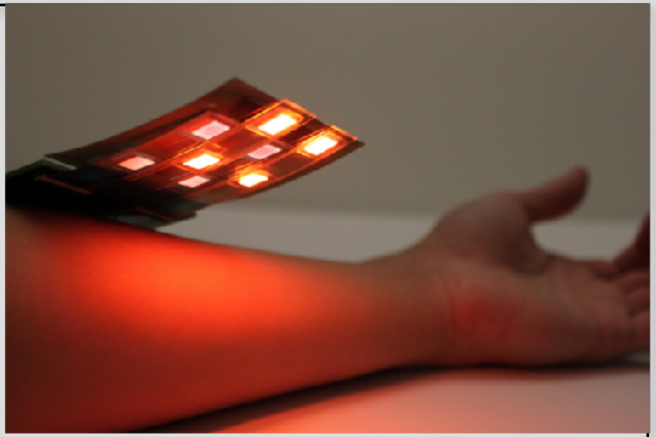




Welcome to EECS 16A!

Designing Information Devices and Systems I

Ana Arias and Miki Lustig

2022

Lecture 12A

Tri-Lateration, Projections

Good morning!

Last time:

- Computing delay with cross-correlation

Today:

- Finding position with multi-lateration
- Projections
- Least Squares (Maybe)

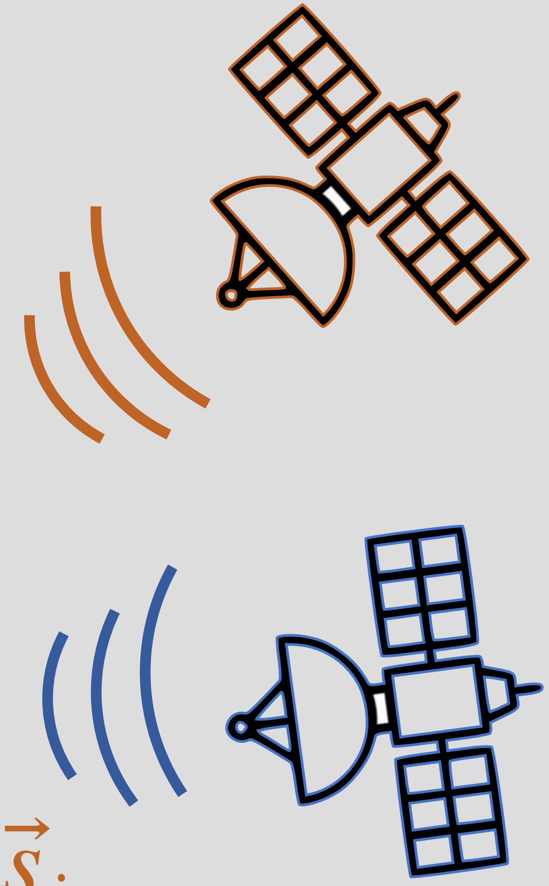
Localization

- Satellites transmit a unique code
  - Radio signal
- Signal is received and digitized by a receiver

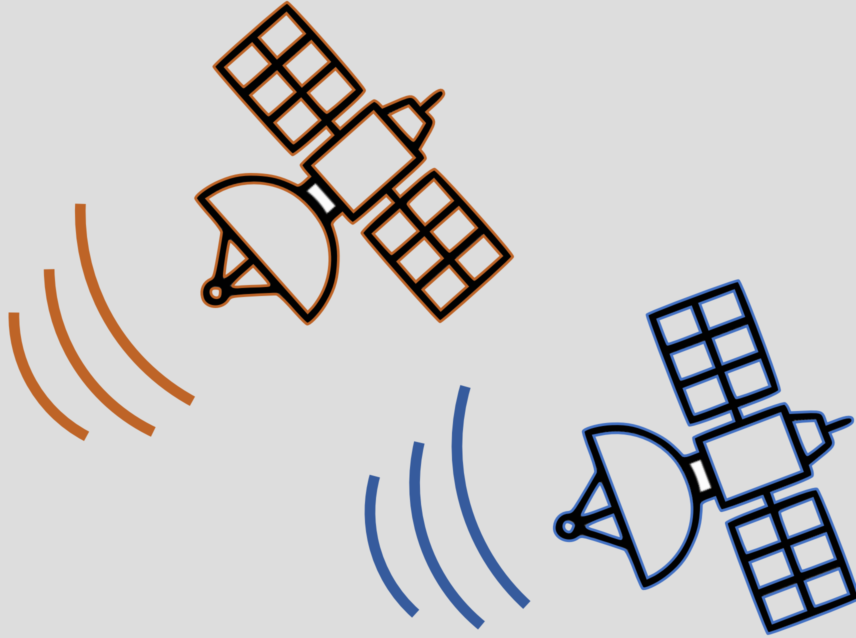
Two problems:

1. Interference
2. Timing

What are good properties for the codes $\vec{s}_i$



Received Signal

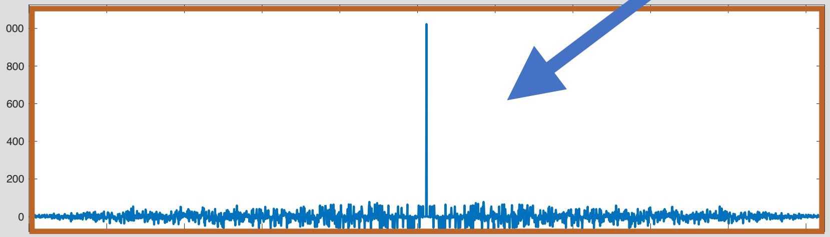


$$r[n] = s_1[n - \tau_1] + s_2[n - \tau_2] + w[n]$$

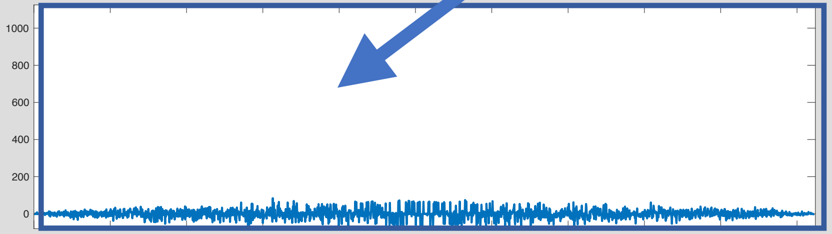
Correlate with $s_1[n]$:

$$\mathrm{corr}_{\vec{r}}(\vec{s}_1)[k] = \langle r[n], s_1[n-k] \rangle$$

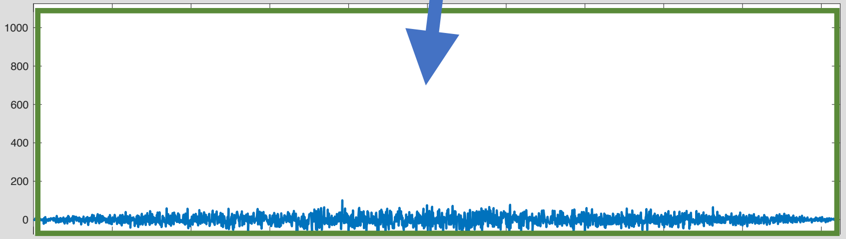
$$= \langle s_1[n-\tau_1], s_1[n-k] \rangle + \langle s_2[n-\tau_2], s_1[n-k] \rangle + \langle w[n], s_1[n-k] \rangle$$



Auto-correlation looks like an impulse



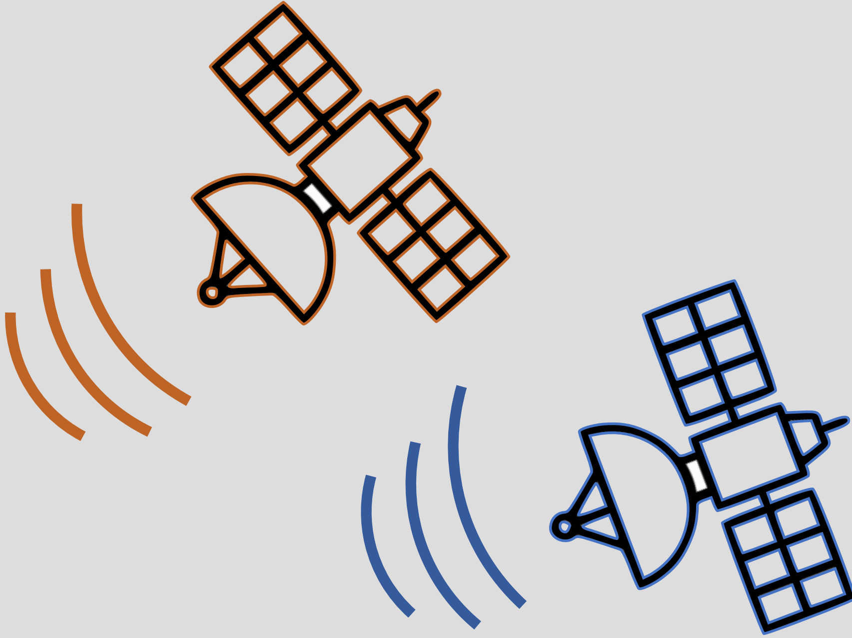
cross-correlation is small

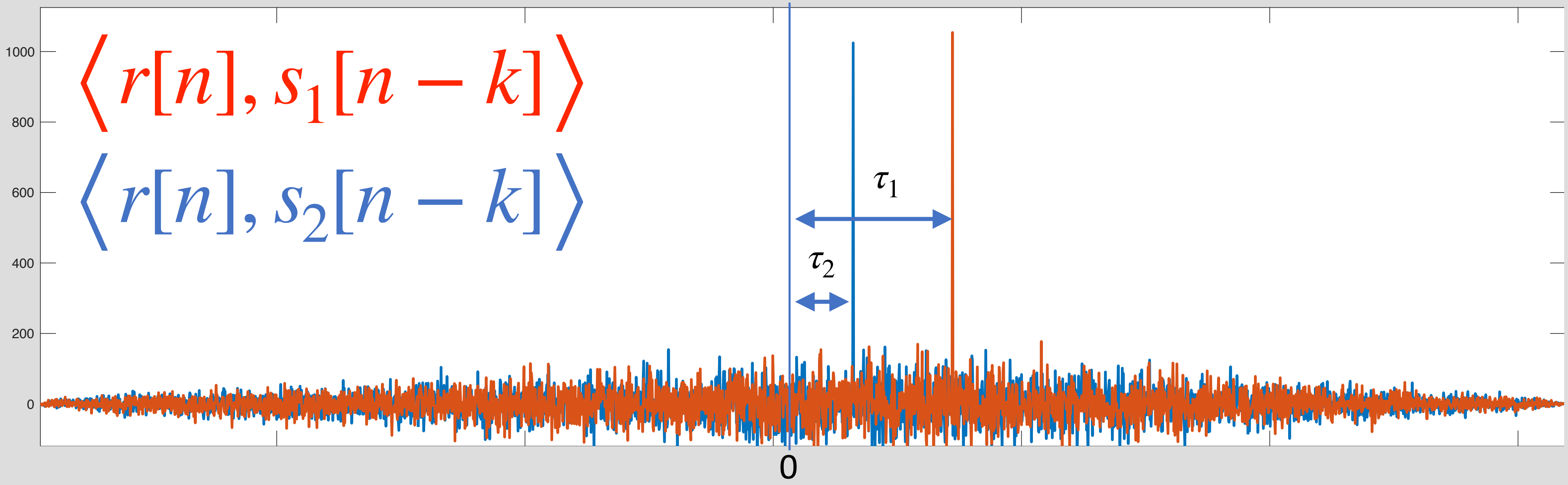


cross-correlation with noise is small (always true)

Received Signal

$$r[n] = s_1[n-\tau_1] + s_2[n-\tau_2] + w[n]$$



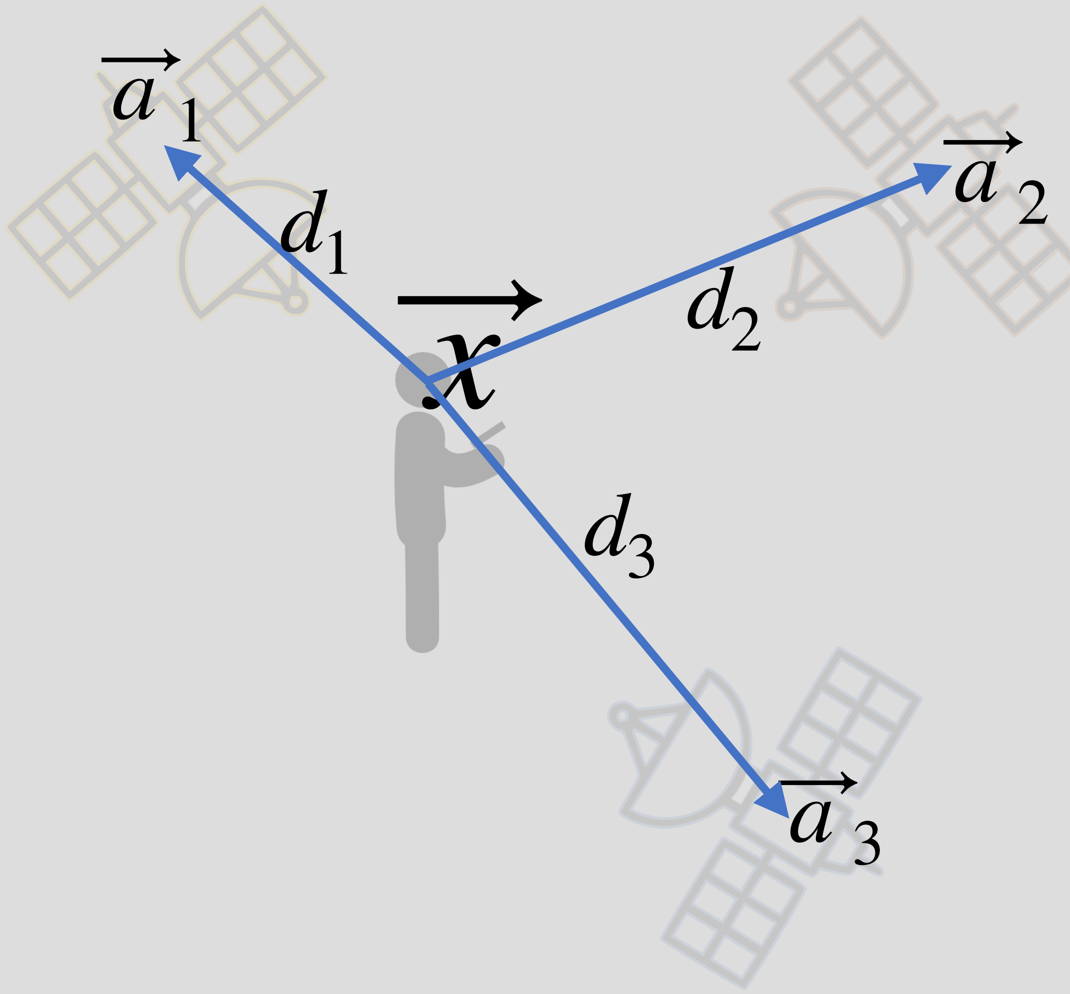


Trilateration

(1) $$\|\vec{x} - \vec{a}_1\|^2 = d_1^2$$

(2) $$\|\vec{x} - \vec{a}_2\|^2 = d_2^2$$

(3) $$\|\vec{x} - \vec{a}_3\|^2 = d_3^2$$



$$d_1 = \tau_1 C$$
$$d_2 = \tau_2 C$$
$$d_3 = \tau_3 C$$

Trilateration

(1) $\|\vec{x} - \vec{a}_1\|^2 = d_1^2$

(2) $\|\vec{x} - \vec{a}_2\|^2 = d_2^2$

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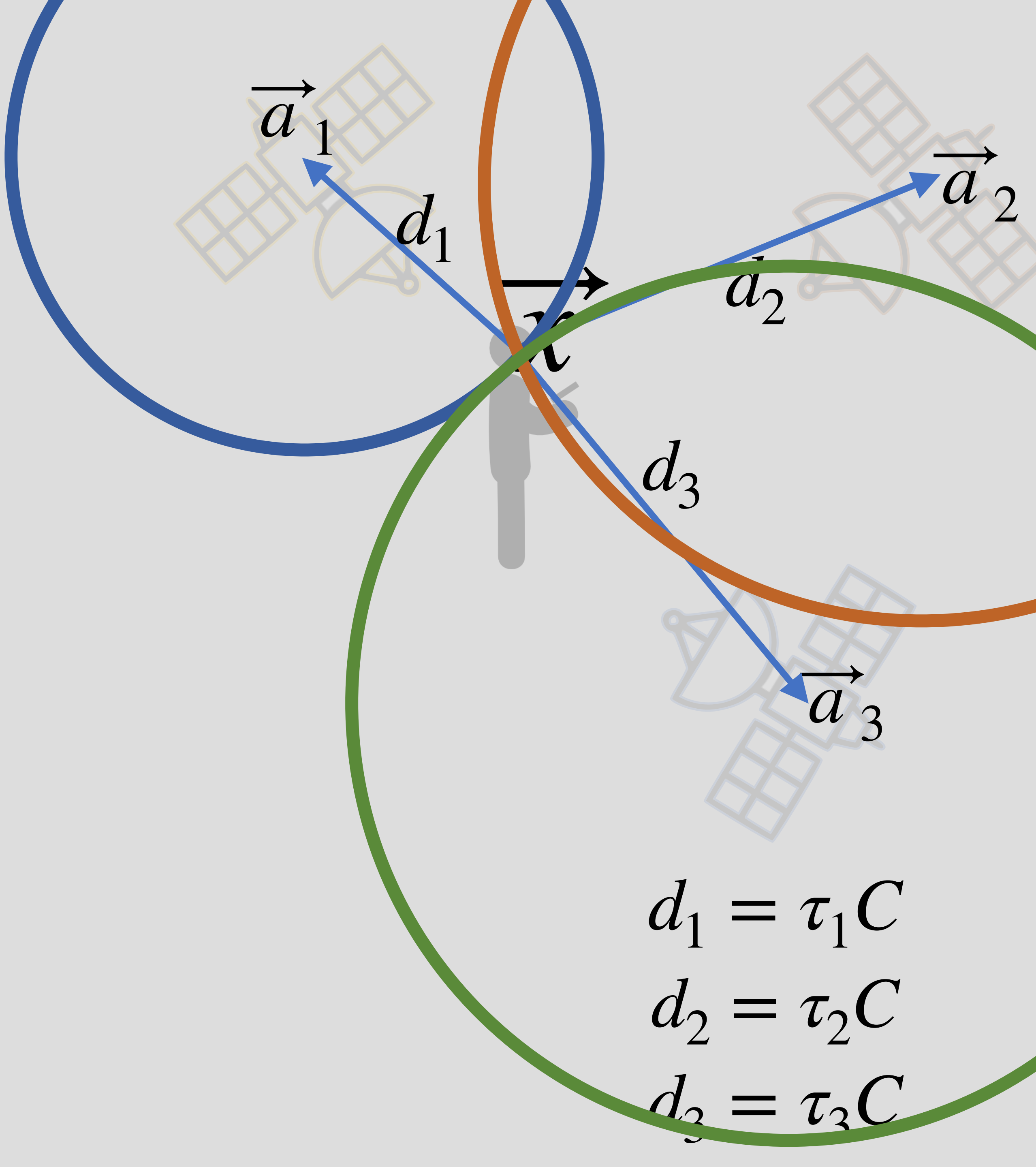

Trilateration

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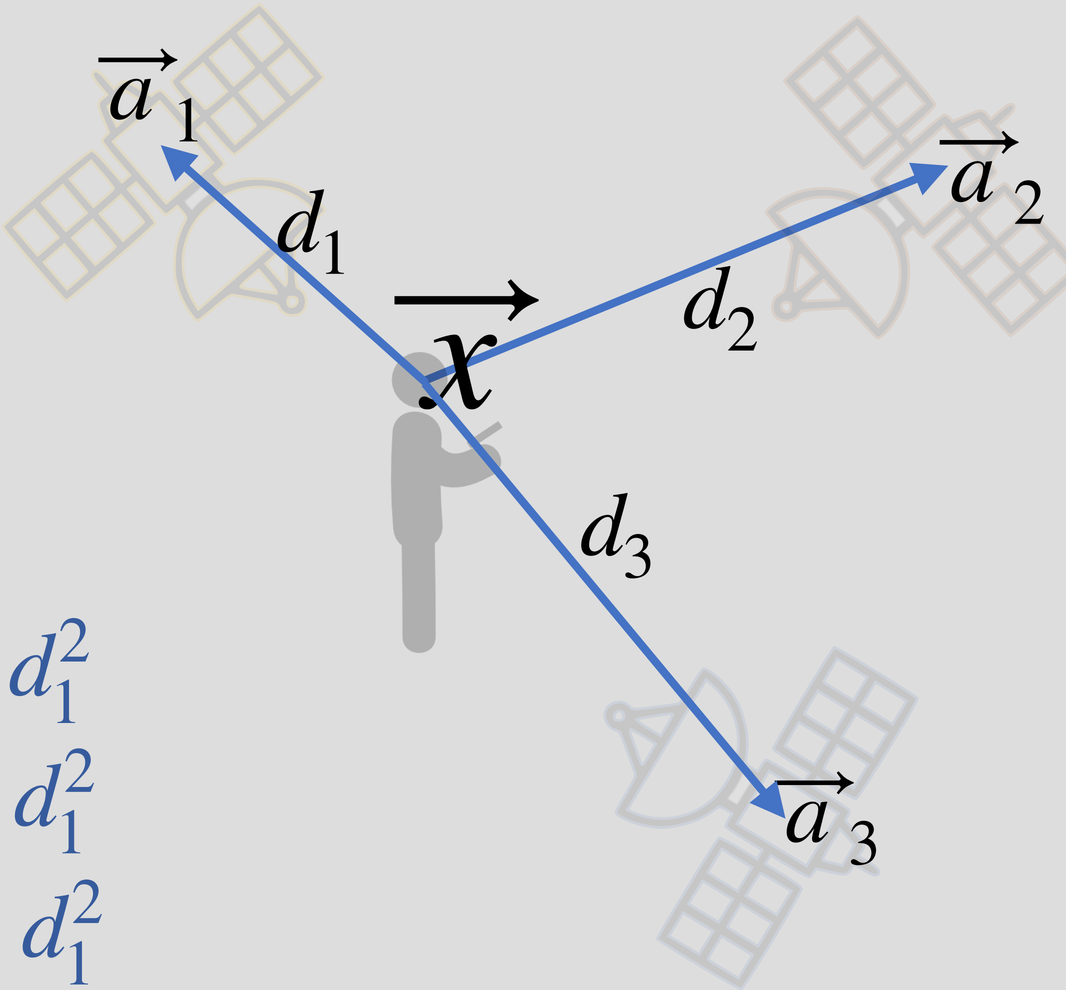


$$\|\vec{x} - \vec{a}_1\|^2 = d_1^2$$

$$(\vec{x} - \vec{a}_1)^T(\vec{x} - \vec{a}_1) = d_1^2$$

$$\vec{x}^T\vec{x} - \vec{a}_1^T\vec{x} - \vec{x}^T\vec{a}_1 + \vec{a}_1^T\vec{a}_1 = d_1^2$$

$$\|\vec{x}\|^2 - 2\vec{a}_1^T\vec{x} + \|\vec{a}_1\|^2 = d_1^2$$

$$\|\vec{x}\|^2 - 2\vec{a}_1^T\vec{x} + \|\vec{a}_1\|^2 = C^2\tau_1^2$$

$$d_1 = \tau_1 C$$

$$d_2 = \tau_2 C$$

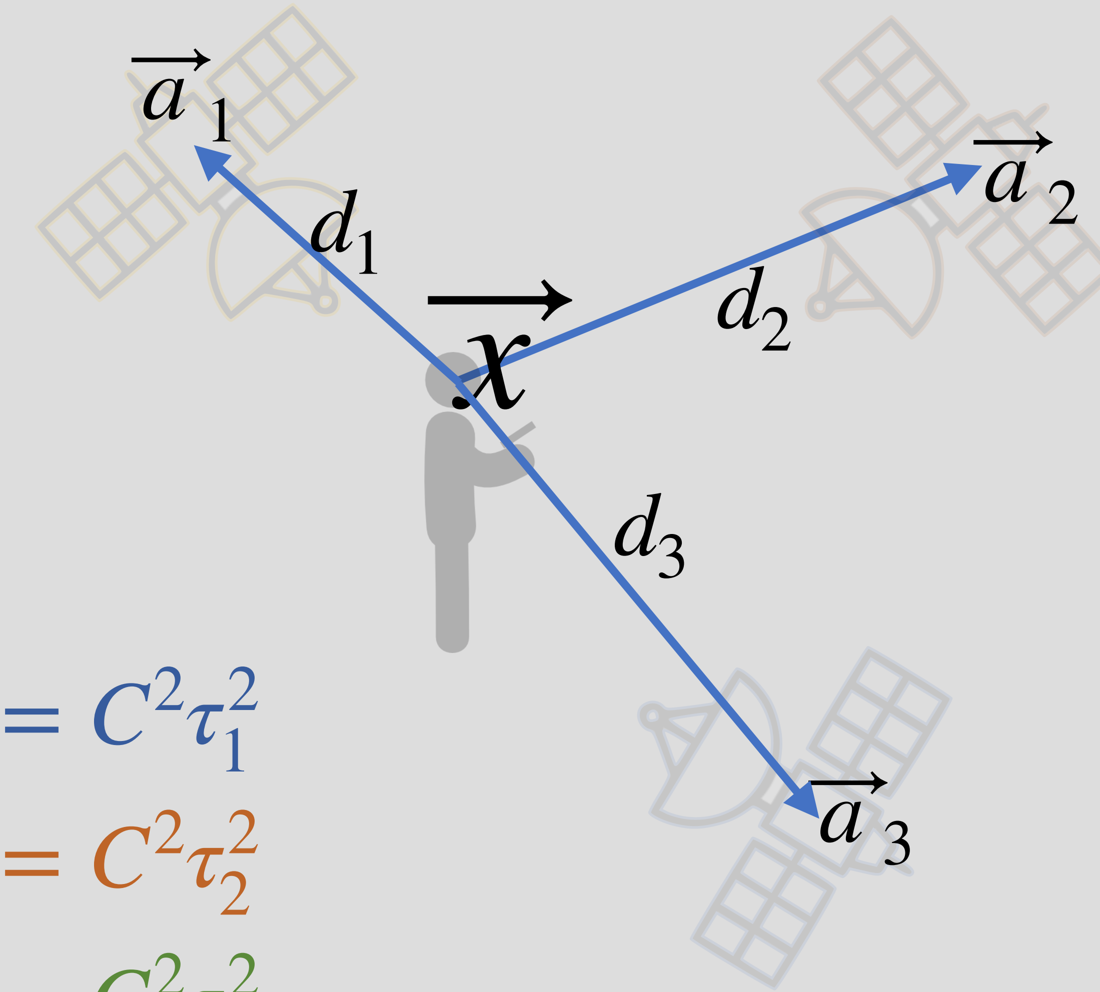
$$d_3 = \tau_3 C$$

Trilateration

(1) $$\|\vec{x} - \vec{a}_1\|^2 = d_1^2$$

(2) $$\|\vec{x} - \vec{a}_2\|^2 = d_2^2$$

(3) $$\|\vec{x} - \vec{a}_3\|^2 = d_3^2$$



(1) $$\|\vec{x}\|^2 - 2\vec{a}_1^T\vec{x} + \|\vec{a}_1\|^2 = C^2\tau_1^2$$

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(3) $$\|\vec{x}\|^2 - 2\vec{a}_3^T\vec{x} + \|\vec{a}_3\|^2 = C^2\tau_3^2$$

$$d_1 = \tau_1 C$$
$$d_2 = \tau_2 C$$
$$d_3 = \tau_3 C$$

Trilateration

(1) $\|\vec{x}\|^2 - 2\vec{a}_1^T\vec{x} + \|\vec{a}_1\|^2 = C^2\tau_1^2$

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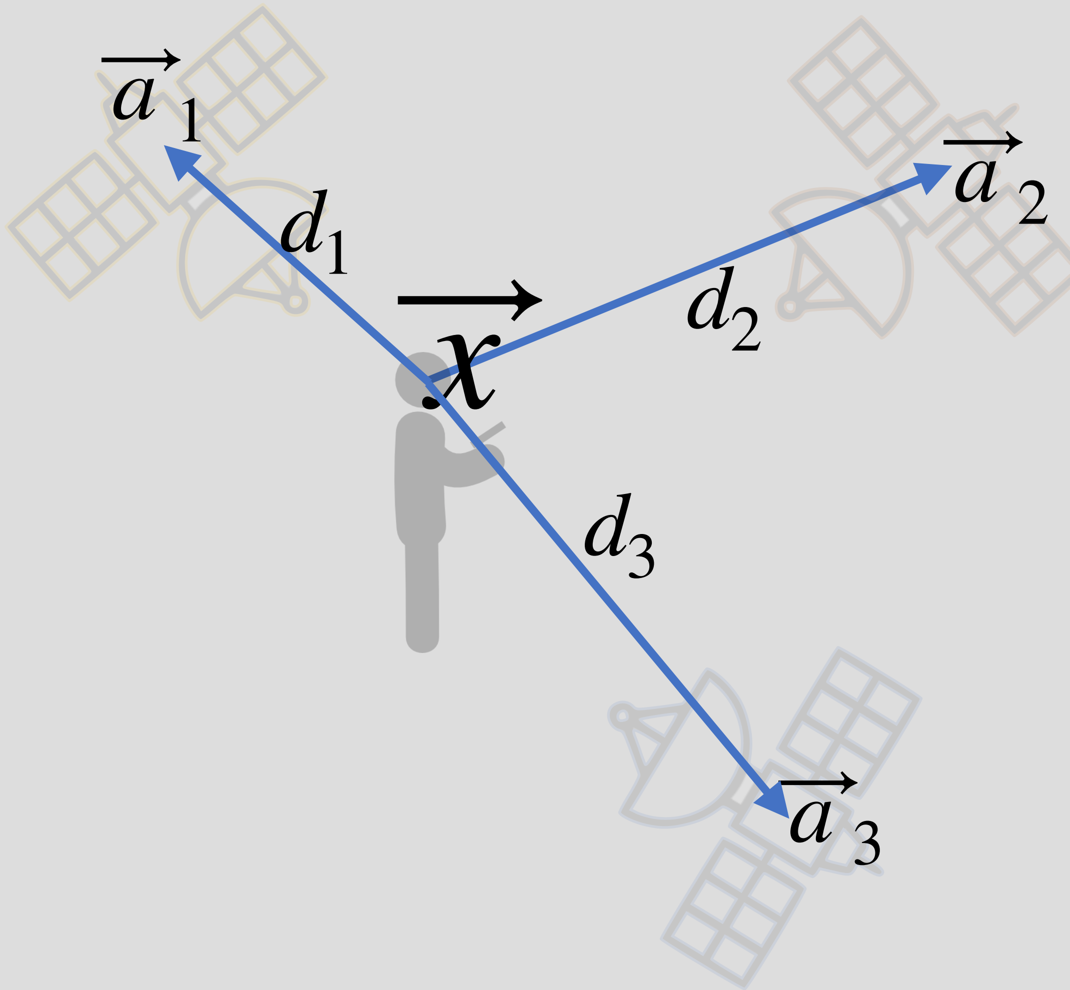
(3) $\|\vec{x}\|^2 - 2\vec{a}_3^T\vec{x} + \|\vec{a}_3\|^2 = C^2\tau_3^2$

(2) - (1)

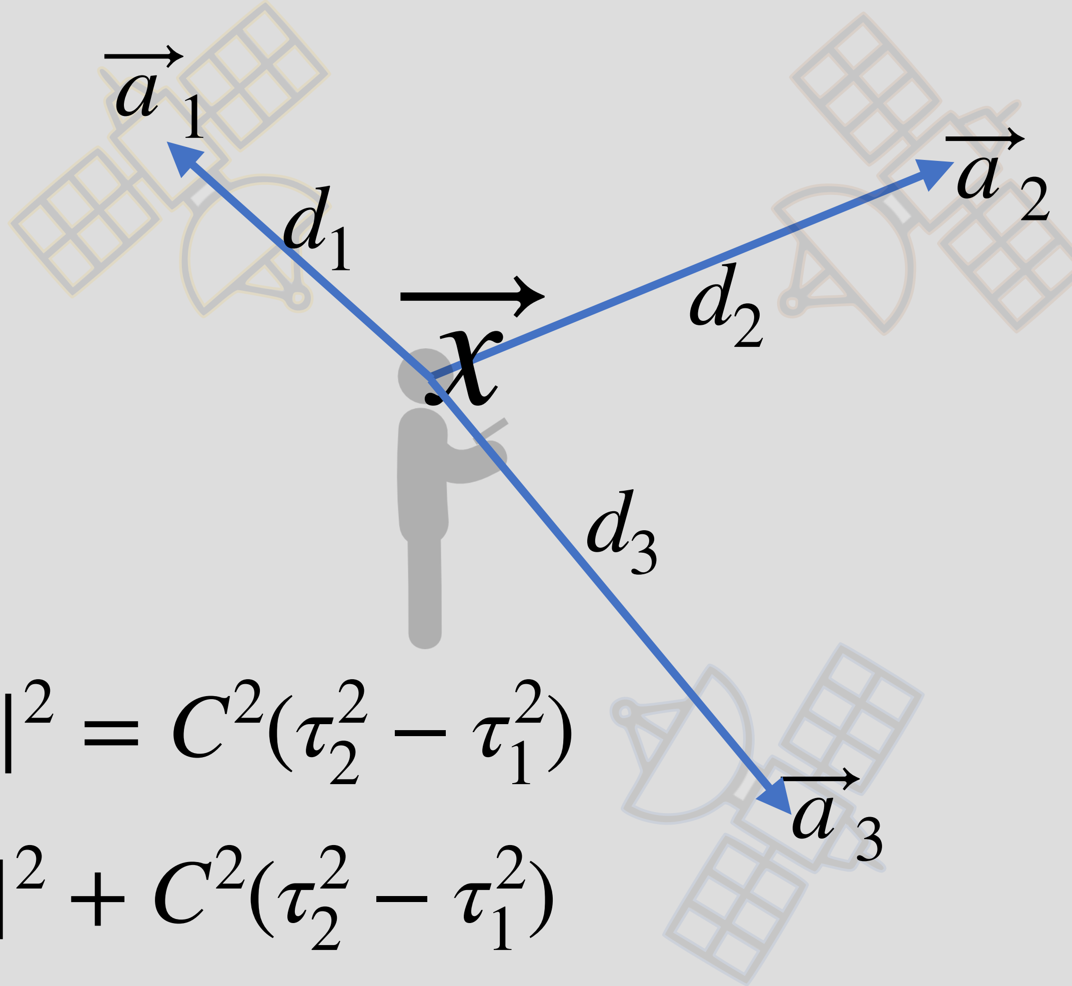


Trilateration

(1) $\|\vec{x}\|^2 - 2\vec{a}_1^T\vec{x} + \|\vec{a}_1\|^2 = C^2\tau_1^2$

(2) $\|\vec{x}\|^2 - 2\vec{a}_2^T\vec{x} + \|\vec{a}_2\|^2 = C^2\tau_2^2$

(3) $\|\vec{x}\|^2 - 2\vec{a}_3^T\vec{x} + \|\vec{a}_3\|^2 = C^2\tau_3^2$



(2) - (1)

$$-2\vec{a}_2^T\vec{x} + 2\vec{a}_1^T\vec{x} + \|\vec{a}_2\|^2 - \|\vec{a}_1\|^2 = C^2(\tau_2^2 - \tau_1^2)$$

$$2(\vec{a}_1 - \vec{a}_2)^T\vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\tau_2^2 - \tau_1^2)$$

(3) - (1)

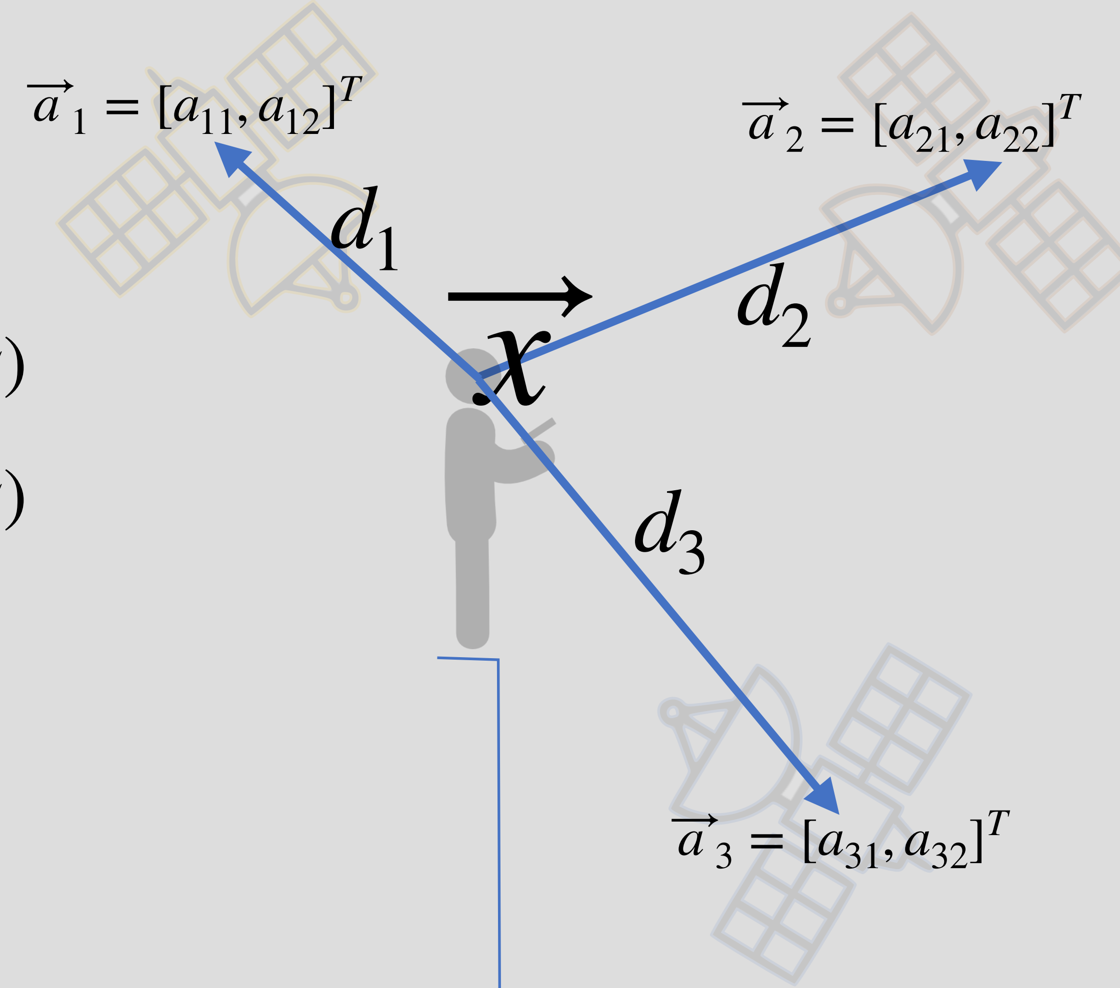
$$2(\vec{a}_1 - \vec{a}_3)^T\vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_3\|^2 + C^2(\tau_3^2 - \tau_1^2)$$

Trilateration

$$2(\vec{a}_1 - \vec{a}_2)^T \vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\tau_2^2 - \tau_1^2)$$

$$2(\vec{a}_1 - \vec{a}_3)^T \vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_3\|^2 + C^2(\tau_3^2 - \tau_1^2)$$

$$\begin{bmatrix} \quad \end{bmatrix} \begin{bmatrix} \quad \end{bmatrix} = \begin{bmatrix} \quad \end{bmatrix}$$



Trilateration

$$2(\vec{a}_1 - \vec{a}_2)^T \vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\tau_2^2 - \tau_1^2)$$

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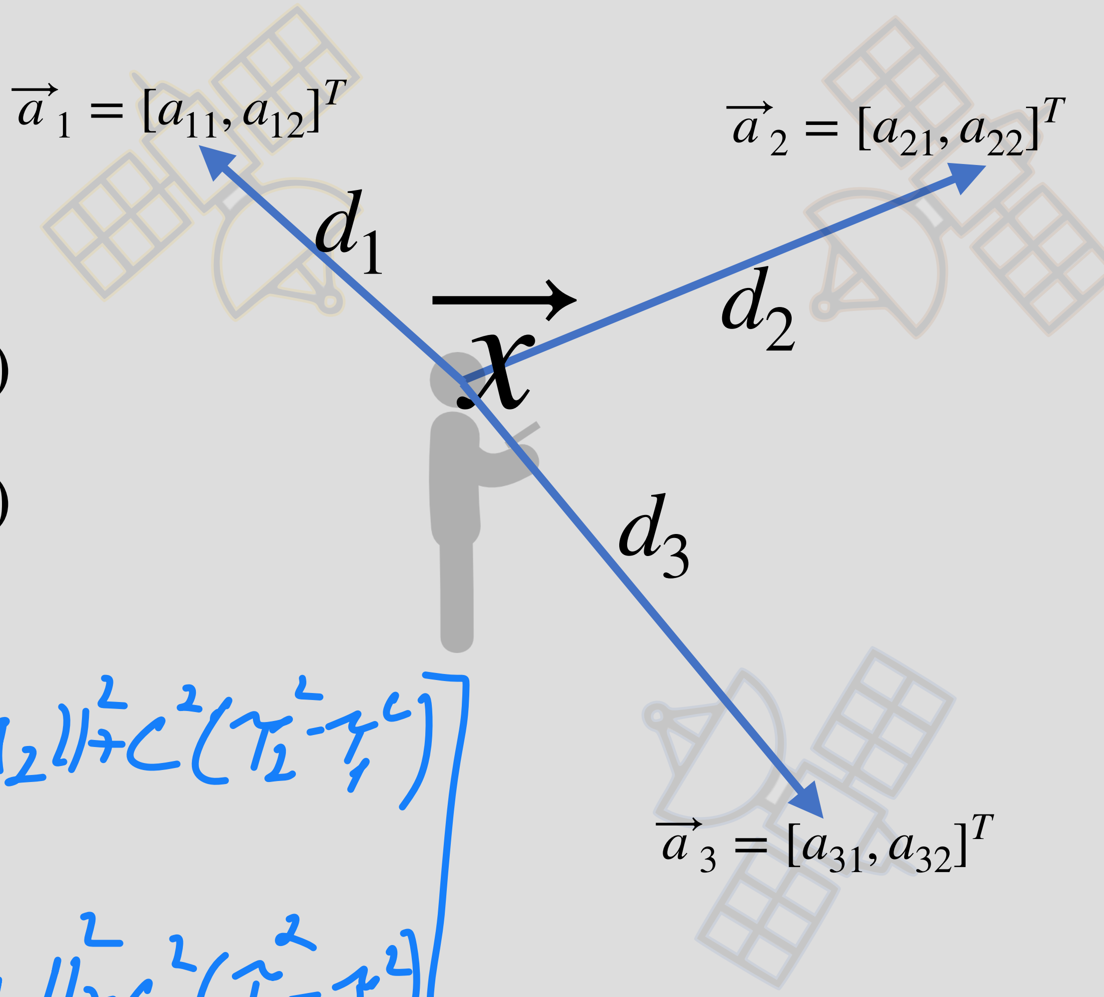


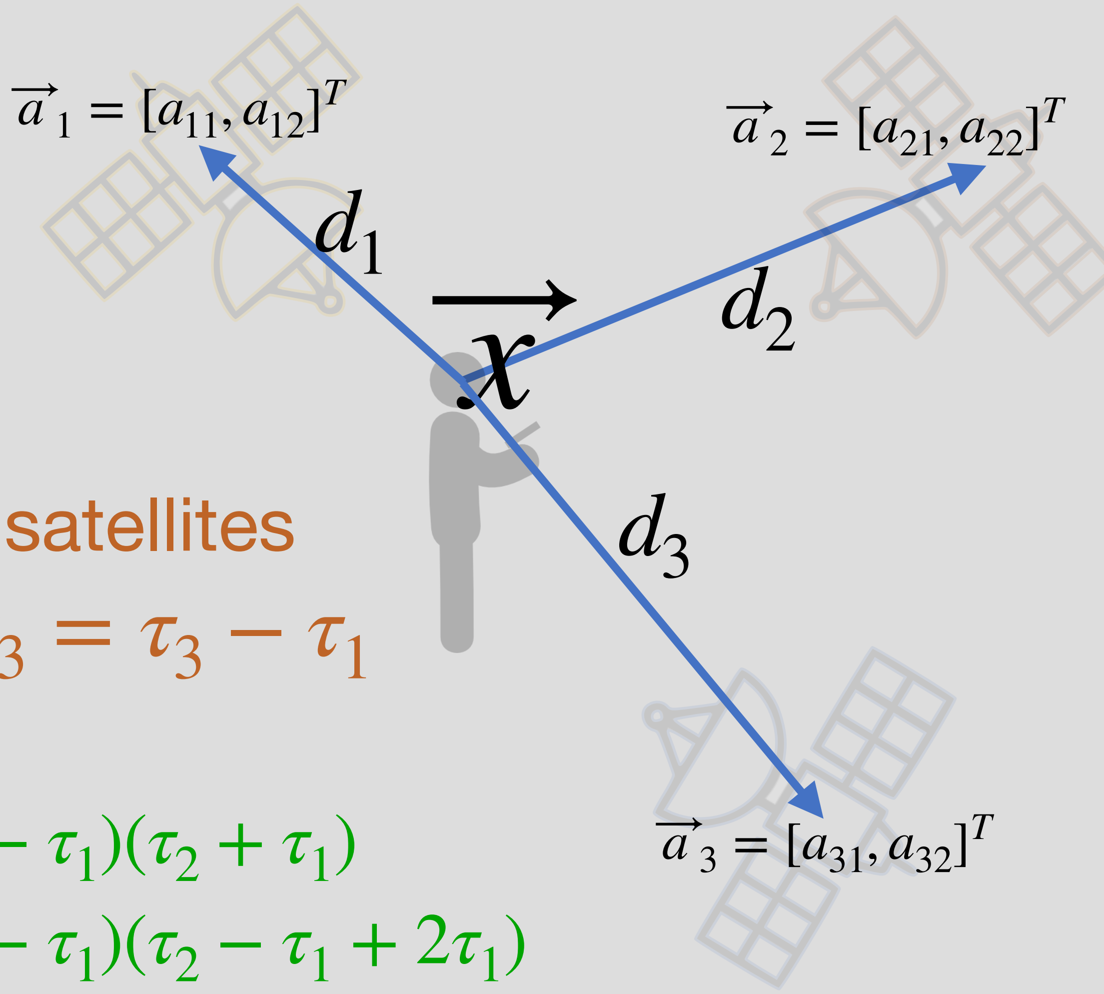
$$2\begin{bmatrix} a_{11}-a_{21} & a_{12}-a_{22} \\ a_{11}-a_{31} & a_{12}-a_{32} \end{bmatrix}\begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} \|a_1\|^2 - \|a_2\|^2 + c^2(\tau_2^2 - \tau_1^2) \\ \|a_1\|^2 - \|a_3\|^2 + c^2(\tau_3^2 - \tau_1^2) \end{bmatrix}$$

Solve via gaussian elimination!

Trilateration

$$2(\vec{a}_1 - \vec{a}_2)^T \vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\tau_2^2 - \tau_1^2)$$

$$2(\vec{a}_1 - \vec{a}_3)^T \vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_3\|^2 + C^2(\tau_3^2 - \tau_1^2)$$



Problem — receiver clock is not synced to satellites

τ_1 is unknown, but $\Delta\tau_2 = \tau_2 - \tau_1$, and $\Delta\tau_3 = \tau_3 - \tau_1$ are known

$$2(\vec{a}_1 - \vec{a}_2)^T \vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\tau_2 - \tau_1)(\tau_2 + \tau_1)$$

$$2(\vec{a}_1 - \vec{a}_2)^T \vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\tau_2 - \tau_1)(\tau_2 - \tau_1 + 2\tau_1)$$

$$2(\vec{a}_1 - \vec{a}_2)^T \vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\Delta\tau_2)(\Delta\tau_2 + 2\tau_1)$$

Trilateration

$$2(\vec{a}_1 - \vec{a}_2)^T \vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\tau_2^2 - \tau_1^2)$$

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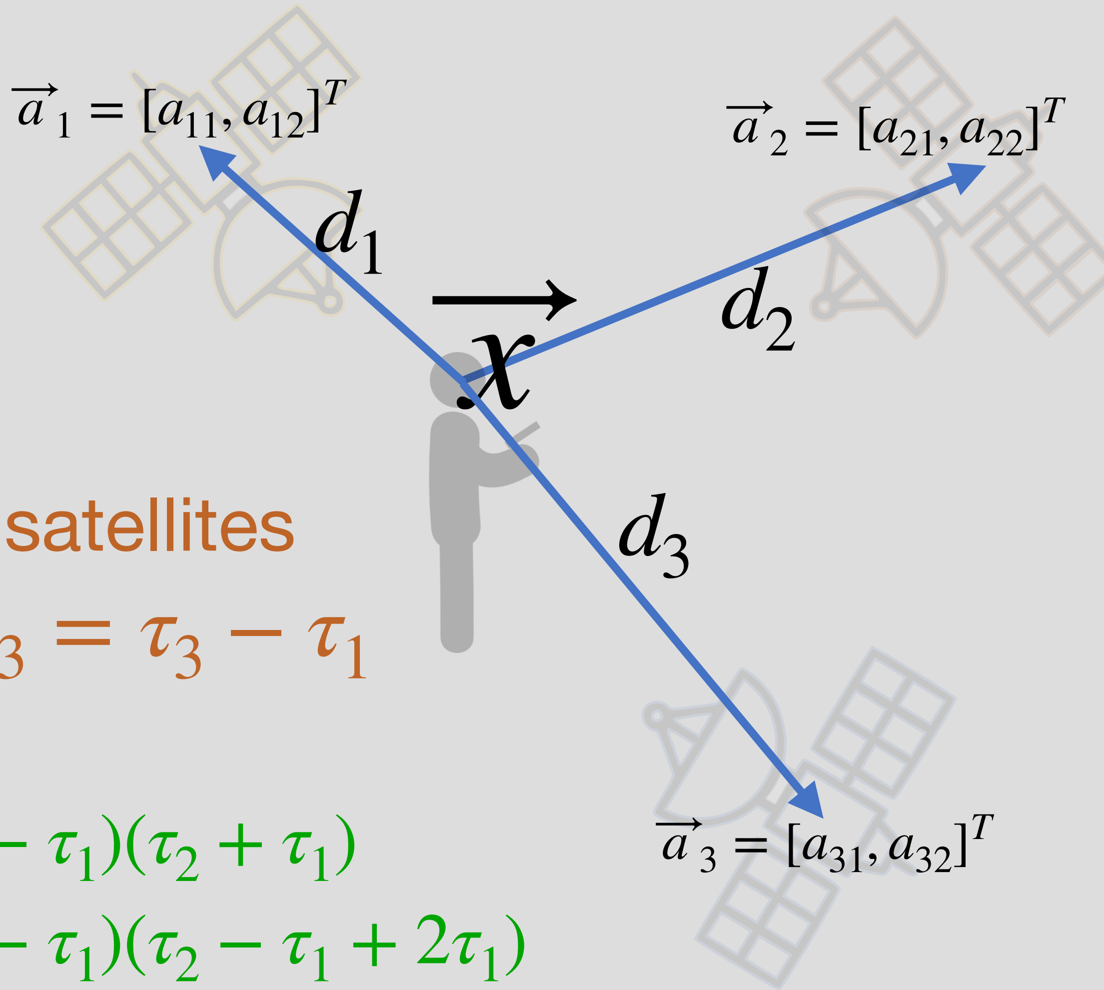

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$$2(\vec{a}_1 - \vec{a}_2)^T \vec{x} = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\Delta\tau_2)(\Delta\tau_2 + 2\tau_1)$$

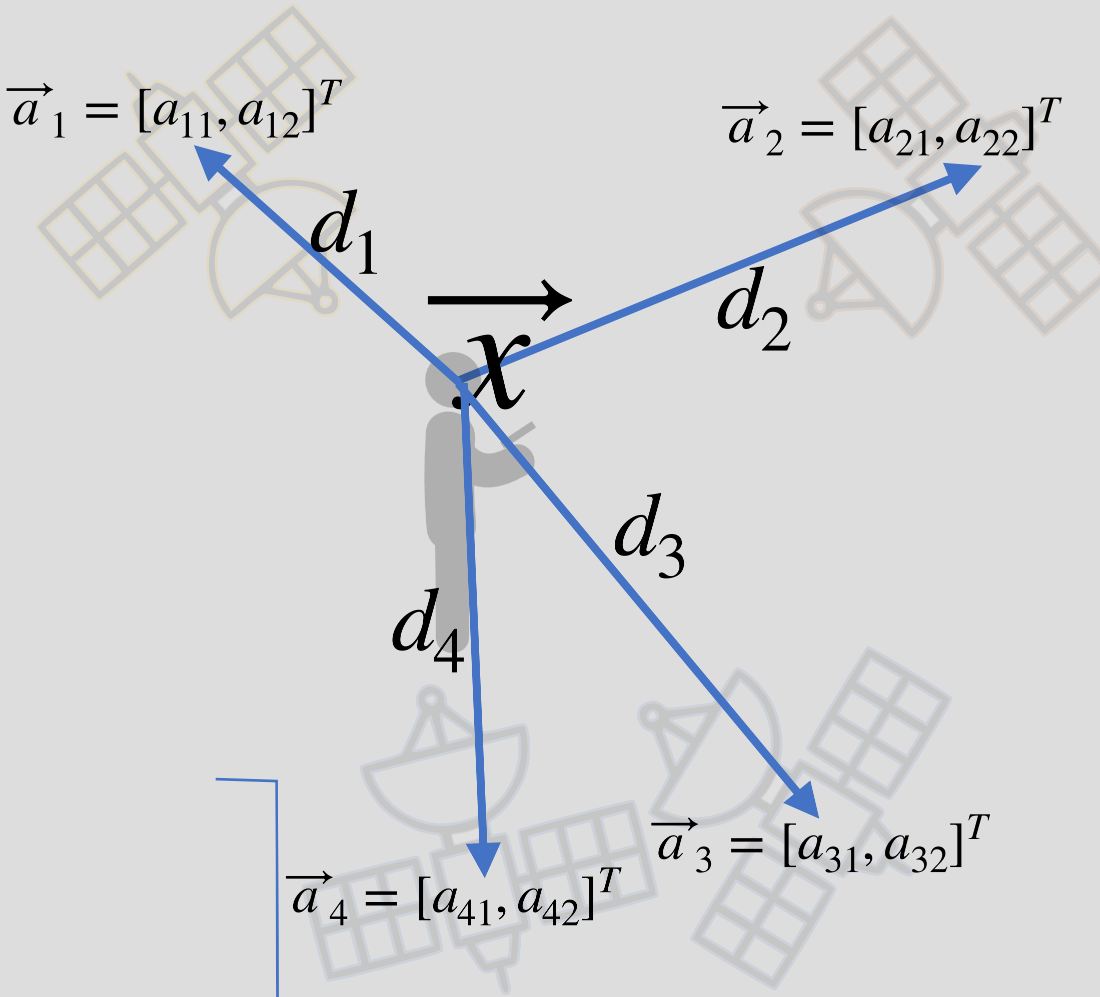
$$2(\vec{a}_1 - \vec{a}_2)^T \vec{x} - 2C^2\Delta\tau_2\tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\Delta\tau_2)^2$$

Another variable! Need 1 more equation (satellite)

Trilateration

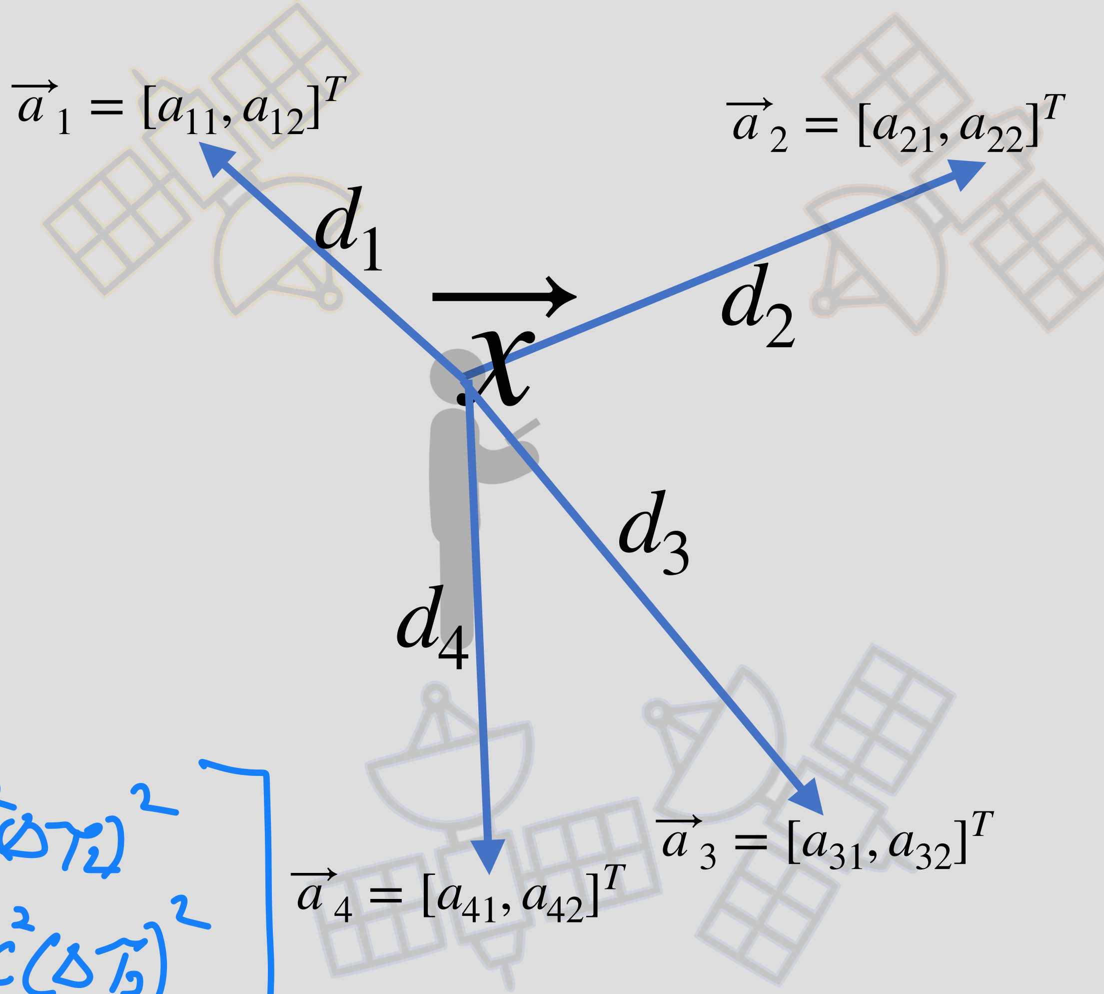
$$2(\vec{a}_1 - \vec{a}_2)^T\vec{x} - 2C^2\Delta\tau_2\tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\Delta\tau_2)^2$$
$$2(\vec{a}_1 - \vec{a}_3)^T\vec{x} - 2C^2\Delta\tau_3\tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_3\|^2 + C^2(\Delta\tau_3)^2$$
$$2(\vec{a}_1 - \vec{a}_4)^T\vec{x} - 2C^2\Delta\tau_4\tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_4\|^2 + C^2(\Delta\tau_4)^2$$

$$\begin{bmatrix} \\ \\ \\ \end{bmatrix}\begin{bmatrix} \\ \\ \\ \end{bmatrix} = \begin{bmatrix} \\ \\ \\ \end{bmatrix}$$



Trilateration

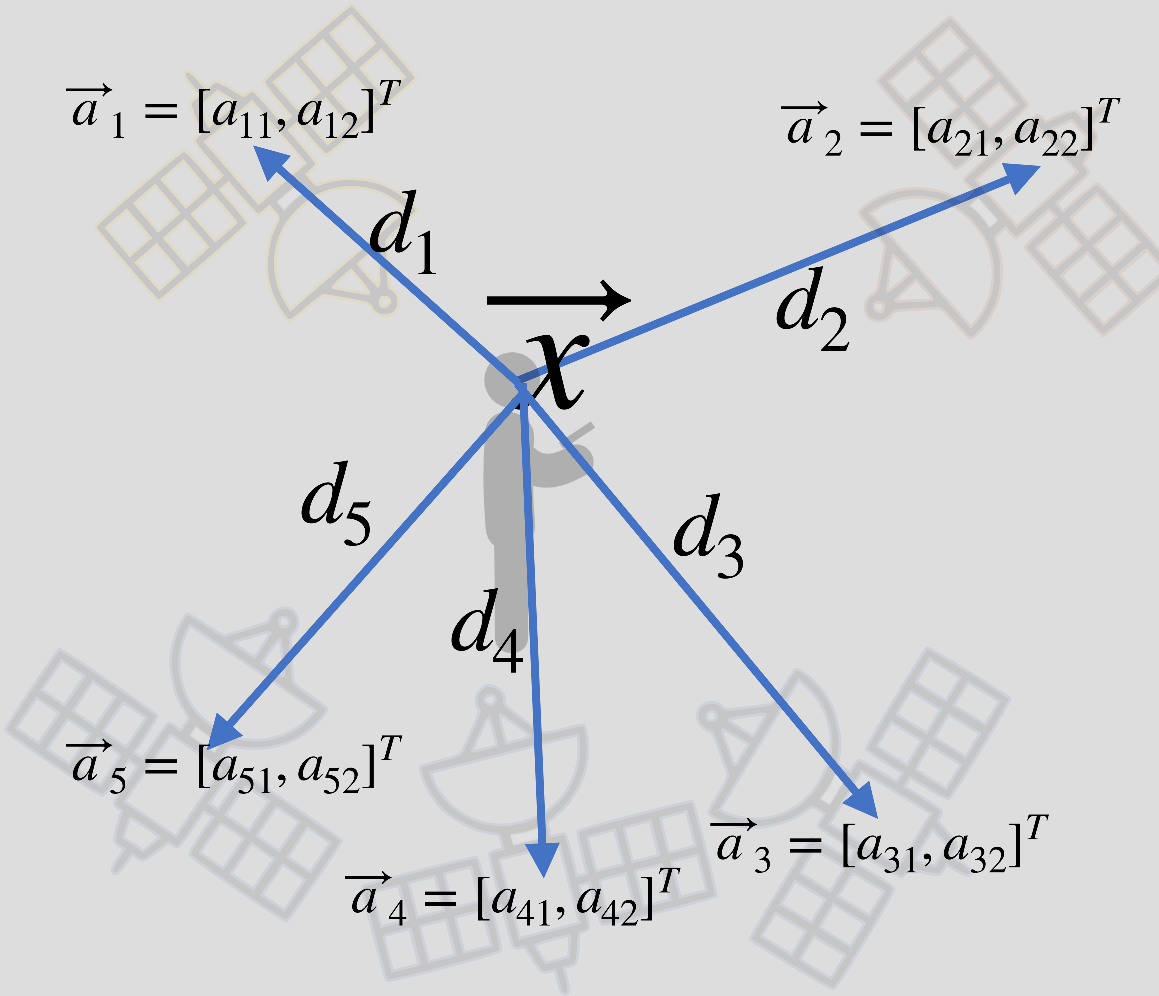
$$2(\vec{a}_1 - \vec{a}_2)^T \vec{x} - 2C^2 \Delta\tau_2 \tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\Delta\tau_2)^2$$
$$2(\vec{a}_1 - \vec{a}_3)^T \vec{x} - 2C^2 \Delta\tau_3 \tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_3\|^2 + C^2(\Delta\tau_3)^2$$
$$2(\vec{a}_1 - \vec{a}_4)^T \vec{x} - 2C^2 \Delta\tau_4 \tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_4\|^2 + C^2(\Delta\tau_4)^2$$



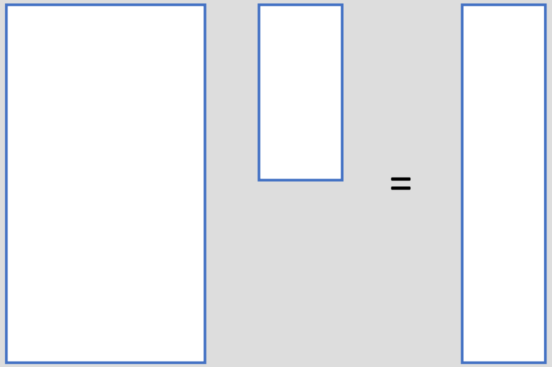
$$2\begin{bmatrix} a_{11}-a_{21} & a_{12}-a_{22} & -C^2\Delta\tau_2 \\ a_{11}-a_{31} & a_{12}-a_{32} & -C^2\Delta\tau_3 \\ a_{11}-a_{41} & a_{12}-a_{42} & -C^2\Delta\tau_4 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ \tau_1 \end{bmatrix} = \begin{bmatrix} \|a_1\|^2 - \|a_2\|^2 + C^2(\Delta\tau_2)^2 \\ \|a_1\|^2 - \|a_3\|^2 + C^2(\Delta\tau_3)^2 \\ \|a_1\|^2 - \|a_4\|^2 + C^2(\Delta\tau_4)^2 \end{bmatrix}$$

Multi-Lateration

$$2(\vec{a}_1 - \vec{a}_2)^T\vec{x} - 2C^2\Delta\tau_2\tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_2\|^2 + C^2(\Delta\tau_2)^2$$
$$2(\vec{a}_1 - \vec{a}_3)^T\vec{x} - 2C^2\Delta\tau_3\tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_3\|^2 + C^2(\Delta\tau_3)^2$$
$$2(\vec{a}_1 - \vec{a}_4)^T\vec{x} - 2C^2\Delta\tau_4\tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_4\|^2 + C^2(\Delta\tau_4)^2$$
$$2(\vec{a}_1 - \vec{a}_5)^T\vec{x} - 2C^2\Delta\tau_5\tau_1 = \|\vec{a}_1\|^2 - \|\vec{a}_5\|^2 + C^2(\Delta\tau_5)^2$$



More equations than unknowns



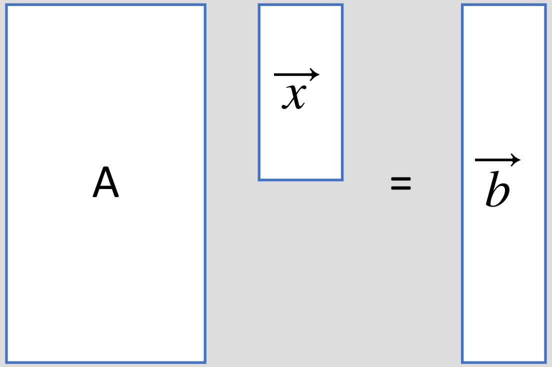
Over-determined — may not have a solution!

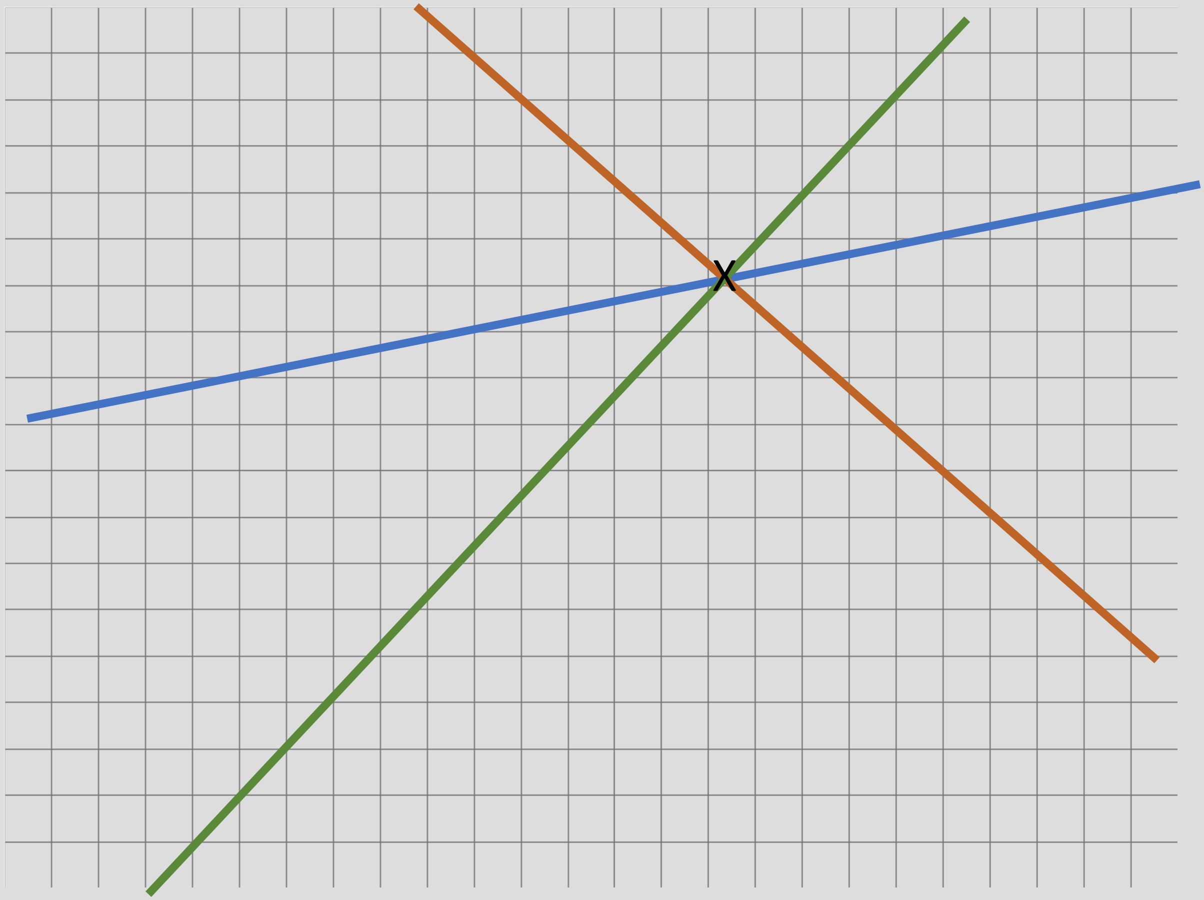
Overdetermined Linear Equations

$$a_{11}x_1 + a_{12}x_2 = b_1$$

$$a_{21}x_1 + a_{22}x_2 = b_2$$

$$a_{31}x_1 + a_{32}x_2 = b_3$$





Q: When is there a solution?

A: When $\overrightarrow{b} \in \mathrm{Span}\{\mathrm{cols\ of\ } A\}$

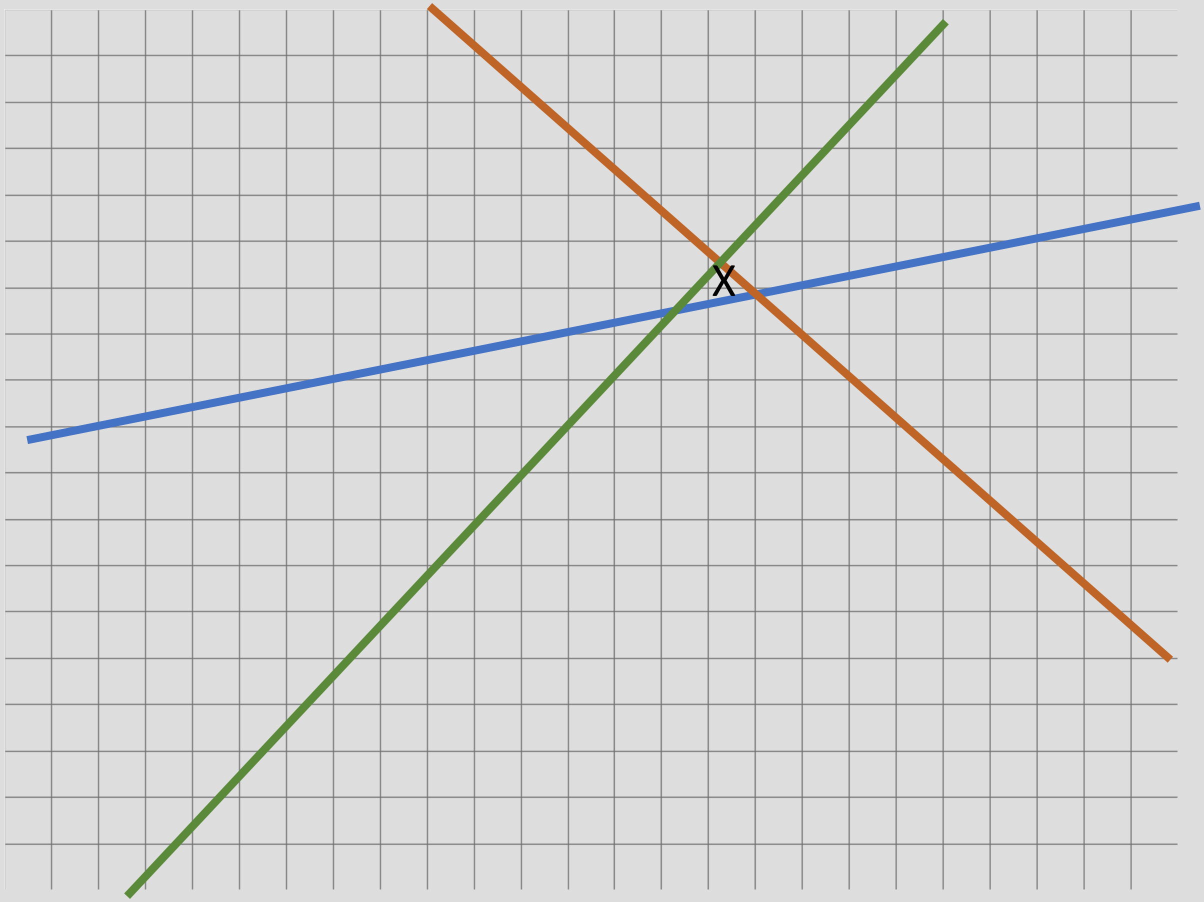
Inconsistent Linear Equations

$$a_{11}x_1 + a_{12}x_2 = b_1 + e_1$$

$$a_{21}x_1 + a_{22}x_2 = b_2 + e_2$$

$$a_{31}x_1 + a_{32}x_2 = b_3 + e_3$$

$$\boxed{A}\ \boxed{\vec{x}} = \boxed{\vec{b}} + \boxed{\vec{e}}$$



Q: With noise, equations will be inconsistent! - no solution.

Towards the Least Squares Algorithm

Fact:

We have measurements: $\overrightarrow{b}$

We have a model that : $A\overrightarrow{x} = \overrightarrow{b}$

Problem:

But $A\overrightarrow{x} = \overrightarrow{b}$ does not have a solution!

What to do?

Want to find $\hat{x}$, such that $A\hat{x}$ is the closest to $\overrightarrow{b}$

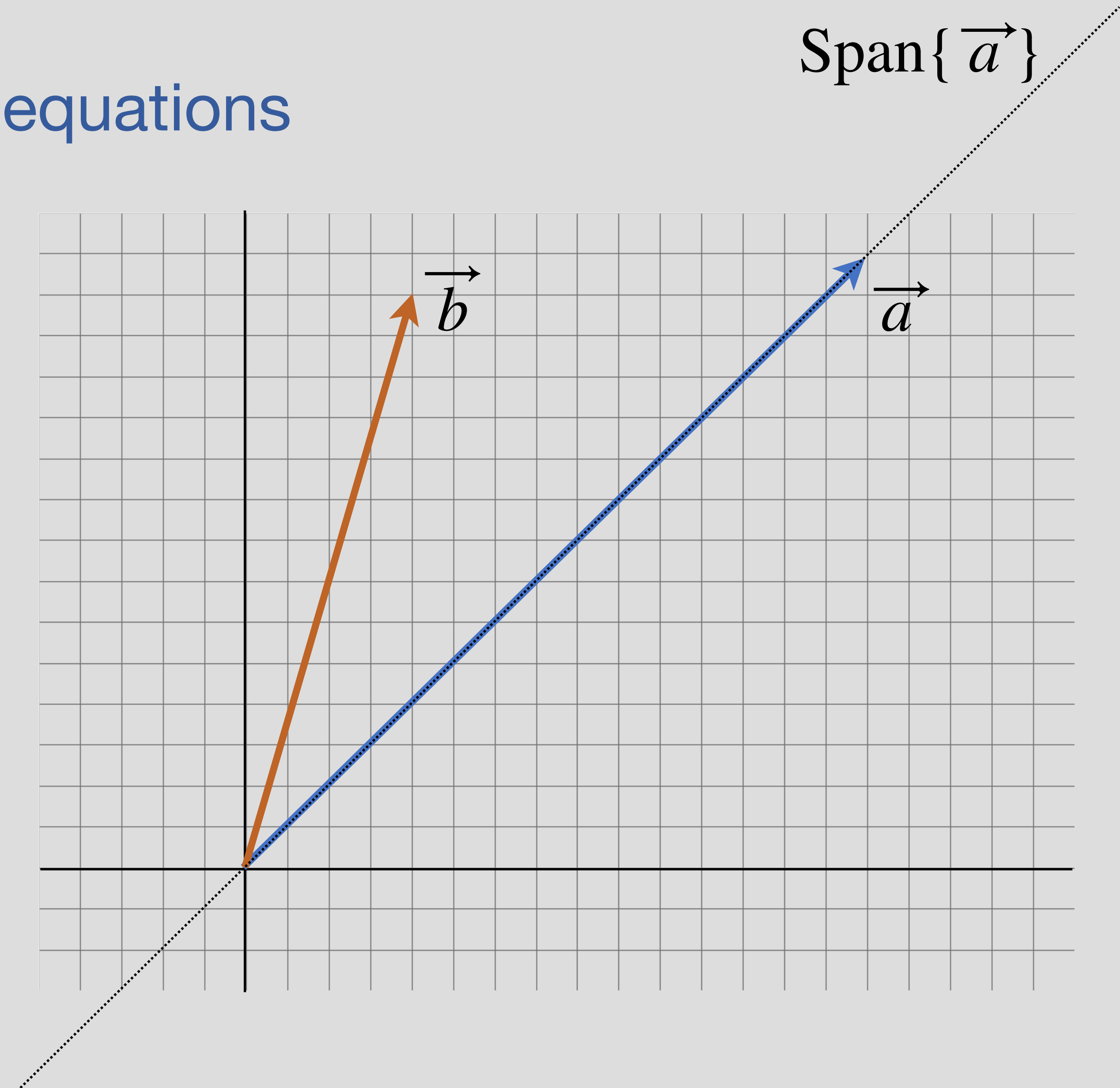
Example: a scalar problem

$$\begin{bmatrix} a_1 \\ a_2 \end{bmatrix} x = \begin{bmatrix} b_1 \\ b_2 \end{bmatrix}$$, one unknown, two equations

Solution:

find $\hat{x}$ that has the smallest error

$$\| \overrightarrow{e} \| = \| \overrightarrow{a} \hat{x} - \overrightarrow{b} \|$$



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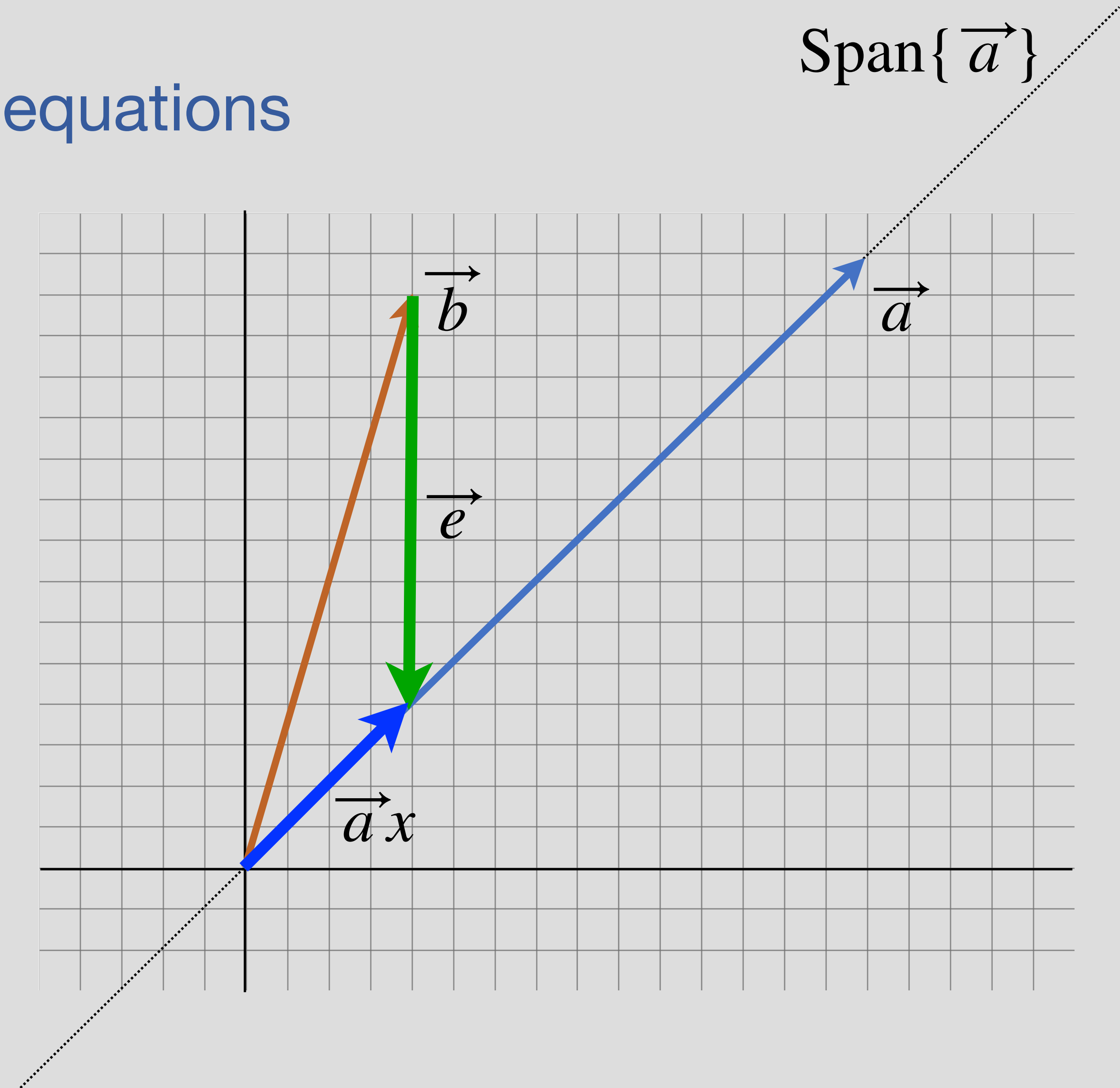
$$\begin{bmatrix} a_1 \\ a_2 \end{bmatrix} x = \begin{bmatrix} b_1 \\ b_2 \end{bmatrix}$$, one unknown, two equations

Solution:

find $\hat{x}$ that has the smallest error

$$\| \vec{e} \| = \| \vec{a}\hat{x} - \vec{b} \| \leq \| \vec{a}x - \vec{b} \|$$



Example: a scalar problem

$$\begin{bmatrix} a_1 \\ a_2 \end{bmatrix} x = \begin{bmatrix} b_1 \\ b_2 \end{bmatrix}$$, one unknown, two equations

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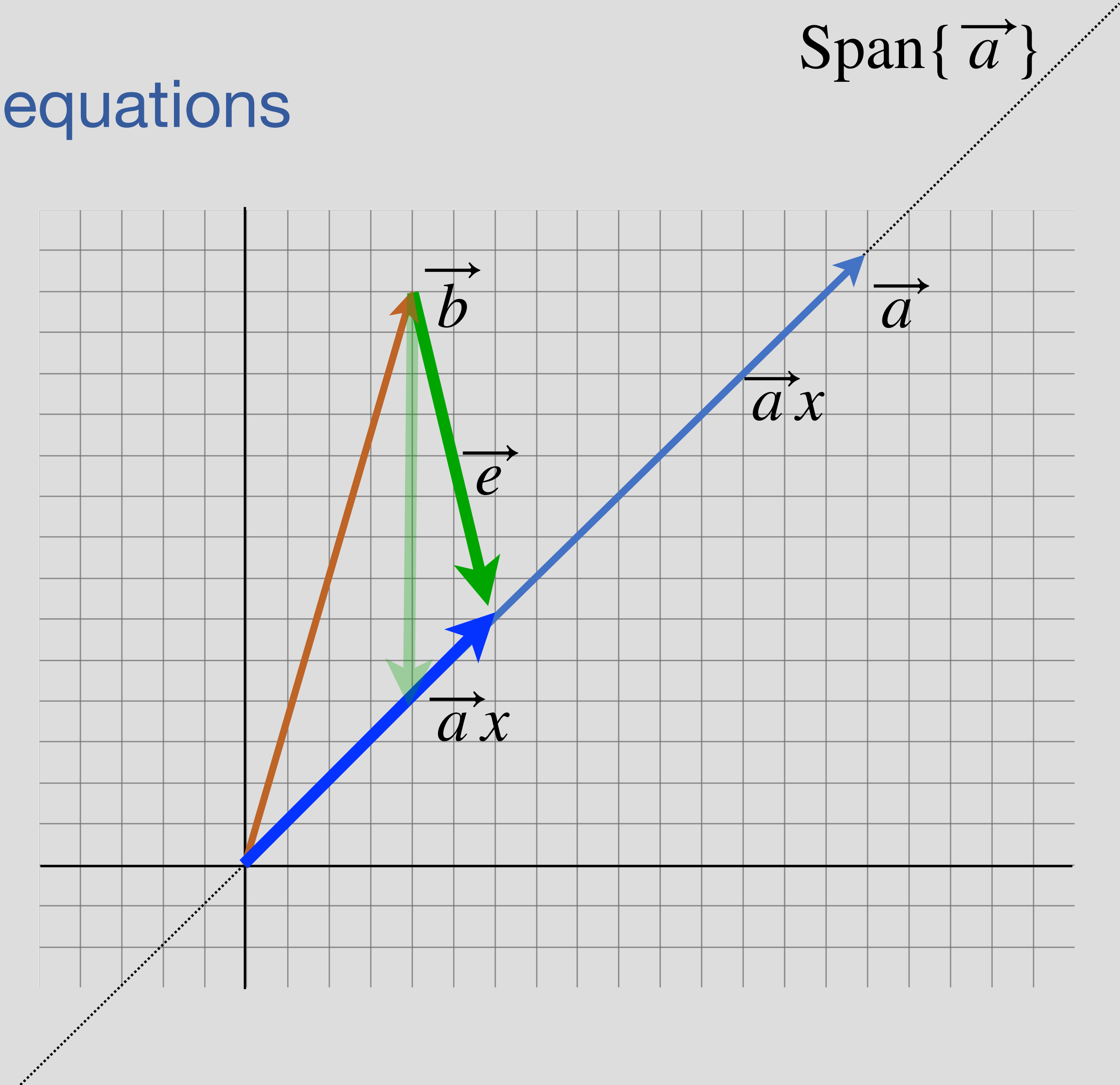
$$\|\vec{e}\| = \|\vec{a}\hat{x} - \vec{b}\| \leq \|\vec{a}x - \vec{b}\|$$



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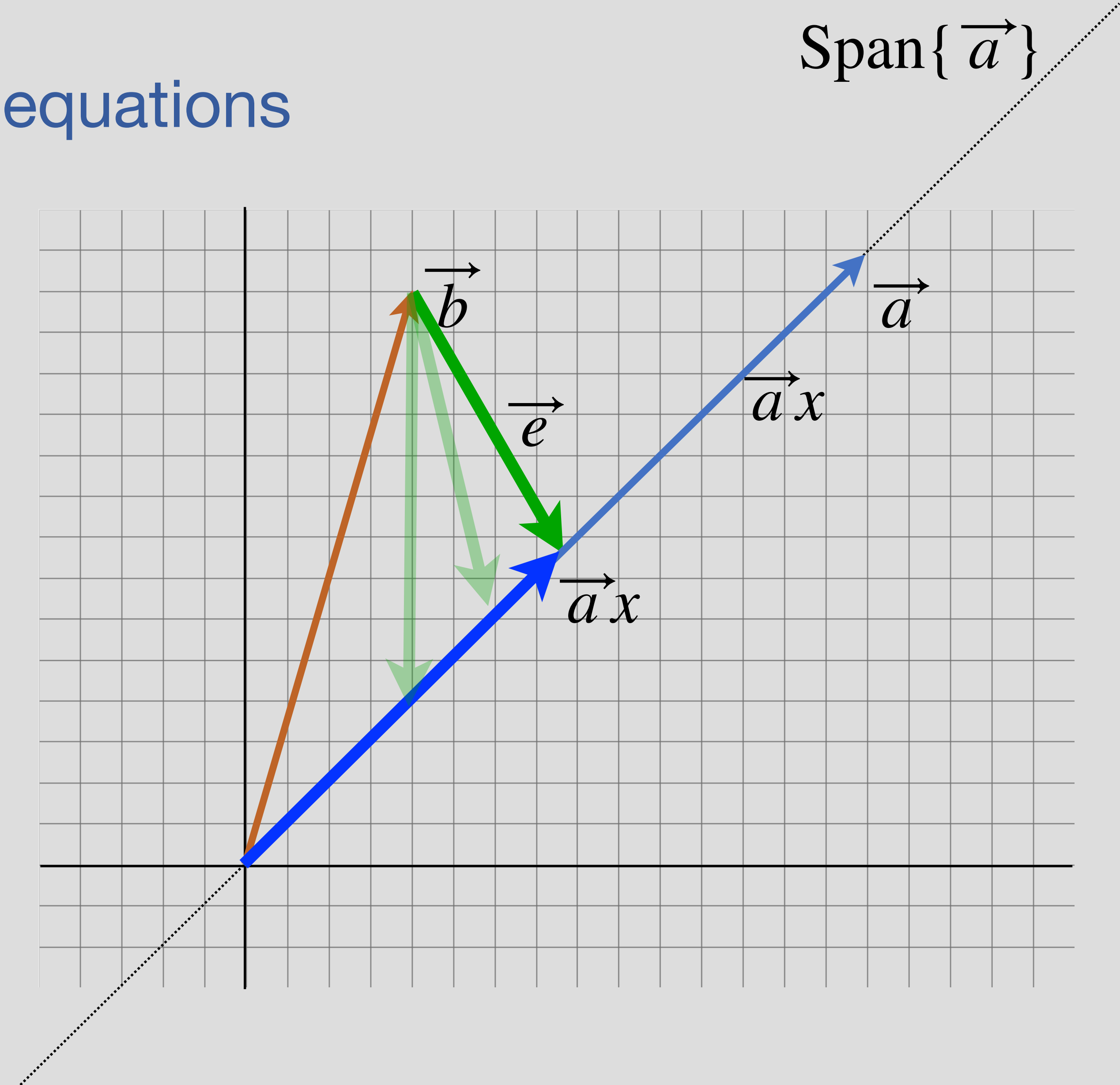

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$$\begin{bmatrix} a_1 \\ a_2 \end{bmatrix} x = \begin{bmatrix} b_1 \\ b_2 \end{bmatrix}$$, one unknown, two equations

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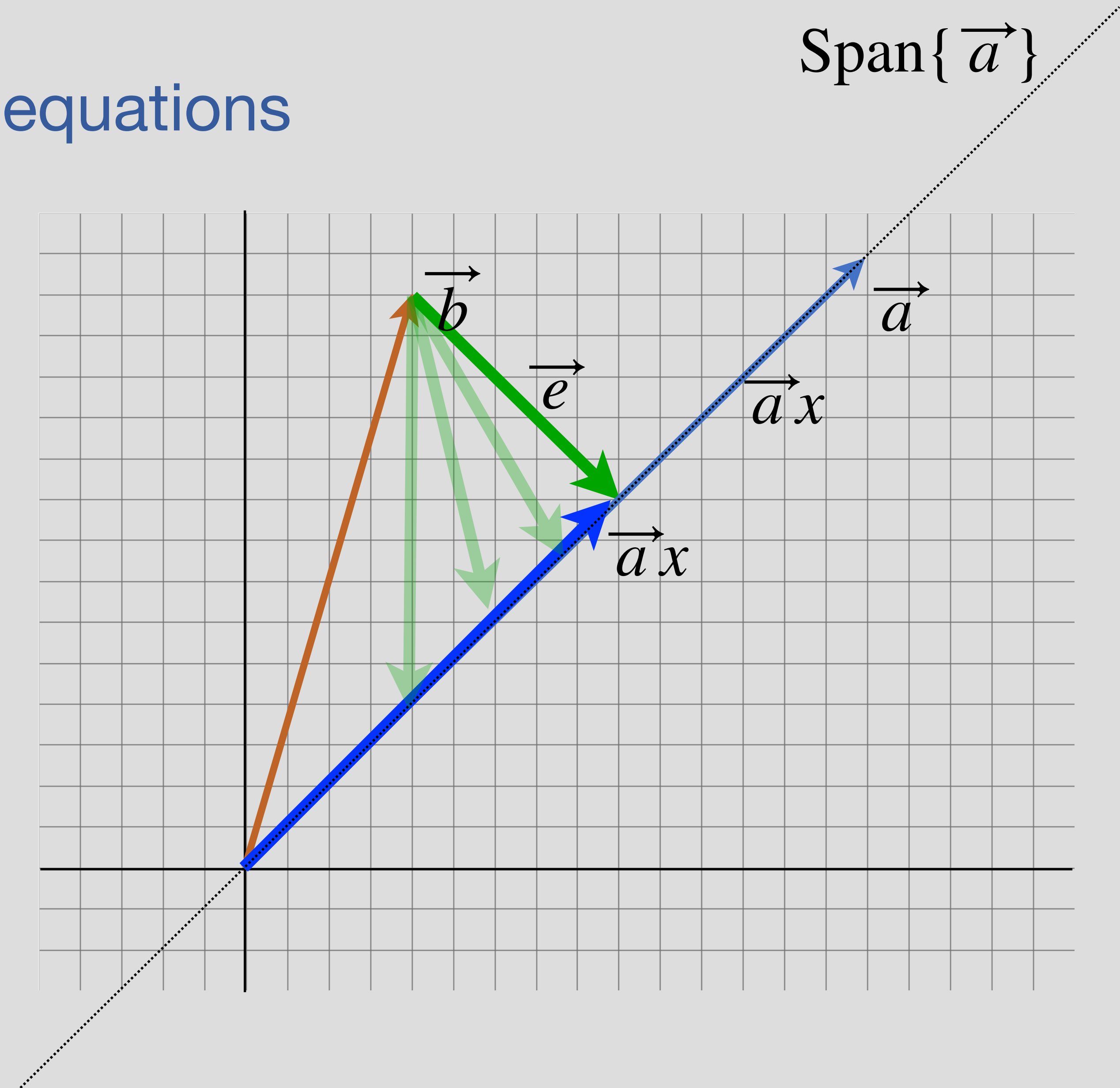
$$\| \vec{e} \| = \| \vec{a}\hat{x} - \vec{b} \| \leq \| \vec{a}x - \vec{b} \|$$



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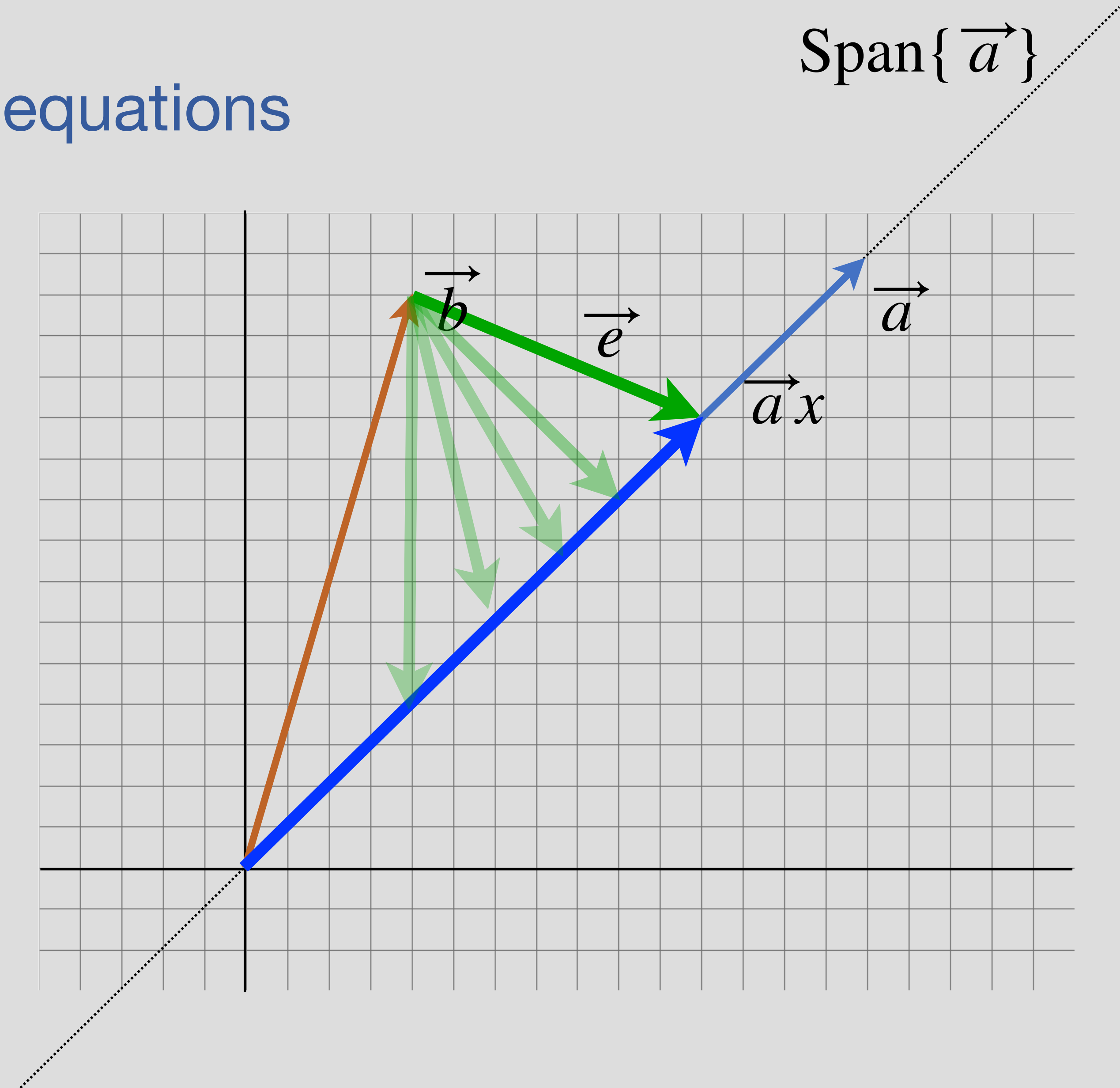
Solution:

find $\hat{x}$ that has the smallest error

$$\|\vec{e}\| = \|\vec{a}\hat{x} - \vec{b}\| \leq \|\vec{a}x - \vec{b}\|$$



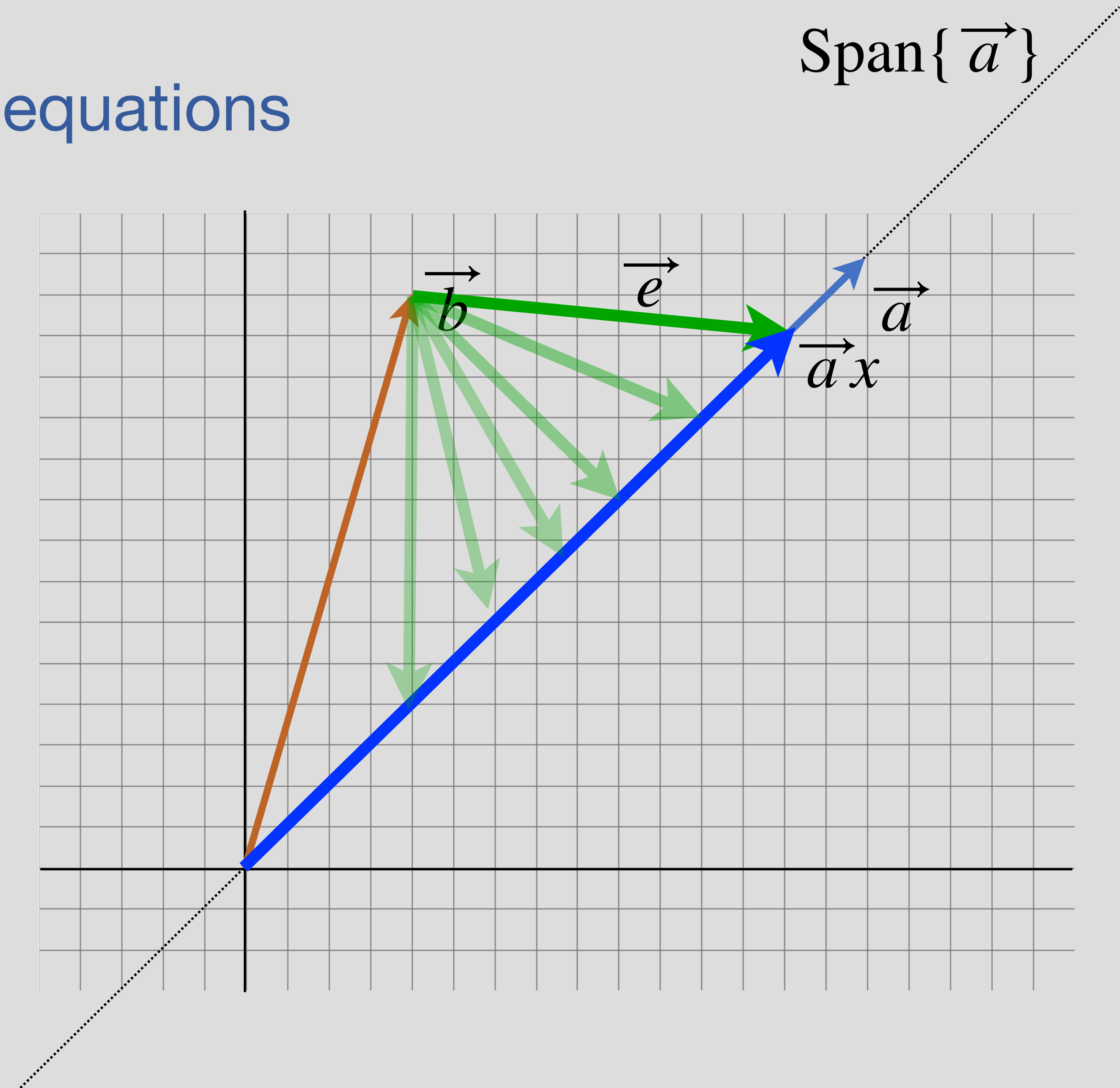
Example: a scalar problem

$$\begin{bmatrix} a_1 \\ a_2 \end{bmatrix} x = \begin{bmatrix} b_1 \\ b_2 \end{bmatrix}$$, one unknown, two equations

Solution:

find $\hat{x}$ that has the smallest error

$$\| \vec{e} \| = \| \vec{a}\hat{x} - \vec{b} \| \leq \| \vec{a}x - \vec{b} \|$$



Example: a scalar problem

$$\begin{bmatrix} a_1 \\ a_2 \end{bmatrix} x = \begin{bmatrix} b_1 \\ b_2 \end{bmatrix}$$, one unknown, two equations

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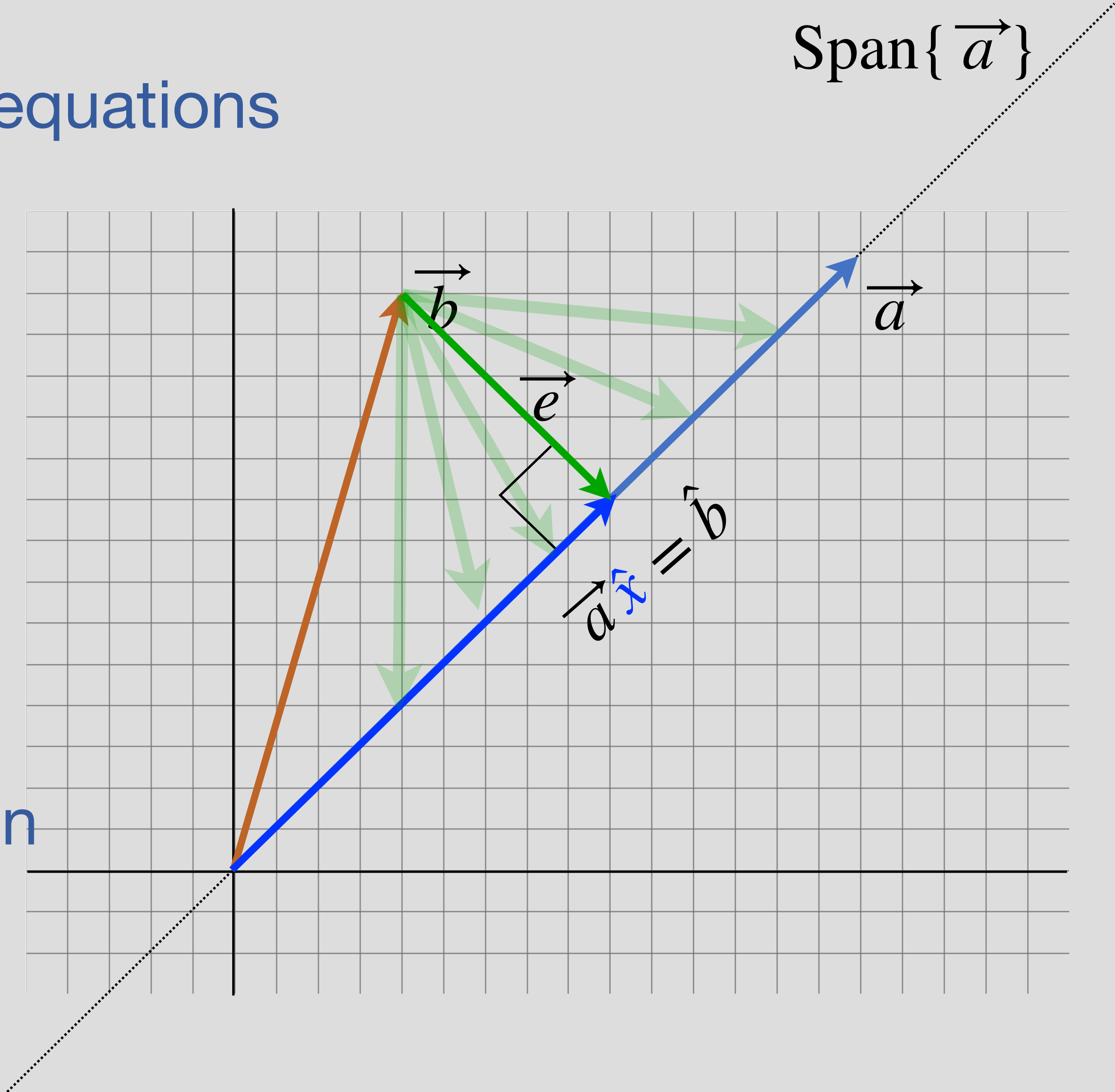
find $\hat{x}$ that has the smallest error

$$\| \vec{e} \| = \| \vec{a}\hat{x} - \vec{b} \| \leq \| \vec{a}x - \vec{b} \|$$

Theorem:

shortest distance between a point and a line is the orthogonal projection



Projections

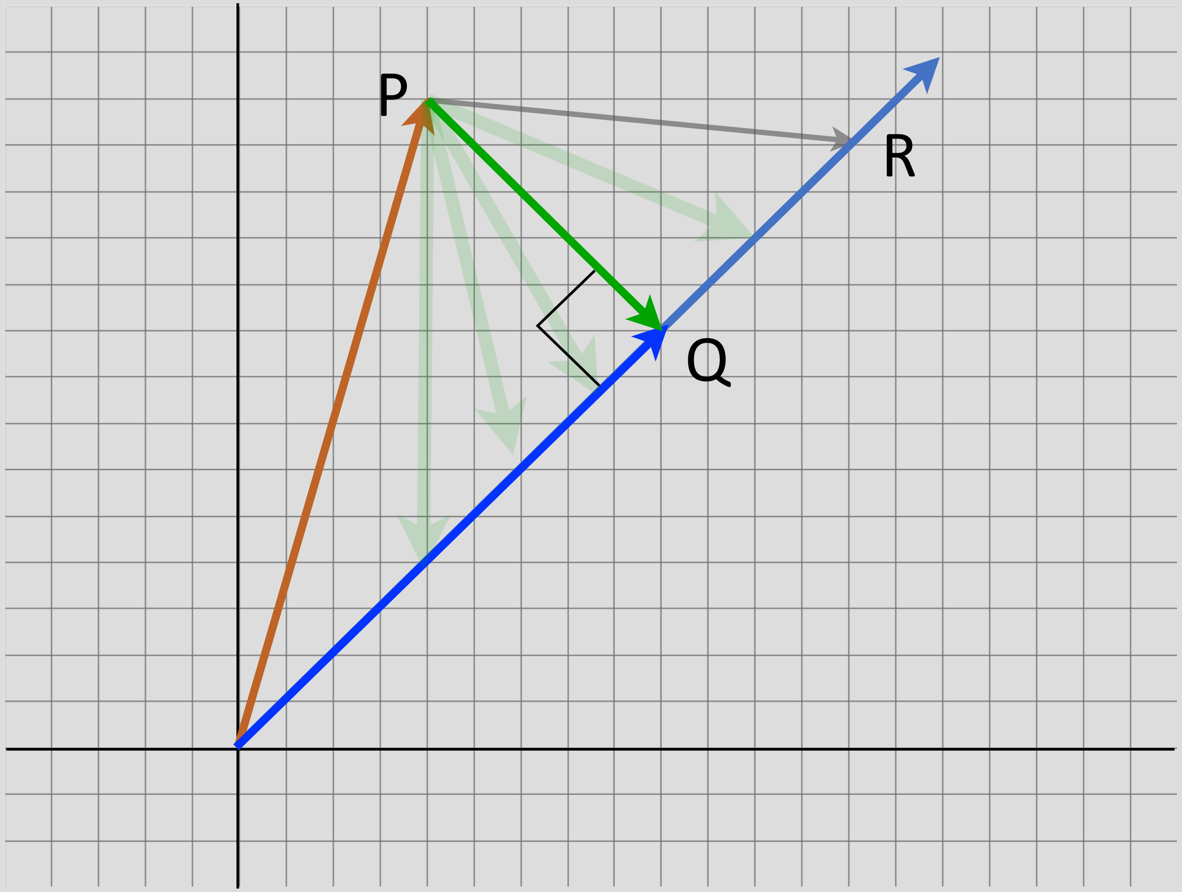
Theorem:
shortest distance between a point and line is the orthogonal projection

Proof:

Pythagoras: $(PR)^2 = (PQ)^2 + \underbrace{(QR)^2}_{>0}$

$$(PR)^2 > (PQ)^2$$

$$(PR) > (PQ)$$



Projections

find $\hat{x}$ that has the smallest error

$$\|\vec{e}\| = \|\vec{a}\hat{x} - \vec{b}\| \le \|\vec{a}x - \vec{b}\|$$

Need to find the orthogonal projection!

We know: $\vec{e} \perp \hat{b}$, $\vec{e} \perp \vec{a}$

$$\left\langle \vec{e}, \vec{a} \right\rangle = 0$$

$$\left\langle \vec{b} - \hat{b}, \vec{a} \right\rangle = 0$$

$$\left\langle \vec{b}, \vec{a} \right\rangle - \left\langle \hat{b}, \vec{a} \right\rangle = 0$$

$$\left\langle \vec{b}, \vec{a} \right\rangle = \left\langle \hat{b}, \vec{a} \right\rangle$$

$$\left\langle \vec{b}, \vec{a} \right\rangle = \left\langle \vec{a}\hat{x}, \vec{a} \right\rangle$$

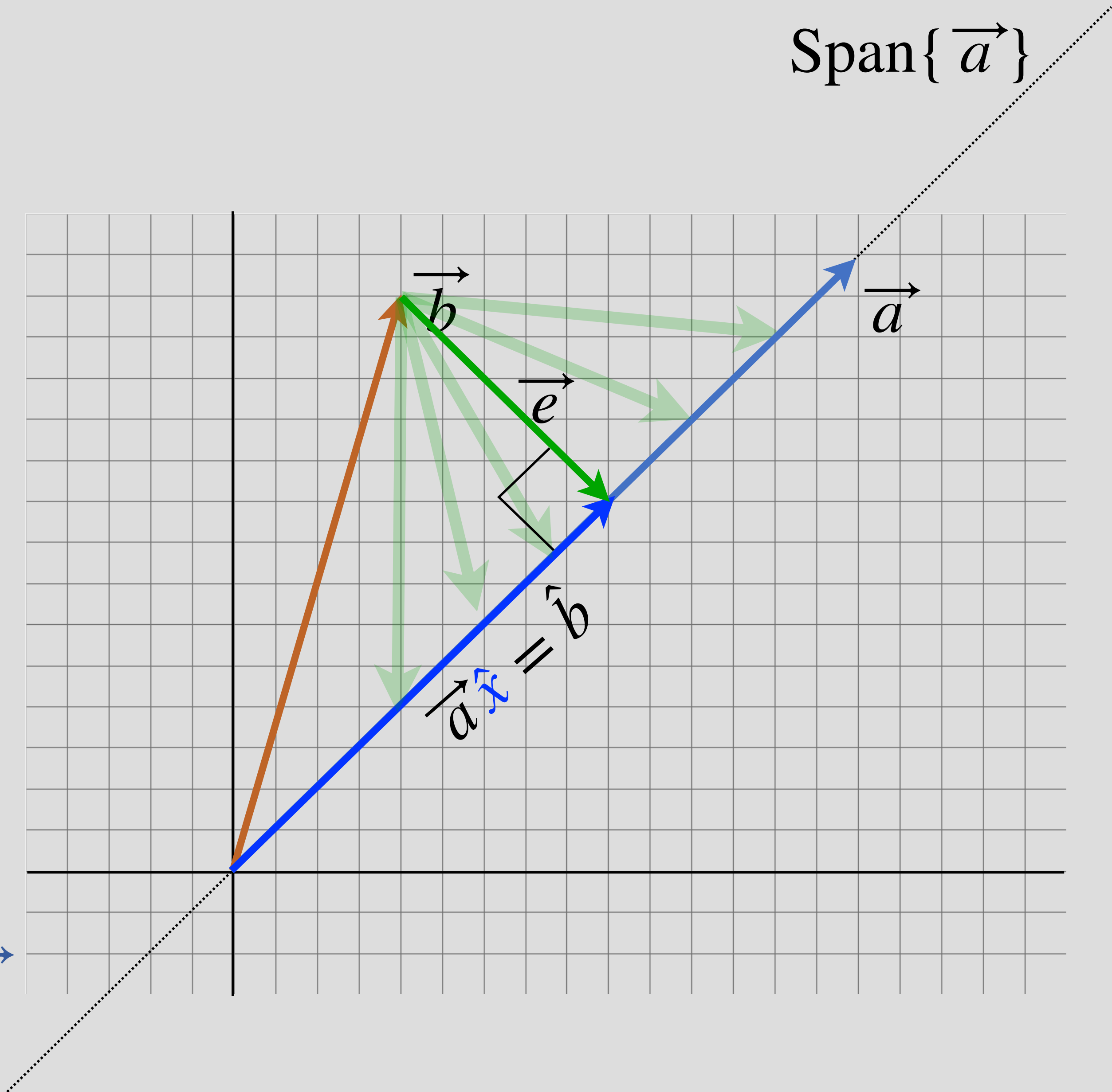
$$\left\langle \vec{b}, \vec{a} \right\rangle = \hat{x} \left\langle \vec{a}, \vec{a} \right\rangle$$

$$\left\langle \vec{b}, \vec{a} \right\rangle = \hat{x} \|\vec{a}\|^2$$

$$\hat{x} = \frac{\left\langle \vec{b}, \vec{a} \right\rangle}{\|\vec{a}\|^2}$$

$$\hat{b} = \frac{\left\langle \vec{b}, \vec{a} \right\rangle}{\|\vec{a}\|^2} \vec{a}$$

$$\hat{b} = \frac{\vec{b}^T \vec{a}}{\vec{a}^T \vec{a}} \vec{a}$$



Orthogonal Projections

Given vectors $\overrightarrow{a}$, $\overrightarrow{b}$, we say that the orthogonal projection of $\overrightarrow{b}$ onto $\overrightarrow{a}$ is:

$$\text{Proj}_{\overrightarrow{b}}(\overrightarrow{a}) = \frac{\overrightarrow{b}^T \overrightarrow{a}}{\| \overrightarrow{a} \|^2} \overrightarrow{a}$$

Example 2D

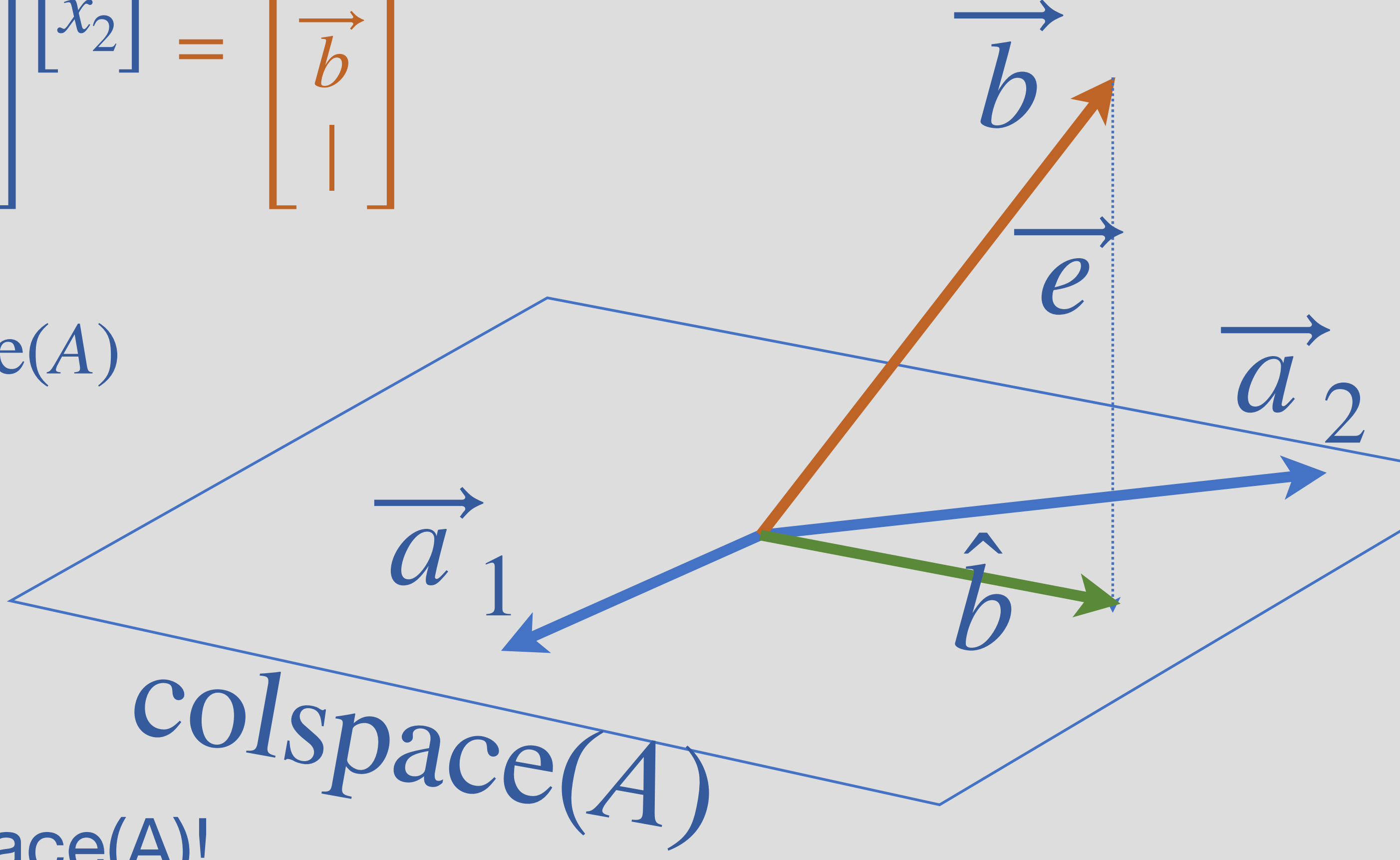
3 equations 2 unknowns:

$$\overset{A}{\begin{bmatrix} a_{11} & a_{12} \\ a_{21} & a_{22} \\ a_{31} & a_{32} \end{bmatrix}} \overset{\vec{x}}{\begin{bmatrix} x_1 \\ x_2 \end{bmatrix}} = \overset{\vec{b}}{\begin{bmatrix} b_1 \\ b_2 \\ b_3 \end{bmatrix}} \qquad \begin{bmatrix} | & | \\ \vec{a}_1 & \vec{a}_2 \\ | & | \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} | \\ \vec{b} \\ | \end{bmatrix}$$

No solution means: $\vec{b} \notin \text{colspace}(A)$

Find $\hat{x}$ that has the smallest error

$$\|\vec{e}\| = \|A\hat{x} - \vec{b}\| \leq \|Ax - \vec{b}\|$$



Orthogonal projection onto colspace(A)!

Theorem: Consider matrix A, and $\vec{y} \in \text{colspace}(A)$

If $\exists \vec{z}$, such that $\langle \vec{z}, \vec{a}_i \rangle = 0$, then $\langle \vec{z}, \vec{y} \rangle = 0$.

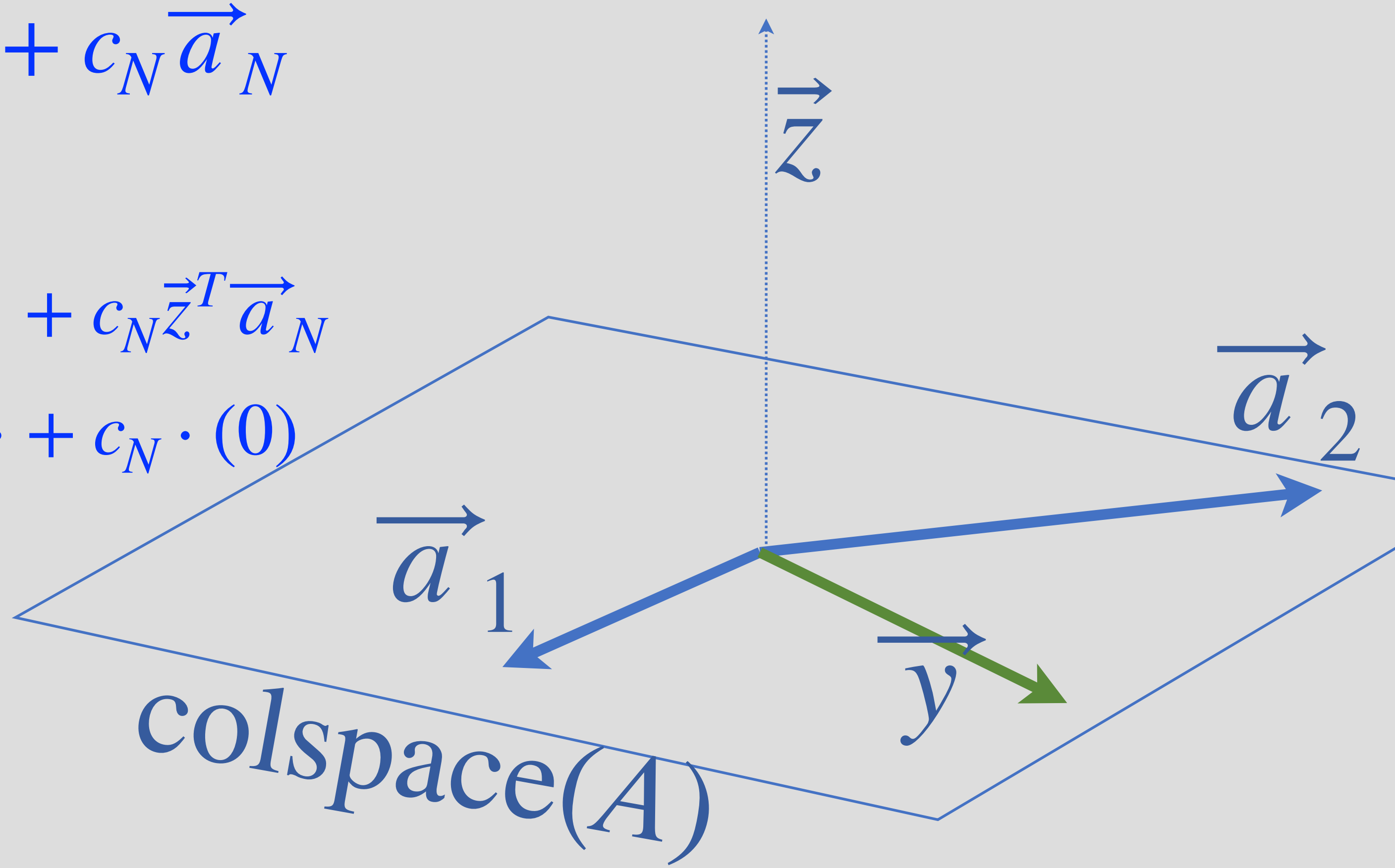
$$A = \begin{bmatrix} | & | & & | \\ \vec{a}_1 & \vec{a}_2 & \cdots & \vec{a}_N \\ | & | & & | \end{bmatrix}$$

Proof:

Know: $\vec{y} = c_1 \vec{a}_1 + c_2 \vec{a}_2 + \cdots + c_N \vec{a}_N$

Show: $\langle \vec{z}, \vec{y} \rangle = 0$

$$\begin{aligned} \langle \vec{z}, c_1 \vec{a}_1 + \cdots + c_N \vec{a}_N \rangle &= c_1 \vec{z}^T \vec{a}_1 + \cdots + c_N \vec{z}^T \vec{a}_N \\ &= c_1 \cdot (0) + \cdots + c_N \cdot (0) \\ &= 0 \end{aligned}$$



Least Squares

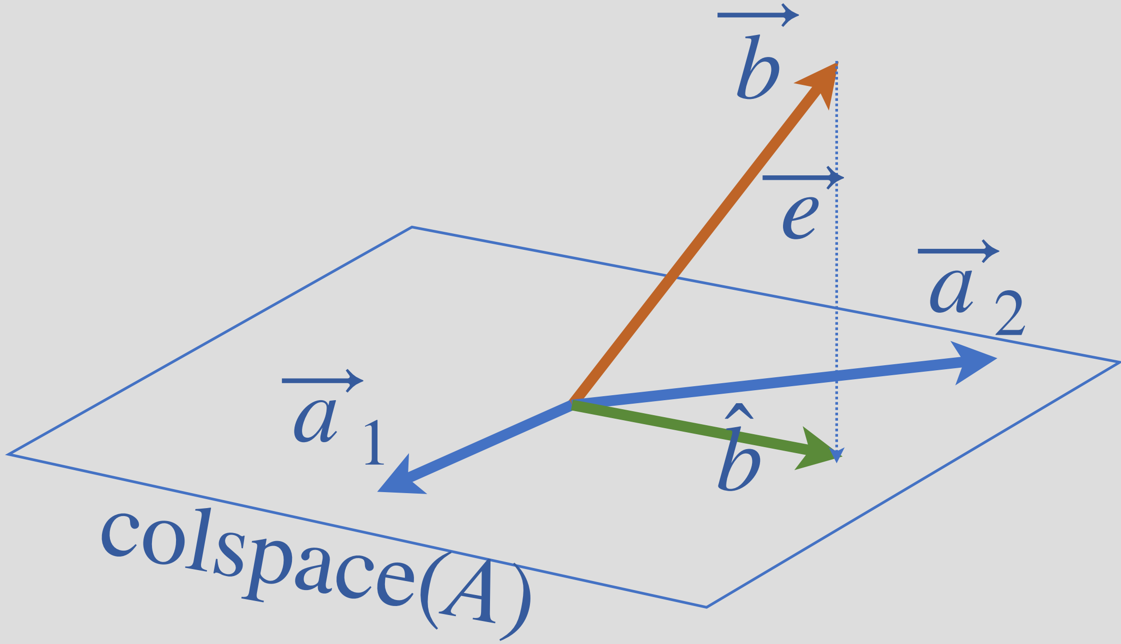
$$\operatorname{argmin}_{\vec{x}} \ \|\vec{e}\| = \|A\vec{x} - \vec{b}\|$$

$$\vec{e} = \vec{b} - \hat{b}$$

Since $\vec{e} \perp \mathrm{col}(A)$, $\langle \vec{a}_i, \vec{e} \rangle = 0$

$$\left\langle \vec{a}_i, \vec{b} - \hat{b} \right\rangle = 0$$

$$\vec{a}_i^T(\vec{b} - \hat{b}) = 0$$



$$A = \begin{bmatrix} | & | & & | \\ \vec{a}_1 & \vec{a}_2 & \cdots & \vec{a}_N \\ | & | & & | \end{bmatrix}$$

$A\vec{x} \in \mathrm{colspace}(A)$

Find $\hat{b} = A\hat{x}$

Least Squares

$$\text{argmin}_{\vec{x}} \ \|\vec{e}\| = \|A\vec{x} - \vec{b}\|$$

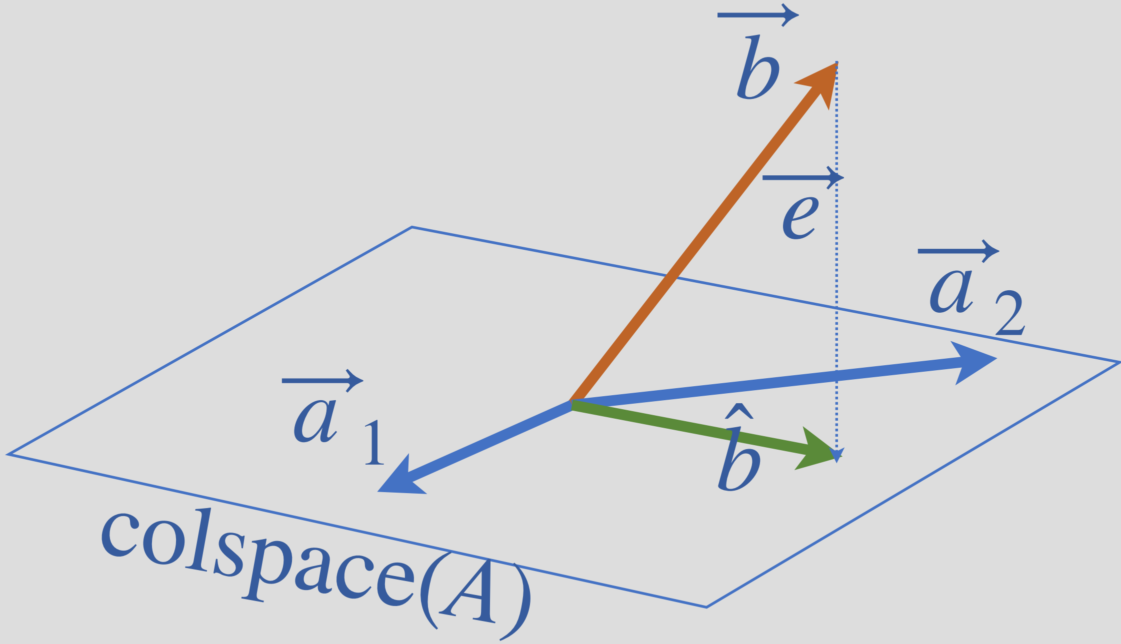
$$\vec{e} = \vec{b} - \hat{b}$$

Since $\vec{e} \perp \text{col}(A)$, $\langle \vec{a}_i, \vec{e} \rangle = 0$

$$\left\langle \vec{a}_i, \vec{b} - \hat{b} \right\rangle = 0$$

$$\vec{a}_i^T(\vec{b} - \hat{b}) = 0$$

$$\begin{bmatrix} - & \vec{a}_1^T & - \\ - & \vec{a}_2^T & - \\ & \vdots & \\ - & \vec{a}_N^T & - \end{bmatrix} \begin{bmatrix} | \\ \vec{b} - \hat{b} \\ | \end{bmatrix} = 0$$



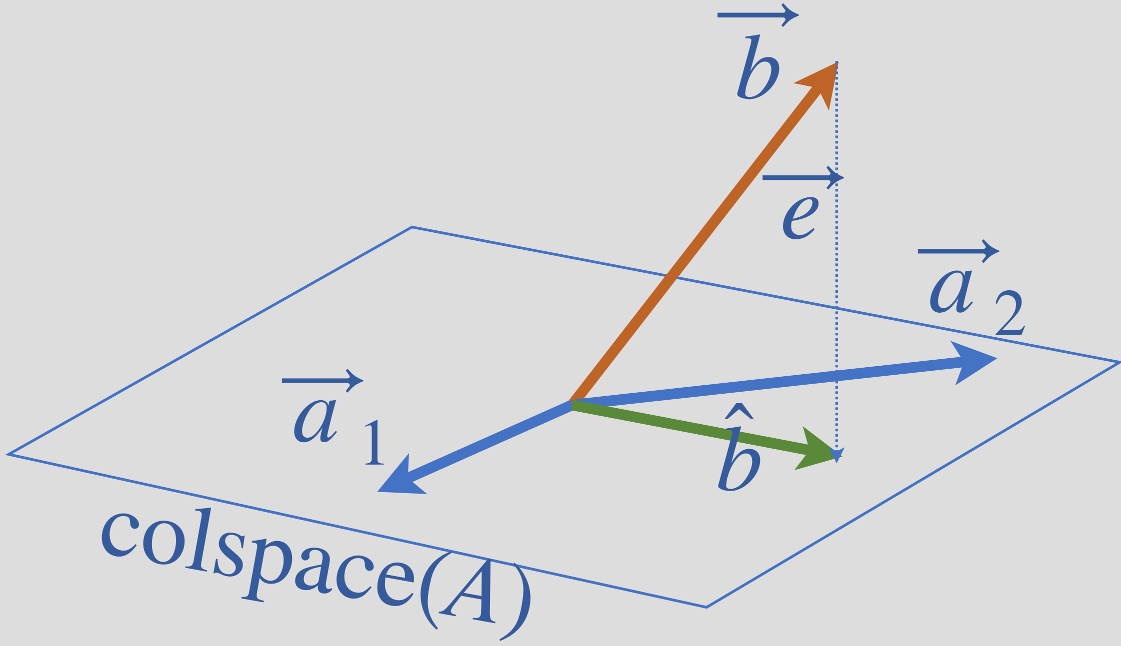
$$A = \begin{bmatrix} | & | & & | \\ \vec{a}_1 & \vec{a}_2 & \cdots & \vec{a}_N \\ | & | & & | \end{bmatrix}$$

$A\vec{x} \in \text{colspace}(A)$

Find $\hat{b} = A\hat{x}$

Least Squares

$$\begin{bmatrix} - & \vec{a}_1^T & - \\ - & \vec{a}_2^T & - \\ & \vdots & \\ - & \vec{a}_N^T & - \end{bmatrix} \begin{bmatrix} | \\ \vec{b} - \hat{b} \\ | \end{bmatrix} = 0$$



$$A^T\left(\vec{b} - A\hat{x}\right) = 0$$

$$A = \begin{bmatrix} | & | & & | \\ \vec{a}_1 & \vec{a}_2 & \cdots & \vec{a}_N \\ | & | & & | \end{bmatrix}$$

$$A^T\vec{b} - A^T A\hat{x} = 0$$

$$A^T A\hat{x} = A^T\vec{b}$$

If A is full Rank, then $A^T A$ is invertible

$$\boxed{\hat{x} = (A^T A)^{-1} A^T \vec{b}}$$

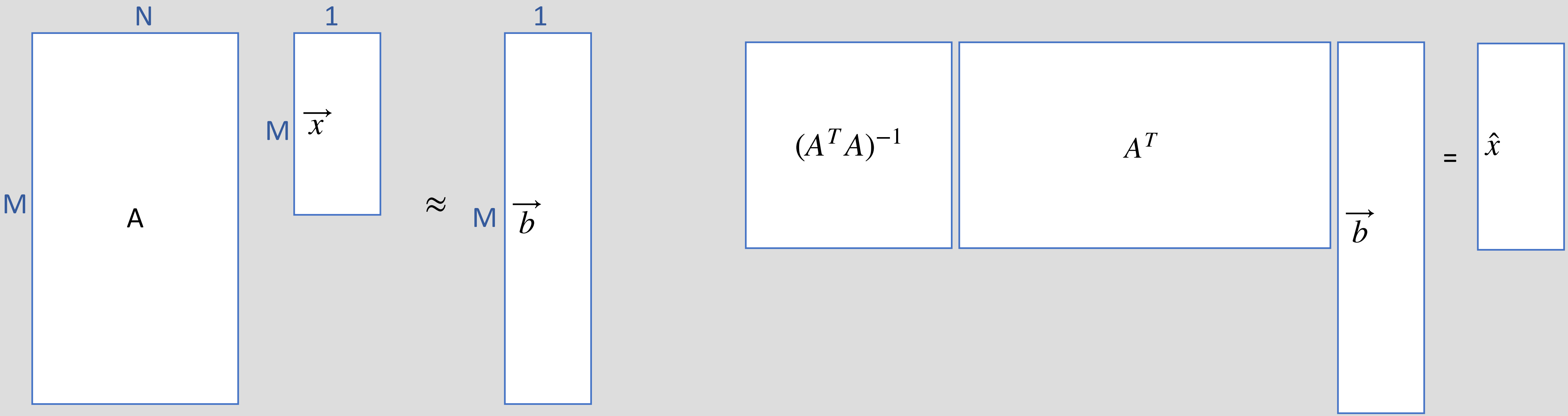
$$\hat{b} = A(A^T A)^{-1} A^T \vec{b}$$

$A\vec{x} \in \text{colspace}(A)$

Find $\hat{b} = A\hat{x}$

⌘3+⌘4

$$\hat{x} = (A^T A)^{-1} A^T \vec{b}$$



15
vineyard vines
$\vec{x}=(A^TA)^{-1}A^T\vec{y}$

Example 1

$$A\vec{x} = \vec{b}$$

$$\begin{bmatrix}2\\1\end{bmatrix}\begin{bmatrix}x\end{bmatrix} = \begin{bmatrix}1\\1\end{bmatrix}$$

$$\left.\begin{aligned} 2x &= 1 \\ 1x &= 1 \end{aligned}\right\} \quad \left[\begin{array}{c|c} 2 & 1 \\ 1 & 1 \end{array}\right] \Rightarrow \left[\begin{array}{c|c} 1 & \frac{1}{2} \\ 0 & \frac{1}{2} \end{array}\right]$$

No solⁿ