

Solving Linear Systems

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Case Study

- Solve for flow rates and pressures in a piping network
- 3 equations for flow in a leg
- I conservation equation
- Unknowns are 3 flow rates and a pressure



Schematic





 $\left|Q_a R_a = p_a - p_0\right|$ $\left| Q_b R_b = p_0 - p_b \right|$ $Q_c R_c = p_0 - p_c$ $Q_a = Q_b + Q_c$



Solution Techniques

- Convert to matrix equation
- Solve using \ operator





$$x + 2y + z = 1$$
$$x + y - z = 0$$
$$2x - y + 2z = 1$$

$$\begin{bmatrix} 1 & 2 & 1 \\ 1 & 1 & -1 \\ 2 & -1 & 2 \end{bmatrix} \begin{cases} x \\ y \\ z \end{cases} = \begin{cases} 1 \\ 0 \\ 1 \end{cases}$$



Terminology

- Ax=b
- A=matrix
- x=solution vector
- b=loading vector (right-hand-side of equation)
- A and b known, solve for x



Using Matlab

- A=[| 2 |; | | -|; 2 -| 2];
- b=[1;0;1];
- x=A\b



Practice

• Solve this problem (previous slide)



Practice

• Revise that problem to this:

$$x + 2y + z = 1$$
$$x - z = 0$$
$$2x - y = 1$$

Uniqueness of Solutions

- For a system of N equations in N unknowns, a unique solution exists only if the determinant of A is not zero
- In Matlab, det(A) will give the determinant of A









Solve this matrix equation



Condition Numbers

- Some matrices are "almost singular"
- The condition number is a measure of this characteristic
- If the condition number is large, errors in solving corresponding matrix equations will tend to be large
- The command is **cond(A)**



What are the condition numbers of these matrices?



The Hilbert matrix is defined below...

 Find the condition number of the Hilbert matrix for N=3, 5, and 7







Code for creating Hilbert matrix

Hsize=7 for i=1:Hsize for j=1:Hsize hilb(i,j)=1/(i+j-1); end end disp(hilb)



Solve pipe flow problem

- P_a=12,500 lb/ft²
- P_b=3,500 lb/ft²
- P_c=2,000 lb/ft²
- $R_a = R_b = R_c = 6,000 \text{ lb-s/ft}^5$

 $\left|Q_a R_a = p_a - p_0\right|$ $Q_b R_b = p_0 - p_b$ $Q_c R_c = p_0 - p_c$ $Q_a = Q_b + Q_c$

My Matrix

 $R_a Q_a$ +0+0 $+ p_0$ p_a $+R_bQ_b$ +00 $-p_{0}$ p_b $+R_cQ_c$ +00 $-p_{0}$ p_c +0 $-Q_c$ Q_a $-Q_b$

 R_a 0 0 Q_a p_a R_b 0 -1 0 Q_b p_b -1 R_{c} 0 Q_c p_c



