

Numerical Matrix Analysis

Notes #16 — Systems of Equations
Gaussian Elimination / LU-Factorization with Pivoting

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Student Learning Targets, and Objectives

Target Gaussian Elimination

- Objective The three fundamental row-reduction operations
- Objective Know how the L and U factors arise from Gaussian Elimination (to Reduced Row Echelon Form)
- Objective Stability issues, and potential remedies: Pivoting Strategies



Outline

- 1 Student Learning Targets, and Objectives
 - SLOs: Gaussian Elimination & LU-Factorization
- 2 Gaussian Elimination
 - Introduction: GE — Something Familiar
 - GE, Backward Substitution, and LU-Factorization
 - Computational Complexity
- 3 GE: Instabilities, and Improvements
 - Partial Pivoting
 - Scaled Partial Pivoting
 - Complete Pivoting



Gaussian Elimination: Introduction

We look at a familiar algorithm — Gaussian Elimination.

- The “pure” form.
- Connection to LU-factorization.
- Pivoting strategies to improve stability:
 - Scaled Partial Pivoting
 - (Rescaled) Scaled Partial Pivoting
 - Complete Pivoting



The Augmented Matrix $[A \ \vec{b}]$

Given a matrix A and a column vector \vec{b}

$$A = \begin{bmatrix} a_{11} & a_{12} & a_{13} \\ a_{21} & a_{22} & a_{23} \\ a_{31} & a_{32} & a_{33} \end{bmatrix} \quad \vec{b} = \begin{bmatrix} b_1 \\ b_2 \\ b_3 \end{bmatrix},$$

we define the **augmented matrix**

$$[A \ \vec{b}] = \left[\begin{array}{ccc|c} a_{11} & a_{12} & a_{13} & b_1 \\ a_{21} & a_{22} & a_{23} & b_2 \\ a_{31} & a_{32} & a_{33} & b_3 \end{array} \right]$$

We are going to operate on this augmented matrix using 3 fundamental operations...



Three Basic Operations on the Linear System / Augmented Matrix

We use three operations to simplify a linear system:

- op#1 **Scaling** — Equation# i (E_i) can be multiplied by any non-zero constant λ with the resulting equation used in place of E_i . We denote this operation $(E_i) \leftarrow (\lambda E_i)$.
- op#2 **Scaled Addition** — Equation# j (E_j) can be multiplied by any non-zero constant λ and added to Equation# i (E_i) with the resulting equation used in place of E_i . We denote this operation $(E_i) \leftarrow (E_i + \lambda E_j)$.
- op#3 **Reordering** — Equation# j (E_j) and Equation# i (E_i) can be transposed in order. We denote this operation $(E_i) \leftrightarrow (E_j)$.



Gaussian Elimination, Backward Substitution, and LU-Factorization

The goal is to apply a sequence of the operations on the augmented matrix

$$[A \ \vec{b}] = \left[\begin{array}{ccc|c} a_{11} & a_{12} & a_{13} & b_1 \\ a_{21} & a_{22} & a_{23} & b_2 \\ a_{31} & a_{32} & a_{33} & b_3 \end{array} \right],$$

in order to transform it into the **upper triangular form**

$$\left[\begin{array}{ccc|c} \tilde{a}_{11} & \tilde{a}_{12} & \tilde{a}_{13} & \tilde{b}_1 \\ 0 & \tilde{a}_{22} & \tilde{a}_{23} & \tilde{b}_2 \\ 0 & 0 & \tilde{a}_{33} & \tilde{b}_3 \end{array} \right].$$

From this form we use **backward substitution** to get the solution:

$$x_3 \leftarrow \tilde{b}_3 / \tilde{a}_{33}, \quad x_2 \leftarrow (\tilde{b}_2 - \tilde{a}_{23}x_3) / \tilde{a}_{22},$$

$$x_1 \leftarrow (\tilde{b}_1 - \tilde{a}_{12}x_2 - \tilde{a}_{13}x_3) / \tilde{a}_{11}.$$



GE+BS+LU

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Given an augmented matrix

$$C = [A \ \vec{b}] = \left[\begin{array}{cccc|c} a_{11} & a_{12} & a_{13} & \dots & a_{1m} & b_1 \\ a_{21} & a_{22} & a_{23} & \dots & a_{2m} & b_2 \\ a_{31} & a_{32} & a_{33} & \dots & a_{3m} & b_3 \\ \vdots & & & \ddots & \vdots & \vdots \\ a_{m1} & a_{m2} & a_{m3} & \dots & a_{mm} & b_m \end{array} \right]$$

We first make all the sub-diagonal entries in the first column zero:

```
for j = 2:m
    [Eliminate the first column]
    lj1 ← -cj1/c11
    rj ← (lj1r1 + rj)  [rj denotes elements in the jth row]
end
```



The pattern is clear... For a full implementation we eliminate all the sub-diagonal elements in columns $1 \rightarrow (m-1)$:

```

for i = 1:(m-1)
  for j = (i+1):m           [Eliminate the i-th column]
    lji ← -cji/cii
    rj ← (ljiri + rj)   [rj -- elements in the j-th row]
  end
end
end
    
```



After the elimination step, we have the following scenario — the augmented matrix is now upper triangular; we identify the upper triangular part U , and the modified right-hand-side \tilde{b} , and collect the multipliers in matrices M_j

$$\tilde{c} = [U \ \tilde{b}] = \left[\begin{array}{cccccc|c} u_{11} & u_{12} & u_{13} & \dots & u_{1m} & \tilde{b}_1 \\ & u_{22} & u_{23} & \dots & u_{2m} & \tilde{b}_2 \\ & & u_{33} & \dots & u_{3m} & \tilde{b}_3 \\ & & & \ddots & \vdots & \vdots \\ & & & & u_{mm} & \tilde{b}_m \end{array} \right], M_1 = \left[\begin{array}{cccccc} 1 & & & & & \\ \ell_{21} & 1 & & & & \\ \ell_{31} & 0 & 1 & & & \\ \vdots & \vdots & \vdots & \ddots & & \\ \ell_{m1} & 0 & \dots & 0 & 1 & \end{array} \right]$$

We have the relation

$$\underbrace{M_{m-1} \cdot M_{m-2} \cdots M_1}_{M} \cdot C = M \cdot C = M \cdot [A \mid \vec{b}] = [U \mid \tilde{b}] = \tilde{C}$$



Now, if we are looking for the solution to $A\vec{x} = \vec{b}$, we simply apply backward substitution to the $[U \mid \tilde{b}]$ system.

If we define $L = M^{-1}$; — think of it as inverting (undoing) the triangularization of A

$$L = M_1^{-1} M_2^{-1} \cdots M_{m-1}^{-1} = \left[\begin{array}{cccccc} 1 & & & & & \\ -\ell_{21} & 1 & & & & \\ -\ell_{31} & -\ell_{32} & 1 & & & \\ \vdots & \vdots & \vdots & \ddots & & \\ -\ell_{m1} & -\ell_{m2} & \dots & -\ell_{m,m-1} & 1 & \end{array} \right]$$

Then we have the **LU-Factorization** of A

$$A = LU.$$



We can view the entire GE-algorithm as a sequence of matrix multiplications:

$$\underbrace{M_{m-1} M_{m-2} \cdots M_2 M_1}_M A = U$$

and it follows that we can write

$$A = M^{-1}U = [M_1]^{-1}[M_2]^{-1} \dots [M_{m-2}]^{-1}[M_{m-1}]^{-1}U$$

The multiplication by the matrices $[M_j]$ correspond to scaled row-addition; the inverse operation is scaled row-subtraction, hence

$$[M_j]^{-1} = \left[\begin{array}{cccccc} 1 & & & & & \\ & \ddots & & & & \\ & & 1 & & & \\ & & -\ell_{j+1,j} & 1 & & \\ & & \vdots & \vdots & \ddots & \\ & & -\ell_{m,j} & & & 1 \end{array} \right] \quad \text{Next, we check this!}$$



GE+BS: Work Required

Elimination Steps

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↓ more work ↓	LU-Factorization	$\frac{2m^3}{3}$	↓ more stability* ↓
	QR: Householder, "Q-less"	$\frac{4m^3}{3}$	
	QR: Gram-Schmidt	$2m^3$	
	SVD	$13m^3$	

* GS-QR is not necessarily more stable than H-QR...



Instability of Gaussian Elimination / LU-Factorization

As described, GE/LU **can run into stability issues** — consider the multipliers in the light of stability and floating-point errors

$$\tilde{\ell}_{ji} = -c_{ij} \oslash c_{ii} = -\frac{c_{ij}}{c_{ii}}(1 + \epsilon), \quad |\epsilon| \leq \epsilon_{\text{mach}}$$

Hence, the absolute errors introduced in the multipliers are

$$\delta \ell_{ji} \sim \epsilon_{\text{mach}} \left(\frac{c_{ij}}{c_{ii}} \right)$$

and if c_{ii} is close to zero, then the error may be very large (especially in comparison with other entries in the matrix).

We need to fix this...

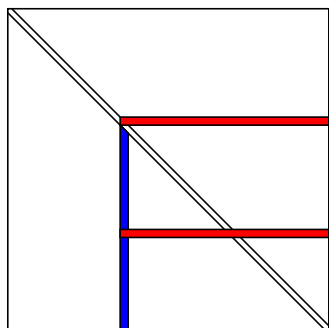
Clearly, **the smaller the multipliers, the smaller the errors...**



Pivoting Strategies

Partial Pivoting

It is fairly easy to re-arrange the computation so that all multipliers are bounded by 1.



Partial pivoting adds $\frac{m^2}{2}$ comparisons to the algorithm.

Figure: Illustration of elimination on the k th level. We search for the largest (in magnitude) pivot element in the k th column, among the diagonal+sub-diagonal elements (vertical blue band). Then we interchange the k th row with the row with the maximal pivot (illustrated with two horizontal red bands).



Gaussian Elimination with Partial Pivoting

$$U = [A \vec{b}]$$

```

1 L = eye(m); P=eye(m); U = [A b];
2 for k = 1:(m-1)
3     Umax = max(abs(U(k:m,k)));
4     Umax_index = find(abs(U(k:m,k)) == Umax);
5     j = Umax_index(1) + (k-1);
6     U([j k],k:(m+1)) = U([k j],k:(m+1));
7     L([j k],1:(k-1)) = L([k j],1:(k-1));
8     P([j k],:) = P([k j],:);
9     for j=(k+1):m
10        L(j,k) = U(j,k) / U(k,k);
11        U(j,k:(m+1)) = U(j,k:m+1) - L(j,k)*U(k,k:(m+1));
12    end
13 end
    
```

The algorithm yields

$$PA = LU.$$

It is much more stable than our initial two implementations of Gaussian Elimination, but it is **not** fail-safe.



Row- and Column-Swapping in Python

```
# Swap Rows r1 and r2
A = np.array([[...], ..., [...]])
A[[r1, r2]] = A[[r2, r1]]
```

```
# Swap Columns c1 and c2
A = np.array([[...], ..., [...]])
A[:, [c1, c2]] = A[:, [c2, c1]]
```



Gaussian Elimination with Partial Pivoting: Breakdown

If we apply GE+PP to a system where the **scales** of the different equations are significantly different, the algorithm may break down (unnecessarily lose precision) e.g

$$\begin{bmatrix} 1 & -2 & 3 \\ 1,000,000 & 2,000,000 & 3,000,000 \\ 0.000001 & -0.000002 & -0.000003 \end{bmatrix} \vec{x} = \begin{bmatrix} 4 \\ 5,000,000 \\ 0.000001 \end{bmatrix}$$

In order to improve stability of GE+PP we must take scale into consideration.

One definition of scale: $s(i) = \max(\text{abs}(B(i,:)))$, i.e. the scale of row #i equals to the magnitude of the largest element on that row.



Gaussian Elimination with Scaled Partial Pivoting

"Scale Invariant PP"???

We can pre-compute the scales $s(i)$ and make the pivoting decision based on the values of $B(i,i)/s(i)$ and $B(j,i)/s(j)$, $j=(i+1):n$.

```
s = zeros(m,1);
for i=1:m
    s(i) = max(abs(B(i,:)));
end
for i=1:(m-1)
    Bmax = max(abs(B(i:m,i)./s(i:m)));
    Bmax_index = find( abs(B(i:m,i)./s(i:m)) == Bmax );
    j = Bmax_index(1) + (i-1);
    B([j i],i:(m+1)) = B([i j],i:(m+1));
    L([j i],1:(i-1)) = L([i j],1:(i-1));
    P([j i],:) = P([i j],:);
    for j=(i+1):m
        L(j,i) = -B(j,i) / B(i,i);
        B(j,i:(m+1)) = L(j,i)*B(i,i:(m+1)) + B(j,i:(m+1));
    end
end
```



GE+SPP: Work Comparison

```
s = zeros(m,1);
for i=1:m
    s(i) = max(abs(B(i,:)));
end
for i=1:(m-1)
    Bmax = max(abs(B(i:m,i)./s(i:m)));
    Bmax_index = find( abs(B(i:m,i)./s(i:m)) == Bmax );
    j = Bmax_index(1) + (i-1);
    B([j i],i:(m+1)) = B([i j],i:(m+1));
    L([j i],1:(i-1)) = L([i j],1:(i-1));
    P([j i],:) = P([i j],:);
    for j=(i+1):m
        L(j,i) = -B(j,i) / B(i,i);
        B(j,i:(m+1)) = L(j,i)*B(i,i:(m+1)) + B(j,i:(m+1));
    end
end
```

Note that the scale computation touches every element in the matrix, hence it adds

$\mathcal{O}(m^2)$ additional operations.

Since this algorithm overall requires $\mathcal{O}(m^3)$ operations, the overhead of scaled partial pivoting does not add a significant amount of work.



GE+SPP: Wait a Minute! — The Scale Changes

Since we are modifying the rows in each elimination step, it seems likely that the scale of the row change. Should we recompute them???

```
s = zeros(m,1);
for i=1:(m-1)
    for k=i:m
        s(k) = max(abs(B(k,:)));
    end
    Bmax = max(abs(B(i:m,i)./s(i:m)));
    Bmax_index = find( abs(B(i:m,i)./s(i:m)) == Bmax );
    j = Bmax_index(1) + (i-1);
    B([j i],i:(m+1)) = B([i j],i:(m+1));
    L([j i],1:(i-1)) = L([i j],1:(i-1));
    P([j i],:) = P([i j],:);
    for j=(i+1):m
        L(j,i) = -B(j,i) / B(i,i);
        B(j,i:(m+1)) = L(j,i)*B(i,i:(m+1)) + B(j,i:(m+1));
    end
end
```

Let's call this GE+Rescaled-SPP (GE+RSPP). Since we are touching all the remaining elements in the matrix in each iteration, this configuration adds

$\mathcal{O}(m^3)$ additional operations,

which is a significant amount of work.



GE with Complete Pivoting

GE+CP

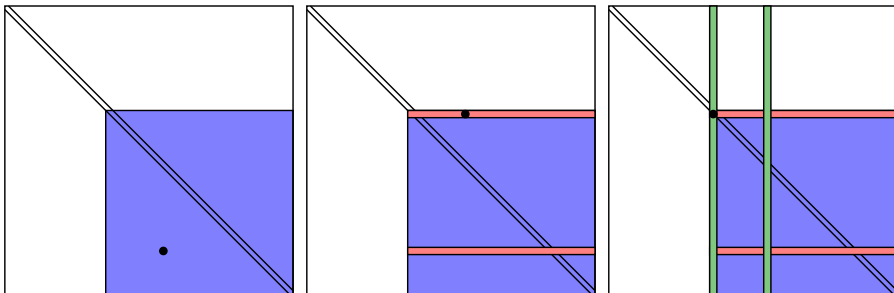
If/when a problem warrants this (GE+RSPP) approach due to high accuracy demands, and we are willing to trade significant time/work for it) **complete pivoting** should be used instead.

```
for i=1:(m-1)
    Bmax = max(max(abs(B(i:m,i:m))));
    [Bmax_r,Bmax_c] = find( abs(B(i:m,i:m)) == Bmax );
    j_r = Bmax_r(1) + (i-1);
    j_c = Bmax_c(1) + (i-1);
    B([j_r i],i:(m+1)) = B([i j_r],i:(m+1));
    L([j_r i],1:(i-1)) = L([i j_r],1:(i-1));
    P([j_r i],:) = P([i j_r],:);
    B(:, [j_c i]) = B(:, [i j_c]);
    for j=(i+1):m
        L(j,i) = -B(j,i) / B(i,i);
        B(j,i:(m+1)) = L(j,i)*B(i,i:(m+1)) + B(j,i:(m+1));
    end
end
```

WARNING!!! — When the columns are interchanged, the unknowns are re-ordered. We have to implement extra book-keeping in order to keep track!



Illustration: Gaussian Elimination with Complete Pivoting



[Left] Illustration of elimination on the k th level. We search for the largest (in magnitude) pivot element in the sub-matrix indicated with blue; the pivot is marked with a black dot.

[Center] We interchange the corresponding rows, to move the pivot to the “active” row.

[Right] We interchange the columns to move the pivot to the “active” A_{kk} pivot location.



GE with Complete Pivoting

Book-keeping

GE+CP

```
col_idx = (1:m)';
for i=1:(m-1)
    Bmax = max(max(abs(B(i:m,i:m))));
    [Bmax_r,Bmax_c] = find( abs(B(i:m,i:m)) == Bmax );
    j_r = Bmax_r(1) + (i-1);
    j_c = Bmax_c(1) + (i-1);
    B([j_r i],i:(m+1)) = B([i j_r],i:(m+1));
    L([j_r i],1:(i-1)) = L([i j_r],1:(i-1));
    P([j_r i],:) = P([i j_r],:);
    B(:, [j_c i]) = B(:, [i j_c]);
    col_idx([j_c i]) = col_idx([i j_c]);
    for j=(i+1):m
        L(j,i) = -B(j,i) / B(i,i);
        B(j,i:(m+1)) = L(j,i)*B(i,i:(m+1)) + B(j,i:(m+1));
    end
end
```

After completion, `col_idx(i)` contains the original index of the variable currently called `x(i)`.

After GE+CP, we solve for \vec{x} using standard Backward Substitution, then we use the `col_idx` array to put the solution array back in the correct order:



GE with Complete Pivoting

Reconstitution

GE+CP

GE+CP+BS gives us a vector with the order of the x_i 's "scrambled" from the column interchanges. To unscramble:

```
I = eye(n);
P2 = I(:,col_idx);
x = P2*x;
```

and we have solved $A\vec{x} = \vec{b}$ in the most stable way! (In the framework of Gaussian elimination, that is...)

Note: We can handle the row-pivoting in the same way (using an "index-array") `row_idx`.



Next Time

- A formal look at stability of Gaussian Elimination.
- Gaussian Elimination for **Hermitian Positive Definite Matrices:**
 - Cholesky Factorization.



Homework (Not Explicitly Due...)

Read Trefethen & Bau's take on Gaussian Elimination and Pivoting, pp. 147–162.

