

$$13) A = \begin{bmatrix} 1 & 0 & 0 \\ 2 & 1 & -2 \\ 3 & 2 & 1 \end{bmatrix}$$

$$P(\lambda) = \det \begin{pmatrix} \lambda-1 & 0 & 0 \\ -2 & \lambda-1 & 2 \\ -3 & -2 & \lambda-1 \end{pmatrix} = (\lambda-1) \cdot (\lambda^2 - 2\lambda + 5) = \lambda^3 - 2\lambda^2 + 5\lambda - \lambda^2 + 2\lambda - 5 = 5 - 2\lambda + 2\lambda^2 - \lambda^2 + 2\lambda - 5 = \lambda^3 - 3\lambda^2 + 7\lambda - 5$$

Autovekt. $\rightarrow P(\lambda) = 0$

$$\begin{aligned} \lambda_1 &= 1 \\ \lambda_2 &= 1 + 2i \\ \lambda_3 &= 1 - 2i \end{aligned}$$

Para $\lambda = 1$

$$\begin{pmatrix} 0 & 0 & 0 \\ -2 & 0 & 2 \\ -3 & -2 & 0 \end{pmatrix} \rightarrow \begin{pmatrix} -3 & -2 & 0 \\ -2 & 0 & 2 \\ 0 & 0 & 0 \end{pmatrix} \xrightarrow{F_2 \leftrightarrow 2F_1 - 3F_2} \begin{pmatrix} -3 & -2 & 0 \\ 0 & -4 & -6 \\ 0 & 0 & 0 \end{pmatrix}$$

$$\rightarrow \begin{cases} -3x - 2y = 0 \rightarrow -3x = -\frac{6}{2}z \rightarrow -3x = -3z \rightarrow x = z \\ -4y - 6z = 0 \rightarrow y = -\frac{3}{2}z \end{cases}$$

$$\rightarrow \vec{x} = \left(z; -\frac{3}{2}z; z \right) = z \cdot \left(1; -\frac{3}{2}; 1 \right)$$

ΑΥΤΟΒΕΚΤΟΡ (ΜΟΝΤΙΠΛΟ)

$$\lambda = 1 \rightarrow (z; -3/2z; z)$$

Para $1 + 2i = \lambda$

$$\begin{pmatrix} 2i & 0 & 0 \\ -2 & 2i & 2 \\ -3 & -2 & 2i \end{pmatrix} \rightarrow \begin{pmatrix} -3 & -2 & 2i \\ -2 & 2i & 2 \\ 2i & 0 & 0 \end{pmatrix} \xrightarrow{\begin{matrix} F_2 \rightarrow 2F_1 - 3F_2 \\ F_3 \rightarrow 2iF_1 + 3F_3 \end{matrix}} \begin{pmatrix} -3 & -2 & 2i \\ 0 & -4-6i & -6+4i \\ 0 & -4i & -4 \end{pmatrix}$$

$\rightarrow \begin{cases} x=0 \\ y=iz \end{cases}$ SISTEMA RESUELTO POR COMPU.

$\rightarrow \bar{X} = (0, iz, z) = z \cdot \underbrace{(0, i, 1)}_{\substack{\text{Autovector} \\ \lambda = 1+zi}}$

Para $\lambda = 1-zi$ será el conjugado:

Autovector $\lambda = 1-zi \rightarrow (0, -i, 1)$

$Y_1 = e^t \cdot \begin{pmatrix} 2 \\ 2 \\ -3 \\ 2 \end{pmatrix}$ $Y_2 = e^{(1+zi)t} \cdot \begin{pmatrix} 0 \\ i \\ 1 \\ 1 \end{pmatrix}$ $Y_3 = e^{(1-zi)t} \cdot \begin{pmatrix} 0 \\ -i \\ 1 \\ 1 \end{pmatrix}$

$\rightarrow Y_t = (Y_1, Y_2, Y_3)$

Se podría pasar todo a reales.