USEFUL CONCEPTS AND FACTS FROM LINEAR ALGEBRA

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Vectors

$$\mathbf{x} = \begin{bmatrix} x_1 \\ x_2 \\ \cdots \\ x_N \end{bmatrix}$$

Vector transpose and Hermitian transpose:

$$\mathbf{x}^T = [x_1, x_2, \ldots, x_N]$$

$$\mathbf{x}^H = \left(\mathbf{x}^T\right)^* = [x_1^*, x_2^*, \ldots, x_N^*]$$

Vector Euclidean norm:

$$||\mathbf{x}|| = \left\{ \sum_{i=1}^{N} |x_i|^2 \right\}^{1/2} = \sqrt{\mathbf{x}^H \mathbf{x}}$$

The scalar (inner) product of two complex vectors:

$$\mathbf{a}^H \mathbf{b} = \sum_{i=1}^{N} a_i^* b_i$$

Cauchy-Schwarz inequality

$$|\mathbf{a}^H \mathbf{b}| \leq ||\mathbf{a}|| \cdot ||\mathbf{b}||$$

Orthogonal vectors:

$$\mathbf{a}^H \mathbf{b} = \mathbf{b}^H \mathbf{a} = 0$$

Example: consider the output of an LTI system (filter)

$$y(n) = \sum_{k=0}^{N-1} h(k)x(n-k) = \mathbf{h}^T \mathbf{x}(n)$$

where

$$\mathbf{h} = \begin{bmatrix} h(0) \\ h(1) \\ \dots \\ h(N-1) \end{bmatrix}, \quad \mathbf{x}(n) = \begin{bmatrix} x(n) \\ x(n-1) \\ \dots \\ x(n-N+1) \end{bmatrix}$$

The set of vectors $\mathbf{x}_1, \mathbf{x}_2, \ldots, \mathbf{x}_n$ is said to be *linearly independent* if

$$\alpha_1\mathbf{x}_1 + \alpha_2\mathbf{x}_2 + \cdots + \alpha_n\mathbf{x}_n = 0 \qquad (*)$$

implies that $\alpha_i = 0$ for all i. If any set of nonzero α_i can be found so that $(*)$ holds, then the vectors are *linearly dependent*. For example, for nonzero α_1,

$$\mathbf{x}_1 = \beta_2\mathbf{x}_2 + \cdots + \beta_n\mathbf{x}_n$$

Example of linearly independent vector set:

$$\mathbf{x}_1 = \begin{bmatrix} 1 \\ 2 \\ 1 \end{bmatrix}, \quad \mathbf{x}_2 = \begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix}$$

Adding to this linearly independent vector set a new vector $\mathbf{x}_3$, we obtain that the new set

$$\mathbf{x}_1 = \begin{bmatrix} 1 \\ 2 \\ 1 \end{bmatrix}, \quad \mathbf{x}_2 = \begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix}, \quad \mathbf{x}_3 = \begin{bmatrix} 0 \\ 1 \\ 0 \end{bmatrix}$$

becomes linearly dependent because

$$\mathbf{x}_1 = \mathbf{x}_2 + 2\mathbf{x}_3$$

Given N vectors $\mathbf{x}_1, \mathbf{x}_2, \ldots, \mathbf{x}_N$, consider the set of all vectors that may be formed as a linear combination of the vectors $\mathbf{x}_i$,

$$\mathbf{x} = \sum_{i=1}^{N} \alpha_i \mathbf{x}_i$$

This set forms a *vector space* and the vectors $\mathbf{x}_i$ are said to span this space. If the vectors $\mathbf{x}_i$ are linearly independent, they are said to form a *basis* for this space and the number of basis vectors N is referred to as the space *dimension*. The basis for a vector space is not unique!

Matrices

$n \times m$ matrix:

$$\mathbf{A} = \{a_{ik}\} = \begin{bmatrix} a_{11} & a_{12} & a_{13} & \cdots & a_{1m} \\ a_{21} & a_{22} & a_{23} & \cdots & a_{2m} \\ a_{31} & a_{32} & a_{33} & \cdots & a_{3m} \\ \vdots & \vdots & \vdots & \vdots & \vdots \\ a_{n1} & a_{n2} & a_{n3} & \cdots & a_{nm} \end{bmatrix}$$

Symmetric square matrix:

$$\mathbf{A}^T = \mathbf{A}$$

Hermitian square matrix:

$$\mathbf{A}^H = \mathbf{A}$$

Some properties (apply to transpose $(\cdot)^T$ as well):

$$(\mathbf{A}+\mathbf{B})^H = \mathbf{A}^H + \mathbf{B}^H\,, \quad (\mathbf{A}^H)^H = \mathbf{A}\,, \quad (\mathbf{A}\mathbf{B})^H = \mathbf{B}^H\mathbf{A}^H$$

Column and row representations of an $n \times m$ matrix:

$$\mathbf{A} = [\mathbf{c}_1, \mathbf{c}_2, \ldots, \mathbf{c}_m] = \begin{bmatrix} \mathbf{r}_1^H \\ \mathbf{r}_2^H \\ \vdots \\ \mathbf{r}_n^H \end{bmatrix} \qquad (*)$$

The *rank* of $\mathbf{A}$ is defined as a number of linearly independent columns in $(*)$, or, equivalently, the number of linearly independent row vectors in $(*)$.

Important property:

$$\mathrm{rank}\{\mathbf{A}\} = \mathrm{rank}\{\mathbf{A}\mathbf{A}^H\} = \mathrm{rank}\{\mathbf{A}^H\mathbf{A}\}$$

For any $n \times m$ matrix:

$$\mathrm{rank}\{\mathbf{A}\} \leq \min\{m, n\}$$

The matrix $\mathbf{A}$ is said to be of *full rank* if

$$\mathrm{rank}\{\mathbf{A}\} = \min\{m, n\}$$

If the square matrix $\mathbf{A}$ is of full rank, then there exists a unique matrix $\mathbf{A}^{-1}$, called the *inverse* of $\mathbf{A}$:

$$\mathbf{A}^{-1}\mathbf{A} = \mathbf{A}\mathbf{A}^{-1} = \mathbf{I}$$

The matrix $\mathbf{I}$ is the so-called *identity matrix*:

$$\mathbf{I} = \begin{bmatrix} 1 & 0 & 0 & \cdots & 0 \\ 0 & 1 & 0 & \cdots & 0 \\ 0 & 0 & 1 & \cdots & 0 \\ \vdots & \vdots & \vdots & \vdots & \vdots \\ 0 & 0 & \cdots & 0 & 1 \end{bmatrix}$$

The $n \times n$ matrix $\mathbf{A}$ is called *singular* if its inverse does not exist (i.e., if $\mathrm{rank}\{\mathbf{A}\} < n$).

Some properties of inverse:

$$(\mathbf{AB})^{-1} = \mathbf{B}^{-1}\mathbf{A}^{-1}, \quad (\mathbf{A}^H)^{-1} = (\mathbf{A}^{-1})^H$$

Determinant of a square $n \times n$ matrix (for any i):

$$\det\mathbf{A} = \sum_{k=1}^{n} (-1)^{i+k} a_{ik} \det\mathbf{A}_{ik}$$

where $\mathbf{A}_{ik}$ is the $(n-1) \times (n-1)$ matrix formed by deleting the ith row and the kth column of $\mathbf{A}$.

Example:

$$\mathbf{A} = \begin{bmatrix} a_{11} & a_{12} & a_{13} \\ a_{21} & a_{22} & a_{23} \\ a_{31} & a_{32} & a_{33} \end{bmatrix}$$

$$\det\mathbf{A} = a_{11} \begin{bmatrix} a_{22} & a_{23} \\ a_{32} & a_{33} \end{bmatrix} - a_{12} \begin{bmatrix} a_{21} & a_{23} \\ a_{31} & a_{33} \end{bmatrix} + a_{13} \begin{bmatrix} a_{21} & a_{22} \\ a_{31} & a_{32} \end{bmatrix}$$

Property: an $n \times n$ matrix $\mathbf{A}$ is *invertible* (nonsingular) if and only if its determinant is nonzero

$$\det \mathbf{A} \neq 0$$

Some additional important properties of determinant:

$$\det\{\mathbf{AB}\} = \det\mathbf{A}\,\det\mathbf{B}\ , \quad \det\{\alpha\mathbf{A}\} = \alpha^n \det\mathbf{A}$$

$$\det\mathbf{A}^{-1} = \frac{1}{\det\mathbf{A}}\ , \quad \det\mathbf{A}^T = \det\mathbf{A}$$

Another important function of matrix is *trace*:

$$\mathrm{trace}\{\mathbf{A}\} = \sum_{i=1}^{n} a_{ii}$$

Linear equations

Many practical DSP problems (such as signal modeling, Wiener filtering, etc.) require the solution to a set of linear equations:

$$\begin{aligned}
a_{11}x_1 + a_{12}x_2 + \cdots + a_{1m}x_m &= b_1 \\
a_{21}x_1 + a_{22}x_2 + \cdots + a_{2m}x_m &= b_2 \\
&\vdots \\
a_{n1}x_1 + a_{n2}x_2 + \cdots + a_{nm}x_m &= b_n
\end{aligned}$$

In matrix notation

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

Case 1: square matrix $\mathbf{A}$ $(m = n)$. The nature of solution depends upon whether or not $\mathbf{A}$ is singular. In the *nonsingular* case

$$\mathbf{x} = \mathbf{A}^{-1}\mathbf{b}$$

If $\mathbf{A}$ is singular, there may be *no solution* or *many solutions*.

Example:

$$\begin{aligned} x_1 + x_2 &= 1 \\ x_1 + x_2 &= 2 \qquad\qquad \text{no solution} \end{aligned}$$

However, if we modify the equations:

$$\begin{aligned} x_1 + x_2 &= 1 \\ x_1 + x_2 &= 1 \qquad\qquad \text{many solutions} \end{aligned}$$

Case 2: rectangular matrix $\mathbf{A}$ $(m < n)$. *More equations than unknowns* and, in general, *no solution exist*. The system is called *overdetermined*. In the case when $\mathbf{A}$ is a full rank matrix, and, therefore, $\mathbf{A}^H\mathbf{A}$ is nonsingular, the common approach is to find *least squares solution* by minimizing the norm of the error vector

$$
\begin{aligned}
||\mathbf{e}||^2 &= ||\mathbf{b} - \mathbf{A}\mathbf{x}||^2 \\
&= (\mathbf{b} - \mathbf{A}\mathbf{x})^H(\mathbf{b} - \mathbf{A}\mathbf{x}) \\
&= \mathbf{b}^H\mathbf{b} - \mathbf{x}^H\mathbf{A}^H\mathbf{b} - \mathbf{b}^H\mathbf{A}\mathbf{x} + \mathbf{x}^H\mathbf{A}^H\mathbf{A}\mathbf{x} \\
&= \left[\mathbf{x} - (\mathbf{A}^H\mathbf{A})^{-1}\mathbf{A}^H\mathbf{b}\right]^H(\mathbf{A}^H\mathbf{A})\left[\mathbf{x} - (\mathbf{A}^H\mathbf{A})^{-1}\mathbf{A}^H\mathbf{b}\right] \\
&+ \left[\mathbf{b}^H\mathbf{b} - \mathbf{b}^H\mathbf{A}(\mathbf{A}^H\mathbf{A})^{-1}\mathbf{A}^H\mathbf{b}\right]
\end{aligned}
$$

The second term is *independent* of $\mathbf{x}$. Therefore, the LS solution is

$$\mathbf{x}_{\mathrm{LS}} = (\mathbf{A}^H\mathbf{A})^{-1}\mathbf{A}^H\mathbf{b}$$

The best (LS) approximation of $\mathbf{b}$ is given by

$$\hat{\mathbf{b}} = \mathbf{A}\mathbf{x}_{\mathrm{LS}} = \mathbf{A}(\mathbf{A}^H\mathbf{A})^{-1}\mathbf{A}^H\mathbf{b} = \mathbf{P}_{\mathbf{A}}\mathbf{b}$$

where

$$\mathbf{P}_{\mathbf{A}} = \mathbf{A}(\mathbf{A}^H\mathbf{A})^{-1}\mathbf{A}^H$$

is the so-called *projection matrix* with the properties

$$\mathbf{P}_{\mathbf{A}}\mathbf{a} = \mathbf{a}$$

if the vector $\mathbf{a}$ belongs to the column-space of $\mathbf{A}$ and

$$\mathbf{P}_{\mathbf{A}}\mathbf{a} = 0$$

if this vector is orthogonal to the columns of $\mathbf{A}$

The minimum LS error

$$\begin{aligned} ||e||^2_{\mathrm{min}} &= ||\mathbf{b} - \mathbf{A}\mathbf{x}_{\mathrm{LS}}||^2 \\ &= ||(\mathbf{I} - \mathbf{A}(\mathbf{A}^H\mathbf{A})^{-1}\mathbf{A}^H)\mathbf{b}||^2 \\ &= ||(\mathbf{I} - \mathbf{P}_{\mathbf{A}})\mathbf{b}||^2 = ||\mathbf{P}^{\perp}_{\mathbf{A}}\mathbf{b}||^2 = \mathbf{b}^H\mathbf{P}^{\perp}_{\mathbf{A}}\mathbf{b} \end{aligned}$$

where $\mathbf{P}^{\perp}_{\mathbf{A}} = \mathbf{I} - \mathbf{P}_{\mathbf{A}}$ is the projection matrix on the subspace orthogonal to the column-space of $\mathbf{A}$.

Alternatively, the LS solution is found from the *normal equations*

$$\mathbf{A}^H\mathbf{A}\mathbf{x} = \mathbf{A}^H\mathbf{b}$$

Case 3: rectangular matrix $\mathbf{A}$ $(n < m)$. *Fewer equations than unknowns* and, provided the equations are consistent, there are *many solutions*. The system is called *underdetermined*.

Special matrix forms

Diagonal square matrix:

$$\mathbf{A} = \mathrm{diag}\{a_{11}, a_{22}, \dots, a_{nn}\} = \begin{bmatrix} a_{11} & 0 & 0 & \cdots & 0 \\ 0 & a_{22} & 0 & \cdots & 0 \\ 0 & 0 & a_{33} & \cdots & 0 \\ \vdots & \vdots & \vdots & \vdots & \vdots \\ 0 & 0 & \cdots & 0 & a_{nn} \end{bmatrix}$$

Exchange matrix:

$$\mathbf{J} = \begin{bmatrix} 0 & \cdots & 0 & 0 & 1 \\ 0 & \cdots & 0 & 1 & 0 \\ 0 & \cdots & 1 & 0 & 0 \\ \vdots & \vdots & \vdots & \vdots & \vdots \\ 1 & 0 & \cdots & 0 & 0 \end{bmatrix}$$

Toeplitz matrix:

$$a_{ik} = a_{i+1,k+1} \text{ for all } i, k < n$$

Example:

$$\begin{bmatrix} 1 & 3 & 2 & 4 \\ 2 & 1 & 3 & 2 \\ 7 & 2 & 1 & 3 \\ 1 & 7 & 2 & 1 \end{bmatrix}$$

2.4 Quadratic and Hermitian forms

Quadratic form of a real symmetric square matrix $\mathbf{A}$:

$$Q(\mathbf{x}) = \mathbf{x}^T \mathbf{A} \mathbf{x}$$

Similarly, *Hermitian form* of a Hermitian square matrix $\mathbf{A}$:

$$Q(\mathbf{x}) = \mathbf{x}^H \mathbf{A} \mathbf{x}$$

Symmetric (Hermitian) matrices are positive semidefinite if $Q(\mathbf{x}) \geq 0$ for all nonzero $\mathbf{x}$.
Example: the matrix $\mathbf{A} = \mathbf{y}\mathbf{y}^H$ is positive semidefinite, where $\mathbf{y}$ is an arbitrary complex vector:

$$Q(\mathbf{x}) = \mathbf{x}^H \mathbf{y}\mathbf{y}^H \mathbf{x} = |\mathbf{x}^H \mathbf{y}|^2 \geq 0$$

Eigenvalues and eigenvectors

Consider the *characteristic equation* of an $n \times n$ matrix $\mathbf{A}$:

$$\mathbf{A}\mathbf{u} = \lambda\mathbf{u}$$

This is equivalent to the following set of *homogeneous linear equations*

$$(\mathbf{A} - \lambda\mathbf{I})\mathbf{u} = 0$$

Therefore, the matrix $\mathbf{A} - \lambda\mathbf{I}$ is *singular*. Hence,

$$p(\lambda) = \det(\mathbf{A} - \lambda\mathbf{I}) = 0$$

where $p(\lambda)$ is the so-called *characteristic polynomial* with n roots λ_i $(i = 1, 2 \ldots, n)$ being the *eigenvalues* of $\mathbf{A}$.

For each eigenvalue λ_i, the matrix $\mathbf{A} - \lambda_i \mathbf{I}$ is singular, and, therefore, there will be at least one nonzero *eigenvector* that solves the equation

$$\mathbf{A}\mathbf{u}_i = \lambda_i \mathbf{u}_i$$

Since for any eigenvector $\mathbf{u}_i$ any vector $\alpha \mathbf{u}_i$ will be also an eigenvector, the eigenvectors are often *normalized*:

$$||\mathbf{u}_i|| = 1\,, \quad i = 1, 2, \ldots, n$$

Property 1: The eigenvectors $\mathbf{u}_1, \mathbf{u}_2, \ldots, \mathbf{u}_n$ corresponding to *distinct* eigenvalues are *linearly independent*.

Property 2: If $\mathrm{rank}\{\mathbf{A}\} = m$, then there will be $n - m$ independent solutions to the homogeneous equation $\mathbf{A}\mathbf{u}_i = 0$. These solutions form the so-called *null-space* of $\mathbf{A}$.

Property 3: The eigenvalues of a Hermitian matrix are *real*.

Proof: From the characteristic equation $\mathbf{A}\mathbf{u}_i = \lambda_i \mathbf{u}_i$, we have

$$\mathbf{u}_i^H \mathbf{A} \mathbf{u}_i = \lambda_i \mathbf{u}_i^H \mathbf{u}_i \qquad (*)$$

Taking the Hermitian transpose of $(*)$, we have

$$\mathbf{u}_i^H \mathbf{A}^H \mathbf{u}_i = \lambda_i^* \mathbf{u}_i^H \mathbf{u}_i \qquad (**)$$

Since $\mathbf{A}$ is Hermitian ($\mathbf{A} = \mathbf{A}^H$), $(**)$ becomes

$$\mathbf{u}_i^H \mathbf{A} \mathbf{u}_i = \lambda_i^* \mathbf{u}_i^H \mathbf{u}_i \qquad (***)$$

Finally, comparison of $(*)$ and $(***)$ shows that λ_i are real.

Property 4: A Hermitian matrix is *positive definite* if and only if the eigenvalues of $\mathbf{A}$ are *positive*.

Similar property holds for *positive semidefinite*, *negative definite*, or *negative semidefinite* matrices.

A useful *relationship* between matrix determinant and eigenvalues:

$$\det\{\mathbf{A}\} = \prod_{i=1}^{n} \lambda_i$$

Therefore, any matrix is *invertible* (nonsingular) if and only if *all of its eigenvalues are nonzero*.

Property 5: The eigenvectors of a Hermitian matrix corresponding to distinct eigenvalues are *orthogonal*, i.e., if $\lambda_i \neq \lambda_k$, then $\mathbf{u}_i^H \mathbf{u}_k = 0$.

Proof: Let λ_i and λ_k be two *distinct* eigenvalues of $\mathbf{A}$. Then

$$\mathbf{A}\mathbf{u}_i = \lambda_i \mathbf{u}_i \quad \text{and} \quad \mathbf{A}\mathbf{u}_k = \lambda_k \mathbf{u}_k$$

Multiplying these equations by $\mathbf{u}_k^H$ and $\mathbf{u}_i^H$, respectively, yields

$$\mathbf{u}_k^H \mathbf{A}\mathbf{u}_i = \lambda_i \mathbf{u}_k^H \mathbf{u}_i \,, \quad \mathbf{u}_i^H \mathbf{A}\mathbf{u}_k = \lambda_k \mathbf{u}_i^H \mathbf{u}_k \qquad (*)$$

Taking the Hermitian transpose of the second equation of $(*)$ and remarking that $\mathbf{A}$ is Hermitian (i.e., $\mathbf{A}^H = \mathbf{A}$ and $\lambda_k^* = \lambda_k$), yields

$$\mathbf{u}_k^H \mathbf{A}\mathbf{u}_i = \lambda_k \mathbf{u}_k^H \mathbf{u}_i \qquad (**)$$

Now, subtracting $(**)$ from the first equation of $(*)$ leads to

$$0 = (\lambda_i - \lambda_k)\mathbf{u}_k^H \mathbf{u}_i$$

Since the eigenvalues are *distinct* (i.e., $\lambda_i \neq \lambda_k$), we have that

$$\mathbf{u}_k^H \mathbf{u}_i = 0$$

which proofs the *orthogonality* of eigenvectors.

Remark: Although proven above for the distinct eigenvalue case, this property can be *extended* to any $n \times n$ Hermitian matrix with *arbitrary* (not necessarily distinct) eigenvalues.

Eigendecomposition

For an $n \times n$ matrix $\mathbf{A}$, we may perform an *eigendecomposition*:

$$\mathbf{A} = \mathbf{U}\boldsymbol{\Lambda}\mathbf{U}^{-1} \qquad (*)$$

To do this, let us write the set of equations

$$\mathbf{A}\mathbf{u}_i = \lambda_i \mathbf{u}_i\,, \quad i = 1, 2, \ldots, n$$

in the form

$$\mathbf{A}[\mathbf{u}_1, \mathbf{u}_2, \ldots, \mathbf{u}_n] = [\lambda_1\mathbf{u}_1, \lambda_2\mathbf{u}_2, \ldots, \lambda_n\mathbf{u}_n]\,, \quad \text{or, equivalentely}$$

$$\mathbf{A}\mathbf{U} = \mathbf{U}\boldsymbol{\Lambda} \quad \text{with} \quad \boldsymbol{\Lambda} = \mathrm{diag}\{\lambda_1, \lambda_2, \ldots, \lambda_n\} \qquad (**)$$

and *nonsingular* $\mathbf{U}$. Multiplying $(**)$ on the right by $\mathbf{U}^{-1}$, we get $(*)$.

For a Hermitian matrix, the following property holds because of the orthonormality of eigenvectors:

$$\mathbf{U}^H\mathbf{U} = \mathbf{I}$$

Hence, $\mathbf{U}$ is *unitary* (i.e., $\mathbf{U}^H = \mathbf{U}^{-1}$), and, therefore, the *eigendecomposition* takes the form

$$\mathbf{A} = \mathbf{U}\mathbf{\Lambda}\mathbf{U}^H$$

or, equivalently,

$$\mathbf{A} = \sum_{i=1}^{n} \lambda_i \mathbf{u}_i \mathbf{u}_i^H$$

Using the unitary property of $\mathbf{U}$, it is easy to find *matrix inverse* via eigendecomposition:

$$\begin{aligned}\mathbf{A}^{-1} &= (\mathbf{U}\mathbf{\Lambda}\mathbf{U}^H)^{-1} \\ &= (\mathbf{U}^H)^{-1}\mathbf{\Lambda}^{-1}\mathbf{U}^{-1} \\ &= \mathbf{U}\mathbf{\Lambda}^{-1}\mathbf{U}^H\end{aligned}$$

Equivalently

$$\mathbf{A}^{-1} = \sum_{i=1}^{n} \frac{1}{\lambda_i}\mathbf{u}_i\mathbf{u}_i^H$$

Hence, the inverse *does not affect eigenvectors* but *transforms eigenvalues* λ_i to $1/\lambda_i$.

In many applications, matrices may be very close to singular (*ill-conditioned*) and, therefore, their inverse may be *unstable*. We may wish to stabilize the problem by adding a constant to each term along diagonal (the so-called *diagonal loading*):

$$\mathbf{A} = \mathbf{B} + \alpha \mathbf{I}$$

This operation *leaves eigenvectors unchanged* but *changes eigenvalues*:

$$\mathbf{A}\mathbf{u}_i = \mathbf{B}\mathbf{u}_i + \alpha \mathbf{u}_i = (\lambda_i + \alpha)\mathbf{u}_i$$

where λ_i and $\mathbf{u}_i$ are the eigenvalues and eigenvectors of $\mathbf{B}$:

$$\mathbf{B}\mathbf{u}_i = \lambda_i \mathbf{u}_i$$

We can reformulate the trace of $\mathbf{A}$ in terms of eigenvalues:

$$\mathrm{trace}\{\mathbf{A}\} = \sum_{i=1}^{n} \lambda_i \qquad (*)$$

Similarly,

$$\mathrm{trace}\{\mathbf{A}^{-1}\} = \sum_{i=1}^{n} \frac{1}{\lambda_i}$$

This property can be easily proven using the eigendecomposition and the property $\mathrm{trace}\{\mathbf{A}+\mathbf{B}\} = \mathrm{trace}\{\mathbf{A}\} + \mathrm{trace}\{\mathbf{B}\}$. In several applications (such as adaptive filtering), we need some simple and close upper bound for the maximal eigenvalue $\lambda_{\max}$. From $(*)$, we obtain that

$$\lambda_{\max} \leq \mathrm{trace}\{\mathbf{A}\}$$

Singular value decomposition

For a nonsquare $n \times m$ matrix $\mathbf{A}$, we may perform the SVD instead of eigendecomposition:

$$\mathbf{A} = \mathbf{U}\mathbf{\Lambda}\mathbf{V}^H$$

or, equivalently

$$\mathbf{A} = \sum_{i=1}^{n} \lambda_i \mathbf{u}_i \mathbf{v}_i^H \quad \text{if } n < m$$

and

$$\mathbf{A} = \sum_{i=1}^{m} \lambda_i \mathbf{u}_i \mathbf{v}_i^H \quad \text{if } n > m$$

where $\mathbf{u}_i$ and $\mathbf{v}_i$ are the $n \times 1$ and $m \times 1$ *left and right singular vectors*, respectively, and λ_i are *singular values*.