

Some relations between equilibria of harmonic vector fields and the domain topology

Theo Koppenhöfer

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Supervisor: Erik Wahlén

Examiner: Evgeniy Lokharu

DEPARTMENT OF MATHEMATICS

UNIVERSITET LUND

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General TODOs

- Check for typos.
- add Alber
- bring in results from [28] and [25]

Some questions

- Should I state Hopf's Lemma?

1 Introduction

Some amazing introduction

Unless otherwise stated we denote by $X \subseteq \mathbb{R}^d$ a compact subset of \mathbb{R}^d with boundary $\Sigma = \partial X$ and nonempty interior $\text{int}(X)$. In the following we will work in dimensions $d \in \{2, 3\}$. Unless otherwise stated we denote by

$$f: X \rightarrow \mathbb{R}$$

a C^2 function on X . Often f will be assumed to be *harmonic*, that is $\Delta f = 0$ on $\text{int}(X)$ where Δ denotes the Laplace operator. We also denote by

$$u: X \rightarrow \mathbb{R}^d$$

a vector field of class C^1 . In the following we often assume that u is in fact a *harmonic vector field*, that is u fulfils $\text{div } u = 0$ and $\text{curl } u = 0$ on $\text{int}(X)$. Note that a harmonic function f gives rise to a harmonic vector field via $u = \nabla f$. In general a harmonic vector field u is not the gradient of a harmonic function as example ?? will illustrate. On simply connected domains this implication is however true:

Proposition 1.1 (Harmonic vector fields on simply connected domains). *Let $d \in \{2, 3\}$ and $\Omega \subseteq \mathbb{R}^d$ be open and simply connected and u be a harmonic vector field. Then*

1. $u = \nabla f$ is the gradient field of some function $f: \Omega \rightarrow \mathbb{R}$.
2. f is harmonic.
3. u is in fact C^∞ .
4. The components u_i are harmonic.

Proof. 1. Since $\text{curl } u = 0$ this is a direct consequence of Stokes theorem.

2. This follows from $\Delta f = \text{div } u = 0$.
3. This follows from the fact that f is harmonic
4. This follows from $u_i = \partial_i f$.

□

1 Introduction

If one considers not necessarily simply connected domains Ω then we obtain the properties of proposition 1.1 at least locally.

One question we seek to answer in this thesis is the following:

Question 1.2 (Flowthrough with stagnation point). Does there exist a region $X \subseteq \mathbb{R}^d$ homeomorphic to a ball with flow u through the region such that

1. u is a harmonic vector field
2. u has an interior stagnation point
3. the boundary on which u enters the region is simply connected?

The answer for this will turn out to be ‘yes’ for dimensions $d \geq 3$ and ‘no’ for $d = 2$ dimensions. Somewhat related, [20, p.198] poses the question whether it is possible to have a harmonic vector field without inflow or outflow through the boundary with interior stagnation points in \mathbb{R}^3 . Inspired by this we will also consider the following question:

Question 1.3 (Stagnation points of harmonic vector fields without inflow or outflow). Let u be a harmonic vector field in a domain X such that at every boundary point it is tangential to the boundary. What can be said about the relation between the number of stagnation points and the domain topology?

This question yields a very nice result in the case of $d = 2$ dimensions. To make the formulation of these questions more precise we begin with some general definitions regarding stagnation points and the boundary behaviour.

General definitions

We start by requiring some regularity for the boundary of X . More precisely, we require X to be a compact Riemannian manifold with corners:

Definition 1.4 (Manifolds with corners, [11]). We introduce the notation

$$H_j^d := \mathbb{R}_{\geq 0}^j \times \mathbb{R}^{d-j} \subseteq \mathbb{R}^d.$$

where $j \in \{0, \dots, d\}$. A *manifold with (convex) corners* is a topological space X together with an atlas \mathcal{A} such that for every point $x \in X$ there exists an open neighbourhood U_x of x , a number $j = j(x)$ and a diffeomorphism $\phi: U_x \rightarrow H_j^d$ in \mathcal{A} with $\phi(x) = 0$. We further define for $k \in \{0, \dots, d\}$ a collection of sets

$$X_k := \{x \in X : j(x) = d - k\}, \tag{1.1}$$

which form a stratification of X .

More generally we give the definition of a stratification as follows:

Definition 1.5 (Stratified space, [11]). Let X be a topological space. A *stratum* is a subspace $X_j \subseteq X$, $j \in \mathcal{J}$, indexed by a partially ordered set \mathcal{J} such that

1. each X_j is a manifold (without boundary) of dimension $n = n(j)$
2. $X = \bigcup_j X_j$
3. $X_j \cap \bar{X}_k \neq \emptyset$ iff $X_j \subseteq \bar{X}_k$ iff $j \prec k$.

The pair of X and the collection of strata is called a *stratified space*. In the case that $X_j \subseteq \bar{X}_k$ we will write $X_j \prec X_k$ using the notation of [11]. If additionally $n(k) = 0$ or $n(k) = n(j) + 1$ we will write $X_j \preceq X_k$ or, abusing notation, we will write $X_k = X_{j+1}$.

$n(k) = 0$ or $n(k) = n(j) + 1$ a little unclear. Also $X_0 \preceq X_0$ unclear.

In the case that the stratification arises through relation (1.1) we have precisely $X_j \preceq X_{j+1}$ for $j \in \{1, \dots, d\}$ and $X_0 \preceq X_0$. Note that in general for a given stratum X_j the stratum X_{j+1} such that $X_j \preceq X_{j+1}$ need not be unique. In the following we assume, unless otherwise stated, that the stratification is finite, that is $\# \mathcal{J} < \infty$ and that the interior $\text{int}(X)$ corresponds to a single stratum.

For completeness we also give the definition of the contingent cone for a stratification X_j of X :

Definition 1.6 (Contingent cone, [17, Def. 4.6]). We denote the (*Bouligand*) *contingent cone* for a set $Y \subseteq X$ at $x \in \bar{Y}$ by $C_x Y$. It is defined as the set of all $v \in \mathbb{R}^d$ such that there exist sequences $\lambda: \mathbb{N} \rightarrow \mathbb{R}_{>0}$ and $x_n \rightarrow x$ in Y such that

$$\lim_n \lambda_n (x_n - x) = v.$$

For clarification we give an example

Example 1.7 (Cubical domain). Consider the domain to be the cube $X = [-1, 1]^2 \subseteq \mathbb{R}^2$. Then we have a stratification given by

$$\begin{aligned} X_0 &= \left\{ \begin{bmatrix} -1 \\ -1 \end{bmatrix}, \begin{bmatrix} -1 \\ 1 \end{bmatrix}, \begin{bmatrix} 1 \\ 1 \end{bmatrix}, \begin{bmatrix} 1 \\ -1 \end{bmatrix} \right\} \\ X_1 &= (I \times \{-1\}) \cup (I \times \{1\}) \cup (\{-1\} \times I) \cup (\{1\} \times I) \\ X_2 &= I \times I \end{aligned}$$

where $I = (-1, 1) \subseteq \mathbb{R}$. The stratification is depicted in figure 1.1. For an interior point $x \in X_2$ we have the contingent cone $C_x X = \mathbb{R}^2$. For a boundary point $x \in Y = I \times \{1\} \subset X_1$ we have the contingent cone

$$C_x X = \{v \in T_x \mathbb{R}^2 : v \cdot n \leq 0\}$$

where the basis vector $n = e_2$ is the outer unit normal. At the boundary point $x = \begin{bmatrix} 1 & 1 \end{bmatrix}^\top \in X_0$ we have

$$C_x X = \{v \in T_x \mathbb{R}^2 : v_1 \leq 0 \text{ and } v_2 \leq 0\}.$$

The situation is depicted in figure 1.2. The contingent cone on the other parts of the square $\Sigma = \partial X$ is given by similar formulas.

1 Introduction

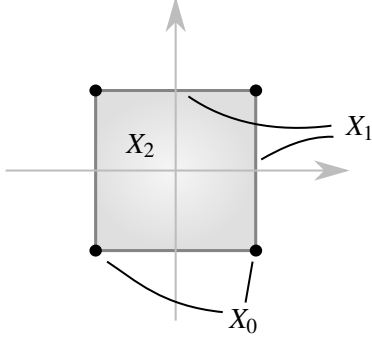


Figure 1.1: A stratification of X .

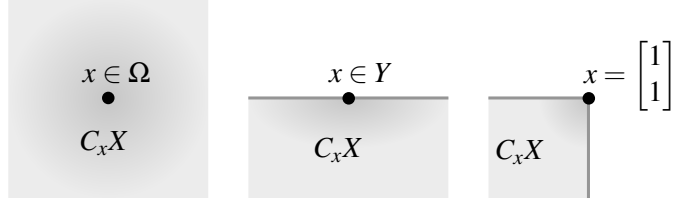


Figure 1.2: The contingent cones for various $x \in X$.

In the following we define the emergent and the entrant boundary in a way that generalises [25, p.282] for stratified manifolds.

Definition 1.8 (Emergent and entrant boundary). We call a vector $v \in T_x X$ *entrant* at a boundary point $x \in \Sigma$ if

1. v points into $\text{int}(X)$ or
2. v lies in the dual cone of the contingent cone $C_x X$, that is

$$v \in (C_x X)^* = \{w \in T_x X : w \cdot w' \geq 0 \text{ for all } w' \in C_x X\}.$$

We call v *strictly entrant* if in addition v is not tangential to Σ and if $v \in (C_x X)^*$ then v lies in the relative interior $\text{relint}(C_x X)^*$. Analogously v is *(strictly) emergent* if $-v$ is (strictly) entrant. Now define the *entrant boundary* $\Sigma^{\leq 0}$ to be the set of boundary points at which u is entrant. We define the *strictly entrant boundary* Σ^- to be the set of strictly entrant boundary points of u . In the same manner we define the *emergent boundary* $\Sigma^{\geq 0}$ and the *strictly emergent boundary* Σ^+ . Further define the *tangential boundary* Σ^0 to be

$$\Sigma^0 := \Sigma^{\leq 0} \cup \Sigma^{\geq 0} \setminus (\Sigma^+ \cup \Sigma^-) \subseteq \Sigma. \quad (1.2)$$

We would now like to illustrate the preceding definitions.

Example 1.9. Consider the domain to be the cube $X = [-1, 1]^2 \subseteq \mathbb{R}^2$ and the harmonic function

$$\begin{aligned} f: X &\rightarrow \mathbb{R} \\ x &\mapsto x_1^2 - x_2^2. \end{aligned} \quad (1.3)$$

This induces the harmonic vector field $u = \nabla f$, or more precisely

$$\begin{aligned} u: X &\rightarrow \mathbb{R}^3 \\ x &\mapsto 2 \begin{bmatrix} x_1 & -x_2 \end{bmatrix}^\top. \end{aligned} \quad (1.4)$$

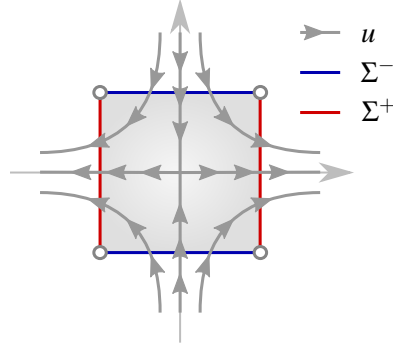


Figure 1.3: Depiction of the entrant and emergent boundaries for the function f given by equation (1.3)

For a boundary point $x \in I \times \{1\}$ the dual cone of the contingent cone $C_x X$ is given by

$$(C_x X)^* = \{-re_2 : r \geq 0\}.$$

Now we have that $x \in \Sigma^{\leq 0}$ if

$$0 \geq n \cdot u = -2x_2$$

which is always fulfilled and thus $I \times \{1\} \subseteq \Sigma^{\leq 0}$. At the boundary point $x = [1 \ 1]^\top$ the dual of the contingent cone is given by

$$(C_x X)^* = C_x X. \quad (1.5)$$

Since $v = u(x) = 2[1 \ -1]^\top$ we have that $v \notin (C_x X)^*$ and $-v \notin (C_x X)^*$ and thus $x \notin \Sigma^{\geq 0} \cup \Sigma^{\leq 0}$. By analogous argumentation on the other sides of the square $\Sigma = \partial X$ one obtains that

$$\begin{aligned} \Sigma^{\leq 0} &= (I \times \{1\}) \cup (I \times \{-1\}) \\ \Sigma^{\geq 0} &= (\{1\} \times I) \cup (\{-1\} \times I). \end{aligned}$$

A plot of the sets can be seen in figure 1.3.

Since the dual of the contingent cone $(C_x X)^*$ will also play a role later on we make a further remark to illustrate the concept.

Remark (Contingent cone). If the angle of the cone $C_x X$ at a corner point x in the plane is α the angle formed by the cone $(C_x X)^*$ is $\pi - \alpha$. Thus equation (1.5) in the previous example is a special case for $\alpha = \pi/2$. The more general case is illustrated in figure 1.4.

Given a vector field $u: X \rightarrow \mathbb{R}^d$ and a stratification X_j of X we can construct for every $j \in \mathcal{J}$ a vector field

$$u_j: X_j \rightarrow T^*X_j.$$

1 Introduction

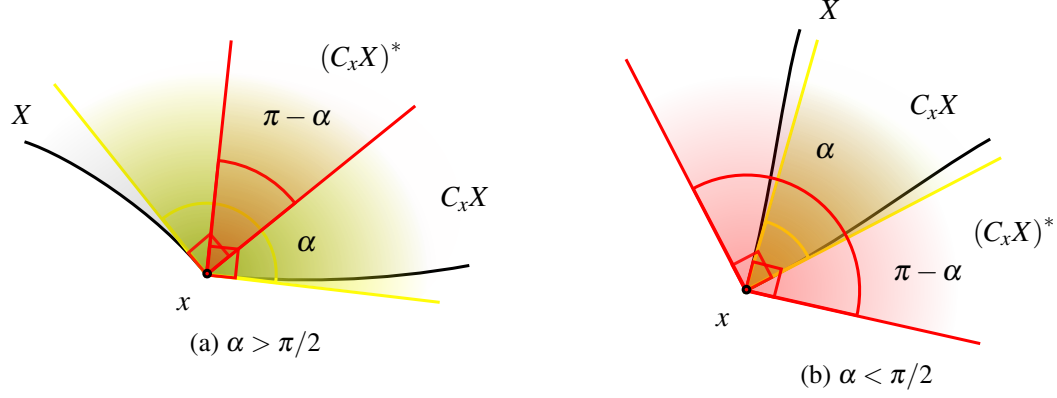


Figure 1.4: Illustration of a planar contingent cone (yellow) and its dual cone (red).

Here T^*X_j denotes the cotangent space of the manifold X_j which is defined for instance in [15, Chapter 6]. More precisely, for $x \in X_j$ let

$$\pi_j|_x: T_x^*X \rightarrow T_x^*X_j \quad (1.6)$$

denote the orthogonal projection of a vector at x onto the cotangent space of the stratum X_j at x . Now let

$$u_j := \pi_j \circ u|_{X_j} \in C^1(T^*X_j) \quad (1.7)$$

be the projection of u onto the cotangent bundle T^*X_j .

The following are slight generalisations of definitions given in [28, p.138f], [26, §5] and [25, p.282f] to include harmonic vector fields.

Definition 1.10 (Stagnation points). Let $u_j: X_j \rightarrow T^*X_j$ be a C^1 vector field on a stratum X_j of X . We call the zeroes $x \in X_j$ of u_j *stagnation points of u_j on X_j* . If $x \in \text{int}(X)$ then we call x an *interior stagnation point*. If $u(x) \in (C_x X)^*$ we call x an *essential stagnation point*. The set of all essential stagnation points of u_j is denoted by $\text{Cr}_j = \text{Cr}_j(u)$ and the essential stagnation points of u and $-u$ on X_j are called *stagnation points of u on X_j* . A stagnation point x of u_j is called *non-degenerate* if the derivative

$$Du_j(x) = Du_j|_x \in T_x T^*X_j \cong \mathbb{R}^{n(j) \times n(j)}$$

is bijective. In addition we say that x has *index k* if $Du_j(x)$ has exactly k negative eigenvalues. u_j is called *(essentially) non-degenerate* if all its (essential) stagnation points are non-degenerate. Finally, we call a non-degenerate essential stagnation point of u_j such that additionally $u(x) \in \text{relint}(C_x X)^*$ *regular*. Boundary points which are non-regular essential stagnation points are called *irregular boundary points*. We call the set of all irregular boundary points the *irregular boundary Σ^{irr}* . u_j is called *regular* if it has no irregular boundary points. We can define the *k -th type number $\text{Ind}_{j,k}(u)$* of the stratum X_j to be the number of regular stagnation points of u_j of index k , that is

$$\text{Ind}_{j,k}(u) := \#\{x \in \text{Cr}_j(u) : x \text{ has index } k\}. \quad (1.8)$$

To illustrate the preceding definitions we return to our previous example.

Example 1.11. Let X , f and u be as in example 1.9. We have that $u_2 = u$ and thus one sees from equation (1.5) that the origin 0 is the sole stagnation point of u on the stratum X_2 . Since we have that

$$Du(x) = \begin{bmatrix} 2 & \\ & -2 \end{bmatrix}$$

for all $x \in \text{int}(X)$ we see that $Du(0)$ is bijective and thus the origin is a non-degenerate interior stagnation point. Since $Du(0)$ has exactly one negative eigenvalue we see that the origin has index 1. Since an interior stagnation point is also an essential stagnation point we have $\text{Ind}_{2,k} = \delta_{k1}$ where δ denotes the Kronecker delta. For $x \in I \times \{1\} = Y$ we calculate

$$u_1(x) = \pi_1 \circ u(x) = (u - (n \cdot u)n)(x) = 2x_1 e_1$$

and thus we have that $x = e_2$ is the unique stagnation point of u on $I \times \{1\}$. Consider the curve

$$\begin{aligned} \gamma: I &\rightarrow Y \\ t &\mapsto te_1 + e_2 \end{aligned}$$

then $\gamma(0) = e_2$ and we have

$$Du_1(e_1)(\gamma'(0)) = (u_1 \circ \gamma)'(0) = (2te_1)'(0) = 2e_1 = 2\gamma'(0)$$

and thus e_1 is an eigenvector of $Du_1(e_2)$ to the eigenvalue 2. Since e_1 spans the eigenspace $T_{e_2}Y$ it follows that e_2 is a non-degenerate stagnation point of u_1 with index 0. Now since $u(e_2) \in \text{relint}(C_x X)^*$ we have that e_2 is in fact a regular point. Proceeding in this manner for the other segments of the square Σ we obtain that $\text{Ind}_{1,k} = 2\delta_{0k}$. If we now consider the point $x = [1 \ 1]^\top$ then we have that $u_0(x) = 0$ and thus x is a stagnation point. Now the derivative $Du_0 = 0 \in T_x T^*X_0 = 0$ is bijective and thus we have that x has index 0. Since however $u(x) \notin (C_x X)^*$ we have that x is not an essential stagnation point. Analogous argumentation on the other three corners yields that $\text{Ind}_{0,0} = 0$.

The following characterisation of the irregular boundary will come in handy for showing the density of Morse functions later on:

Proposition 1.12 (Characterisation of the irregular boundary). *The condition that the stagnation point $x \in X_j$ lies in Σ^{irr} is equivalent to that x is stagnation point of u_{j+1} for a stratum $X_j \prec X_{j+1}$.*

We first remark that x being a stagnation point of u_{j+1} makes at first sight no sense since $x \notin X_{j+1}$. We have however that $x \in \partial X_{j+1}$. The concept of tangent space $T_x X_{j+1}$ and the projection π_{j+1} can thus be extended to ∂X_{j+1} by continuity and so we can reasonably speak of evaluating u_{j+1} at the point x .

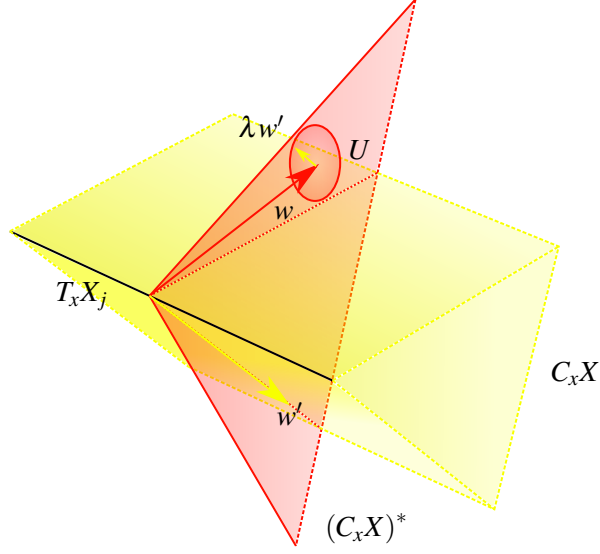


Figure 1.5: An overview of the proof of (+) in equation (1.9).

Proof. We first claim that for some boundary point $x \in \Sigma \cap X_j$ the relations

$$\begin{aligned} \partial(C_x X)^* &:= (C_x X)^* \setminus \text{relint}(C_x X)^* \\ &\stackrel{(+)}{=} \left\{ w \in T_x X \left| \begin{array}{l} w \cdot w' \geq 0 \text{ for all } w' \in C_x X \text{ and} \\ w \cdot w' = 0 \text{ for some } w' \in C_x X \setminus T_x X_j \end{array} \right. \right\} \\ &\stackrel{(*)}{=} \left\{ w \in T_x X \left| \begin{array}{l} w \cdot w' \geq 0 \text{ for all } w' \in C_x X \text{ and} \\ w \cdot w' = 0 \text{ for some } w' \in T_x X_{j+1} \setminus T_x X_j \\ \text{where } X_j \preceq X_{j+1} \end{array} \right. \right\} \end{aligned} \quad (1.9)$$

hold. To see the equality (+) let $w \in \partial(C_x X)^*$ and $w_k \in T_x X \setminus (C_x X)^*$ be a sequence converging to w . Then there exists for each w_k a $w'_k \in C_x X$ such that $w_k \cdot w'_k < 0$. We can assume that $|w'_k| = 1$ and after taking a subsequence that w'_k converge to a $w' \in C_x X$. But then we have by continuity that $w \cdot w' \leq 0$ so the inclusion ' \subseteq ' follows. On the other hand if $w \in \text{relint}(C_x X)^*$ then there exists a relatively open neighbourhood $U \subseteq (C_x X)^*$ of w . Assume that $w \cdot w' = 0$ for some $w' \in C_x X \setminus T_x X_j$. Since we have that $T_x X_j \perp (C_x X)^*$ are perpendicular we can assume that the component of w' projected onto the space $T_x X_j$ vanishes. Then we have for $\lambda < 0$ small enough that $w + \lambda w' \in U$ and it follows that $(w + \lambda w') \cdot w' = \lambda |w'|^2 < 0$, a contradiction. Thus ' \supseteq ' follows.

For (*) we show the inclusion ' \subseteq '. Let $w \in \partial(C_x X)^*$ and $w' \in (T_x X_k \cap C_x X) \setminus T_x X_j$ for some stratum $X_j \prec X_k$ with $w \cdot w' = 0$. We assume that X_k is chosen to be of minimal dimension. Now if $X_j \preceq X_k$ we are finished. Else there exist strata $X_{k-1}^1, X_{k-1}^2 \preceq X_k$ adjacent to X_j . Then there further exist $w'_1 \in (T_x X_{k-1}^1 \cap C_x X) \setminus T_x X_j$ and $w'_2 \in (T_x X_{k-1}^2 \cap C_x X) \setminus T_x X_j$ such that $w' = w'_1 + w'_2$. But then it follows from

$$0 = w \cdot w' = \underbrace{w \cdot w'_1}_{\geq 0} + \underbrace{w \cdot w'_2}_{\geq 0}$$

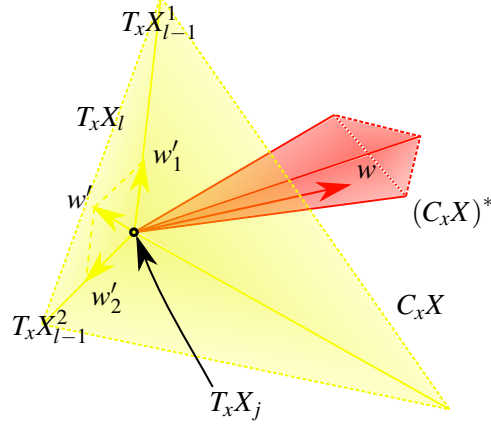


Figure 1.6: An overview of the proof of (*) in equation (1.9).

that also $0 = w \cdot w_1'$ which contradicts the choice of X_k having minimal dimension. Hence the inclusion ' \subseteq ' follows.

Now let x be an irregular stagnation point of u_j then $u(x) \in \partial(C_x X)^*$. Hence there exists a $w' \in T_x X_{j+1} \setminus T_x X_j$ such that $u(x) \cdot w' = 0$. Additionally we have that $u(x) \cdot w = 0$ for all $w \in T_x X_j$ since x is stagnation point of u_j . Since we have that $\text{Span}(w') + T_x X_j = T_x X_{j+1}$ by dimension reasons it then follows that $u(x) \cdot w = 0$ for all $w \in T_x X_{j+1}$ which means that $u_{j+1}(x) = 0$.

Conversely assume that x is stagnation point for some stratum X_{j+1} . Then we have that $u(x) \cdot w = 0$ for all $w \in T_x X_{j+1}$. Since $\text{Span}(w') + T_x X_j = T_x X_{j+1}$ for some $w' \in T_x X_{j+1} \setminus T_x X_j$ it then follows from equation (1.9) that $u(x) \in \partial(C_x X)^*$ and thus x is an irregular stagnation point. \square

The following definition of type numbers is inspired by [26, Definition 10.3]:

Definition 1.13 (Morse functions, [26, Definition 10.3]). We call u *Morse* if for all $j \in \mathcal{J}$ we have that u_j is regular. If both u and $-u$ are Morse we call u *strongly Morse*. For a Morse function u we define the *interior type numbers* M_k to be the number of essential interior stagnation points of u of index k , that is

$$M_k := \sum_{\substack{j \in \mathcal{J} \text{ s.t.} \\ n(j)=d}} \text{Ind}_{j,k}(u) = \# \left\{ x \in \bigcup_{\substack{j \in \mathcal{J} \text{ s.t.} \\ n(j)=d}} \text{Cr}_j(u) : x \text{ has index } k \right\}. \quad (1.10)$$

The total number M of interior stagnation points of u is then given by

$$M := \sum_k M_k. \quad (1.11)$$

Analogously we define the *k-th boundary type numbers* to be the number of essential boundary stagnation points of u of index k , that is

$$\mu_k := \sum_{\substack{j \in \mathcal{J} \text{ s.t.} \\ n(j)<d}} \text{Ind}_{j,k}(u) \quad (1.12)$$

1 Introduction

We further write v_k for the k -th boundary type number of $-u$. We define the *type number* to be the number of essential stagnation points of u of index k , that is

$$\text{Ind}_k(u) := \sum_{j \in \mathcal{J}} \text{Ind}_{j,k}(u) = M_k + \mu_k. \quad (1.13)$$

We return to our example:

Example 1.14. Let X , f and u be as in example 1.9. By the calculations of the previous example 1.11 we have that u is Morse and we can calculate the interior type numbers

$$M_k = \text{Ind}_{2,k} = \delta_{1k}$$

and the boundary type numbers

$$\mu_k = \text{Ind}_{0,k}(u) + \text{Ind}_{1,k}(u) = 2\delta_{0k}$$

This then yields the type numbers

$$\text{Ind}_k(u) = M_k + \mu_k = \delta_{1k} + 2\delta_{0k}.$$

The finiteness of the number of critical points for Morse functions is a known fact which is mentioned for example in [25]. For completeness we give the following proposition:

Proposition 1.15. *The number of non-degenerate stagnation points of u_j on X_j is finite.*

Proof. Let $x \in X_j$ be a non-degenerate stagnation point of u_j . Since $Du_j(x)$ is invertible there exists by the inverse function theorem an open neighbourhood $U_x \subseteq X_j$ of x on which u_j is bijective. Hence x is the only stagnation point in U_x . Let C denote the set of all non-degenerate stagnation points of u_j . Then the sets U_x for $x \in C$ together with

$$U_C = \mathbb{R}^d \setminus \overline{C} \quad (1.14)$$

form an open cover of \overline{X}_j . But \overline{X}_j is compact and thus there exists a finite subcover. Since we have for every stagnation point $x \in C$ that $x \notin U_y$ for all other $y \in C \setminus \{x\}$ and $x \notin U_C$ we must have that U_x is contained in the finite subcover. Thus it follows that $\#C < \infty$ is finite. \square

As a consequence we obtain the following observation:

Corollary 1.16. *For a Morse vector field $u: X \rightarrow \mathbb{R}^d$ the type numbers M_0, \dots, M_d and the boundary type numbers μ_0, \dots, μ_{d-1} are finite.*

The previous definitions translate naturally to f . That is, we call f Morse, non-degenerate, et cetera if $u = \nabla f$ is Morse, non-degenerate, et cetera. Similarly we call x a *critical point* of f if it is a stagnation point of u . Note that most authors refer to regular and essential stagnation points as simply non-degenerate stagnation points and that this naming was introduced simply to distinguish between these different concepts.

Density of Morse functions

In the following section we argue that u and f being Morse is not a great restriction. Given u we define the modification

$$u^\varepsilon := u + \varepsilon \quad (1.15)$$

for some $\varepsilon \in \mathbb{R}^d$. We would like to show that the set E of ε for which u^ε is Morse is residual in \mathbb{R}^d . Recall that a *residual* set is a set whose complement is *meagre*, that is whose complement is the countable union of nowhere dense subsets. Since residual sets are dense in a Baire space by the Baire category theorem we can use u^ε to approximate a degenerate u . Our approach is to use Thom's theorem which is inspired by the approach in [15, Chapter 6].

Definition 1.17 (Transversality, [15, §3.2] and [1]). Let X be a manifold with corners and Y a manifold without boundary. We call a function $g: X \rightarrow Y$ *transverse* to a submanifold $A \subseteq Y$ with corners if for all points in the preimage $x \in g^{-1}(A)$ we have that

$$Dg|_x(C_x X) + C_{g(x)} A = T_{g(x)} Y. \quad (1.16)$$

In the remainder of this section we will deal with manifolds without boundaries and then condition (1.16) reduces to

$$\text{Image}(Dg_x) + T_{g(x)} A = T_{g(x)} Y.$$

As an application of this definition we make the following observation:

Proposition 1.18 (Transversal characterisation of non-degeneracy). *Let $u_j: X_j \rightarrow T^*X_j$ be a differentiable vector field. Then u_j is non-degenerate iff u_j is transverse to the zero section A_j of the cotangent space T^*X_j .*

Proof. First note that we have that $x \in u_j^{-1}(A)$ iff $u_j(x) = 0$ and thus $u_j^{-1}(A) = C$ is the set of stagnation points. Unravelling the definition of transversality we get that u_j is transverse to the zero section iff for all $x \in C = u_j^{-1}(A)$ we have that

$$\text{Image}(Du_j(x)) + T_{u_j(x)} A = T_{u_j(x)} TX. \quad (1.17)$$

As A is the zero section we have $T_{u_j(x)} A = 0$ and equation (1.17) is equivalent to stating that Du_j is of full rank at x . But Du_j being of full rank at all stagnation points is equivalent to u_j being non-degenerate. \square

The alternative characterisation of non-degeneracy given in proposition 1.18 is sometimes used as a definition of non-degeneracy. We can now state a weakened version of the Thom's transversality theorem which is proven in [15, §3 Theorem 2.7]:

Theorem 1.19 (Parametric transversality theorem, [15, §3 Theorem 2.7]). *Let \mathcal{E}, Y_1, Y_2 be C^r -manifolds (without boundary) and $A \subseteq Y_2$ a C^r submanifold such that*

$$r > \dim Y_1 - \dim Y_2 + \dim A.$$

1 Introduction

Let further $F: \mathcal{E} \rightarrow C^r(Y_1, Y_2)$ be such that the evaluation map

$$\begin{aligned} F^{ev}: \mathcal{E} \times Y_1 &\rightarrow Y_2 \\ (\varepsilon, x) &\mapsto F_\varepsilon(x) \end{aligned}$$

is C^r and transverse to A . Then the set

$$E = \{\varepsilon \in \mathcal{E} : F_\varepsilon \text{ is transverse to } A\}$$

is residual in \mathcal{E} .

From this we obtain a generalisation of the results in [25, §2] which will prove useful later:

Corollary 1.20 (Density of boundary generic functions). *Let $u: X \rightarrow T^*X$ be a harmonic vector field on X and let X_j be a stratification of X . Assume that u has no irregular stagnation points. Then there exists a $\delta > 0$ and a residual (and thus dense) set $E \subseteq B_\delta \subseteq \mathbb{R}^d$ such that for every $\varepsilon \in E$ the following statements hold:*

1. $u_j^\varepsilon \rightarrow u_j$ converge uniformly on all strata X_j as $\varepsilon \rightarrow 0$.
2. If $x_\varepsilon \rightarrow x$ is a convergent sequence of stagnation points of u_j^ε as $\varepsilon \rightarrow 0$ then x is a stagnation point of u_j .
3. u^ε is strongly Morse.
4. Additionally we can find for every $\eta > 0$ a $\delta > 0$ such that all stagnation points of u^ε are contained in an η -neighbourhood of the set of stagnation points of u .
5. the property of being entrant or emergent of stagnation points of u^ε is preserved, that is a stagnation point x^ε of u^ε lies in $\Sigma^\pm(u^\varepsilon)$ iff it lies in $\Sigma^\pm(u)$.
6. If u_j is non-degenerate on the stratum X_j we have for all k that

$$\text{Ind}_{X_j, k}(u^\varepsilon) = \text{Ind}_{X_j, k}(u) \quad \text{and} \quad \text{Ind}_{X_j, k}(-u^\varepsilon) = \text{Ind}_{X_j, k}(-u).$$

Proof. Part 1. Follows from compactness of $\overline{X_j} \subseteq X$ and the continuity of π_j .

Part 2. Let $x_\varepsilon \rightarrow x$ be a convergent sequence of stagnation points on the stratum X_j . By part 1 $u_j^\varepsilon \rightarrow u_j$ as $\varepsilon \rightarrow 0$ uniformly which implies

$$0 = \lim_{\varepsilon} u_j^\varepsilon(x_\varepsilon) = u_j(x) \tag{1.18}$$

and thus x is a stagnation point of u_j .

Part 3. The following is essentially an adaptation of a proof given in [25, §2]. We first show that we can choose a $\delta > 0$ such that for all $\varepsilon \in B_\delta \subseteq \mathbb{R}^d$ the function u^ε has no irregular stagnation points. Assume not. Then there exists a sequence $\varepsilon_k \rightarrow 0$ and irregular stagnation points $x_k \in \Sigma^{\text{irr}}(u^{\varepsilon_k})$ of u^{ε_k} . By compactness of X we can assume that $x_k \rightarrow x$ for some $x \in X$ after taking a sub-sequence. After taking a further sub-sequence we can also assume that all x_k lie in a stratum X_j . The condition that the $x_k \in \Sigma^{\text{irr}}(u^{\varepsilon_k})$ are stagnation points means that after

taking a further sub-sequence there exists a stratum X_{j-1} such that x_k is also stagnation point of this stratum by proposition 1.12. But then $x \in \bar{X}_j$ is also a stagnation point of X_{j-1} by part 2. Analogously x is also stagnation point of X_j . Thus $x \in \Sigma^{\text{irr}}$ is an irregular stagnation point. A contradiction.

The next part of the proof is inspired by the use of transversality in [15, §6 Theorem 1.2] to show a similar statement. Set $r = 2$, $\mathcal{E} = B_\delta$ and $Y_2 = T^*X_j$ in the previous theorem. We initially set $Y_1 = X_j = \text{int}(X)$. We would like to apply the parametric transversality theorem to the function

$$\begin{aligned} F: \mathcal{E} &\rightarrow C^\infty(X_j, T^*X_j) \\ \varepsilon &\mapsto u^\varepsilon \end{aligned}$$

and note that F^{ev} is sufficiently smooth. We need to show that F^{ev} is transverse to the zero section $A \subseteq T^*X_j$. Then the parametric transversality theorem yields a residual $E_j \subseteq \mathcal{E}$ on which $F_\varepsilon = u^\varepsilon$ is transverse to A . For this note that for all $(\varepsilon, x) \in F^{-1}(A)$ we have

$$\text{Image}\left(DF_{(\varepsilon, x)}^{\text{ev}}\right) = T_x T^*X_j \quad (1.19)$$

since

$$DF_{(\varepsilon, x)}^{\text{ev}} = [\text{Id}_{d \times d} \mid Du_x]$$

is surjective. Proposition 1.18 now implies that u^ε is non-degenerate on X_j for $\varepsilon \in E_j$.

Analogously we set $Y_1 = X_j$ to be an arbitrary strata in the previous proof and replace u^ε with the projection u_j^ε . To show that equation (1.19) holds we resort to the fact that

$$DF_{(\varepsilon, x)}^{\text{ev}} = D(u_j^\varepsilon(x))_{(\varepsilon, x)} = D\pi_j \circ (Du^\varepsilon(x))_{(\varepsilon, x)}$$

is surjective as a concatenation of surjective functions. Thus there also exists a residual set $E_j \subseteq \mathcal{E}$ on which u_j^ε is non-degenerate on X_j .

Now the intersection

$$E = \bigcap_j E_j \subseteq \mathcal{E} = B_\delta$$

is residual and for every $\varepsilon \in E$ the function u^ε fulfils condition 3.

Part 4. Let C_η denote the open η -neighbourhood of the set of stagnation points of u . Since u has no irregular stagnation points we have for any stratum X_j that $u_j \neq 0$ on the compact set $\bar{X}_j \setminus C_\eta$ which implies that we can choose $\delta > 0$ so small that $|u_j| > 2\delta$ on $\bar{X}_j \setminus C_\eta$ for all strata X_j . For any $\varepsilon \in B_\delta$ it then follows that u^ε has no stagnation points on the set $\bar{X}_j \setminus C_\eta$ which yields the claim.

Part 5. Now consider a stratum X_j and the continuous mapping

$$\begin{aligned} \Phi: X_j &\rightarrow \mathbb{R}_{\geq 0} \\ x &\mapsto \text{dist}(u(x), \partial C_x X) \end{aligned}$$

1 Introduction

on X_j . Φ is positive on the set of stagnation points C of u_j on X_j and thus we can choose $\eta > 0$ such that Φ is also positive in the neighbourhood $C_{2\eta}$. Choose $\delta > 0$ smaller than in part 4. Now the mapping Φ attains a positive minimum on the compact set $\overline{C_\eta}$. We can assume that $\delta > 0$ is less than this minimum. The choice of δ in this way ensures that emergent stagnation points of u_j are also emergent stagnation points of u_j^ε on X_j . Analogous argumentation with $-u$ then ensures that entrant stagnation points of u_j are also entrant stagnation points of u_j^ε on X_j . Since there are finitely many strata X_j we can choose $\delta > 0$ such that part 5 follows.

Part 6. Pick $\delta > 0$ as in part 5 and such that If x is a non-degenerate stagnation point of u on the stratum X_j it follows from the inverse function theorem that there exists for sufficiently small δ a neighbourhood around x on which there is a one-to-one correspondence between the stagnation points of u and u^ε . Since there are by proposition 1.15 at most finitely many non-degenerate stagnation points of u we can choose δ to be minimal over all these stagnation points. The equality of the indexes then follows from $Du^\varepsilon = Du$. \square

2 The Morse inequalities

The aim of this chapter is to state and motivate the Morse inequalities for manifolds with corners. For this we first introduce the Betti numbers of the domain X , then we state the Morse inequalities and finally we give a motivation as to why these inequalities hold. After that we state the Morse inequalities in the special case of $d \in \{2, 3\}$ dimensions for a harmonic Morse function f .

Betti numbers

Let $H_k(X)$ denote the k -th homology group of X with coefficients in the field \mathbb{K} . For an introduction and definition of these we refer the reader to [14, Chapter 2]. We define the k -th Betti number as the dimension

$$b_k = b_k(X) := \dim_{\mathbb{K}} H_k(X). \quad (2.1)$$

We proceed to give examples for Betti numbers of selected connected domains in \mathbb{R}^d .

Example 2.1 (In flatland). In $d = 2$ dimensions the 0-th Betti number counts the number of connected components of X and the first Betti number counts the number of holes of this domain. All other Betti numbers vanish in \mathbb{R}^2 . More concretely, we give the Betti numbers for selected domains in table 2.1.

Example 2.2 (In spaceland). In $d = 3$ dimensions the 0-th Betti number counts the number of connected components of X , the first Betti number counts the number of holes and the second Betti number counts the number of bubbles of the domain. All other Betti numbers vanish. The Betti numbers for selected domains can be seen in table 2.2.

Now we can define the *Euler characteristic* to be

$$\chi(X) = \sum_{k=0}^d (-1)^k b_k(X)$$

the alternating sum of the Betti numbers.

The Morse inequalities

We state the Morse inequalities.

2 The Morse inequalities

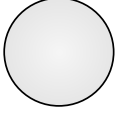
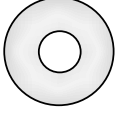
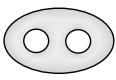
Domain	Picture	b_0	b_1	$b_k, k \geq 2$
Disk D		1	0	0
Annulus $2D \setminus D$		1	1	0
Two holed button		1	2	0

Table 2.1: Betti numbers for selected domains in \mathbb{R}^2 .

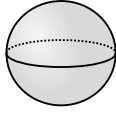

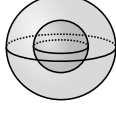
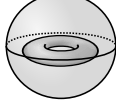
Domain	Picture	b_0	b_1	b_2	$b_k, k \geq 3$
Ball B		1	0	0	0
Solid torus $S^1 \times D$		1	1	0	0
Ball with bubble $2B \setminus B$		1	0	1	0
Ball with bubble in shape of torus		1	1	1	0

Table 2.2: Betti numbers for selected domains in \mathbb{R}^3 .

Theorem 2.3 (Morse inequalities, [1, Theorem 2.4]). *Let X be a manifold with corners and $f: X \rightarrow \mathbb{R}$ be smooth and Morse. Then we have for $l \in \{0, \dots, d\}$ the inequalities*

$$\sum_{k=0}^l (-1)^{k+l} \text{Ind}_k(f) \geq \sum_{k=0}^l (-1)^{k+l} b_k(X). \quad (2.2)$$

For $l = d$ we in fact have equality

$$\sum_{k=0}^d (-1)^k \text{Ind}_k(f) = \chi(X) \quad (2.3)$$

where $\chi(X)$ denotes the Euler characteristic.

The definition of regular critical points of f and their index given in definition 1.10 coincides with the definition of a critical point and its co-index of $-f$ given in [1]. Theorem 2.3 then follows from [1, Theorem 2.4]. Nonetheless we will give an idea of the proof.

Define for $a \in \mathbb{R}$ the manifold $X^a := \{x \in X : f(x) \leq a\}$. The main idea in the proof of the Morse inequalities is to inspect how the topology of the manifold X^a changes as we vary a . This was the idea in Morse's original proof of these inequalities for manifolds without boundary in [24]. Later proofs of the Morse inequalities for manifolds without boundary using this approach added more terminology from algebraic topology and differential geometry. Proofs of the Morse inequalities can be found in [22, §5] for manifolds without boundary and in [26, Theorem 10.2'] for manifolds with C^1 boundary. There also exists proofs using dynamical system techniques which can be found for instance in [29]. We require however the Morse inequalities on manifolds with corners. This is a special case of stratified Morse theory by Goresky and McPherson which is outlined for instance in [6, §5.5]. We will try to avoid the fancy tools that are used in stratified Morse theory and instead resort to [1] and [11] where the Morse inequalities are shown for manifolds with corners. In the following we will outline the main ideas of the proof to convince the reader as to why equation (2.3) is reasonable.

We first cite a result from [1].

Proposition 2.4 ([1, Theorem 2.1]). *Let $t_0, t_1 \in \mathbb{R}$ and $F: \mathbb{R} \times X \rightarrow Y$ be a smooth map such that for each $t_0 \leq t \leq t_1$ the function $f_t = F(t, \cdot)$ is transverse to a submanifold with corners $W \subseteq Y$. Then the sets $f_{t_0}^{-1}(W) \simeq f_{t_1}^{-1}(W)$ are homotopic.*

Idea of proof. See [1, Theorem 2.1]. The proof involves the construction of a flow P defined on a neighbourhood of X for which $P_t(f_{t_0}^{-1}(W)) \subseteq f_t^{-1}(W)$ for all $t_0 \leq t \leq t_1$. \square

With this result one can show the following:

Lemma 2.5 (Interval without critical value, [11, Theorem 7] and [1, p.7]). *Assume that the interval $[a, b]$ contains no critical value of f . Then $X^a \simeq X^b$ are homotopic.*

2 The Morse inequalities

Proof. One sets $f_t = f - t$ in the previous lemma and $W = \mathbb{R}_{\leq 0}$. Note that $X^c = f_c^{-1}(W)$ for all $c \in \mathbb{R}$. We have for every $a \leq t \leq b$ and $x \in f_t^{-1}(W)$ that

$$Df_t|_x(C_x X) + C_{f(x)} W = C_{f(x)} \mathbb{R} = \mathbb{R}$$

since $C_{f(x)} W = \mathbb{R}$ for $f(x) < t$ and

$$Df_t|_x(C_x X) = Df|_x(C_x X) = \mathbb{R}$$

for $f(x) = t$ since f has no critical values on the interval $[a, b]$. Thus f_t is transverse to W for each $a \leq t \leq b$ and the result follows. \square

A similar result is given in [11, Theorem 7]. The proof in [11, Theorem 7] also involves the construction of a flow on the manifold X . It requires however an additional technical property, named property (3), which is why we gave the proof by [1] for this lemma.

We state Morse's lemma according to [11, Lemma 5].

Proposition 2.6 (Morse's lemma, [11, Lemma 5]). *Let $f: X \rightarrow \mathbb{R}$ be C^2 and x be an essential regular non-degenerate critical point of index k on the stratum X_j of dimension n . Then there exists a local chart $\varphi: H_{d-n}^d \supseteq V \rightarrow U$ such that*

$$f \circ \varphi^{-1}(y) = f(x) - \sum_{j=1}^k y_j^2 + \sum_{j=k+1}^n y_j^2 + \sum_{j=n+1}^d y_j. \quad (2.4)$$

Idea of proof. The case that $n = d$ is the classical version of the Morse lemma and can be found for instance in [15, §6, Lemma 1.1]. Note that the definition of an essential critical point in [11] fulfilling property (3) also encompasses our definition of a non-degenerate regular essential critical point. Here the regularity condition ensures that property (3) in [11] is fulfilled. Hence this statement follows from [11, Lemma 5]. The idea of the proof involves first applying the Morse lemma on the stratum of the critical point. Then this coordinate chart is extended with Taylor in a suitable manner to a full coordinate chart on X such that equation (2.4) holds. \square

Using the Morse lemma one can then show the following result:

Lemma 2.7 (Interval with critical value, [11, Theorem 8] and [1, Theorem 2.2]). *If the interval $[a, b]$ contains one critical value $a < c < b$ with corresponding non-degenerate essential critical point x of index k then X^b is homotopic to X^a by attaching the k -cell D^k .*

Idea of proof. This is proven in [11, Theorem 8]. Here we note that we do not require what [11] calls property (3) since this was only used to show the analogue of lemma 2.5 and in the formulation of the Morse lemma. The proof is in structure very similar to [22]. One first uses the Morse lemma to choose a suitable coordinate system in a neighbourhood of the critical point. Then one chooses $\varepsilon > 0$ so small such that $B_{2\varepsilon} \subseteq V$. The proof then proceeds in three steps. First one defines a region H as in figure 2.1. Then one shows that $X^{c-\varepsilon}$ with H attached is homotopic

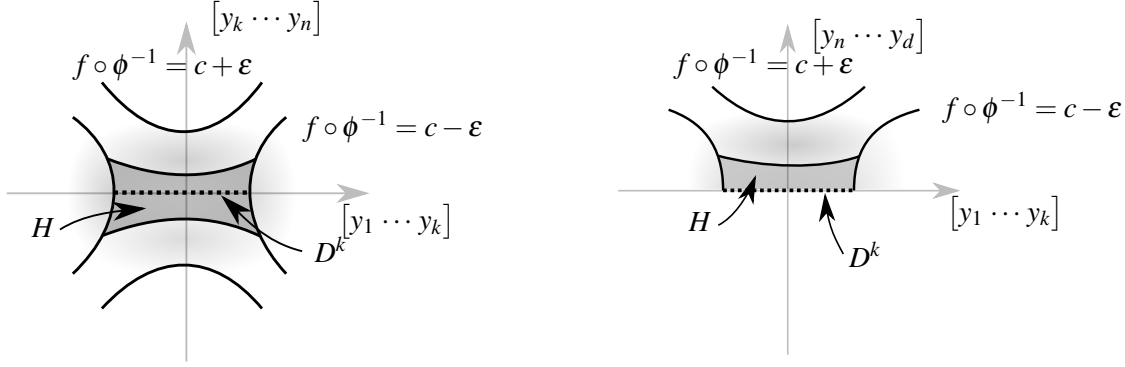


Figure 2.1

to $X^{c+\varepsilon}$. Finally one shows that $X^{c-\varepsilon}$ with the k -cell D^k attached is homotopic to $X^{c-\varepsilon}$ with H attached. The claim then follows from

$$X^a \cup D^k \simeq X^{c-\varepsilon} \cup D^k \simeq X^{c-\varepsilon} \cup H \simeq X^{c+\varepsilon} \simeq X^b$$

where we also used the result of lemma 2.5. □

In the original proof [24] of the Morse inequalities Morse inspected in the analogues to lemmas 2.5 and 2.7 directly how the Betti numbers of the manifold changed from X^a to X^b . The modern proofs however lean on the language of algebraic topology which is why we now need to argue how lemmas 2.5 and 2.7 imply the Morse inequalities. This final part of the proof is given in all details in [22, §I.5]. Since we only use the equality in equation (2.3) we shall outline its proof.

Denote the k -th relative homology group by $H_k(X, A)$ for spaces $A \subseteq X$. Once again we refer the reader to [14, Chapter 2] for details regarding their definition. We require a result from algebraic topology proven in [14, Corollary 2.24]:

Proposition 2.8 (Corollary of the excision theorem, [14, Corollary 2.24]). *Let $X = A \cup B$ be a CW-complex. Then we have for every k that $H_k(X, A) \cong H_k(B, A \cap B)$ are isomorphic.*

Now define the Euler characteristic for relative homology group by

$$\chi(X, Y) := \sum_k (-1)^k \dim_{\mathbb{K}} H_k(X, Y). \quad (2.5)$$

It is shown in [22, §5] that this is additive, in the sense that given suitable $X \supseteq Y \supseteq Z$ we have that

$$\chi(X, Z) = \chi(X, Y) + \chi(Y, Z) \quad (2.6)$$

Let $a_0 < \dots < a_L$ be such that $[a_l, a_{l+1}]$ contains precisely one critical value in its interior with index k_l and such that $X = X^{a_L}$ and $X^{a_0} = \emptyset$. It now follows from lemma 2.7 and proposition 2.8

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that

$$\begin{aligned} H_k(X^{a_{l+1}}, X^{a_l}) &= H_k(X^{a_l} \cup D^{k_l}, X^{a_l}) \\ &= H_k(D^{k_l}, S^{k_l}) \\ &= \begin{cases} \mathbb{K} & \text{if } k = k_l, \\ 0 & \text{else} \end{cases} \end{aligned}$$

so

$$\chi(X^{a_{l+1}}, X^{a_l}) = (-1)^{k_l}. \quad (2.7)$$

Hence we obtain by inductively applying equation (2.6) and then (2.7) that

$$\chi(X) = \chi(X^{a_L}, X^{a_0}) = \sum_l \chi(X^{a_{l+1}}, X^{a_l}) = \sum_k (-1)^k \text{Ind}_k(f)$$

so equation (2.3) of the Morse inequalities follows for the case that no two critical points lie in the same level set. In case there are multiple critical points on the same level set the notation becomes a little more involved but the idea of the proof is the same. The proof of the inequalities (2.2) involves defining the Betti numbers for relative homology groups and then making a similar argumentation as above with these Betti numbers instead of the Euler characteristic. For details we refer the reader to [22, §5].

In the final part of this chapter we inspect the Morse inequalities in the special case that f is harmonic. If we assume that f is harmonic the maximum principle implies that $M_0 = 0 = M_d$. If we additionally assume that we have dimensions $d = 2$ we obtain from the Morse inequalities (theorem 2.3) a result from [26, Corollary 10.1].

Corollary 2.9 (Morse inequalities for harmonic f in \mathbb{R}^2 , [26, Corollary 10.1]). *Let $X \subseteq \mathbb{R}^2$ be a manifold with corners and $f: X \rightarrow \mathbb{R}$ be harmonic and Morse. Then we have*

$$\begin{aligned} \mu_0 &\geq b_0 \\ M + \mu_1 - \mu_0 &= -\chi(X). \end{aligned}$$

In dimensions $d = 3$ we obtain from theorem 2.3 a result from [26, Corollary 10.2].

Corollary 2.10 (Morse inequalities for harmonic f in \mathbb{R}^3 , [26, Corollary 10.2]). *Let $X \subseteq \mathbb{R}^3$ be a manifold with corners and $f: X \rightarrow \mathbb{R}$ be harmonic and Morse. Then we have*

$$\begin{aligned} \mu_0 &\geq b_0 \\ M_1 + \mu_1 - \mu_0 &\geq b_1 - b_0 \\ M_2 + \mu_2 - M_1 - \mu_1 + \mu_0 &= \chi(X). \end{aligned}$$

Perhaps give a classical example of a Morse function to determine the Betti numbers.

3 Connected entrant boundaries in \mathbb{R}^2

We will start this section by giving an essentially negative answer to question 1.2 in $d = 2$ dimensions. Thus it is not possible to have a harmonic function with interior critical point on a simply connected planar domain with connected entrant boundary. The proof of this will involve Morse theory on manifolds with corners which was introduced in the previous chapter. We shall then state a result from [2] which more generally relates the number of entrant components with the number of critical points in the plane using tools from complex analysis. After that we give examples showing that dropping the condition of simply connectedness on the domain yields a harmonic function with interior stagnation point. We will also consider the analogous problem in $d = 4$ dimensions and show that there exists a function and domain with the desired properties.

A negative result for simply connected domains

We now give a result which is essentially a negative answer to question 1.2. It was possible to prove this statement using level sets of critical points or using invariant manifolds. The following proof involves Morse theory since the techniques of the proof generalise to the three dimensional case.

Proposition 3.1 (Negative answer to question 1.2 in $d = 2$ dimensions). *Let $d = 2$ and X be a simply connected manifold with corners and let $f: X \rightarrow \mathbb{R}$ have no irregular critical points. Assume further that Σ^- contains at least two points and is simply connected. Then f has no non-degenerate interior critical point.*

Proof. Let $\gamma = \{x_1, x_2\} = \partial\Sigma^-$. Then we can cut the domain along a curve Γ such that the endpoints $\gamma = \partial\Gamma$ of the cut coincide with x_1 and x_2 , that is $\partial\Gamma = \{x_1, x_2\}$. Now we obtain two new domains X^+ and X^- such that $\partial X^+ \cap \Sigma^- \subseteq \gamma$ and $\partial X^- \cap \Sigma^+ \subseteq \gamma$. We can assume that Γ is a smooth manifold and corresponds to the stratum X_{Γ^+} for X^+ and X_{Γ^-} for X^- . Analogously γ corresponds to strata X_{γ^\pm} on X^\pm . Locally around the corner point x_1 we have a situation depicted as in figure 3.1. We assume that we chose Γ in such a way that it forms an acute angle with $u = \nabla f$ at the boundary points γ . For the following argumentation we require that u is strongly Morse on both X^+ and X^- , so assume for a moment that this is the case. Since each point of γ is an essential critical point for either f or $-f$ on precisely one of the domains X^+ or X^- we have the relation

$$\text{Ind}_{\gamma^+,0}(f) + \text{Ind}_{\gamma^+,0}(-f) + \text{Ind}_{\gamma^-,0}(f) + \text{Ind}_{\gamma^-,0}(-f) = 2. \quad (3.1)$$

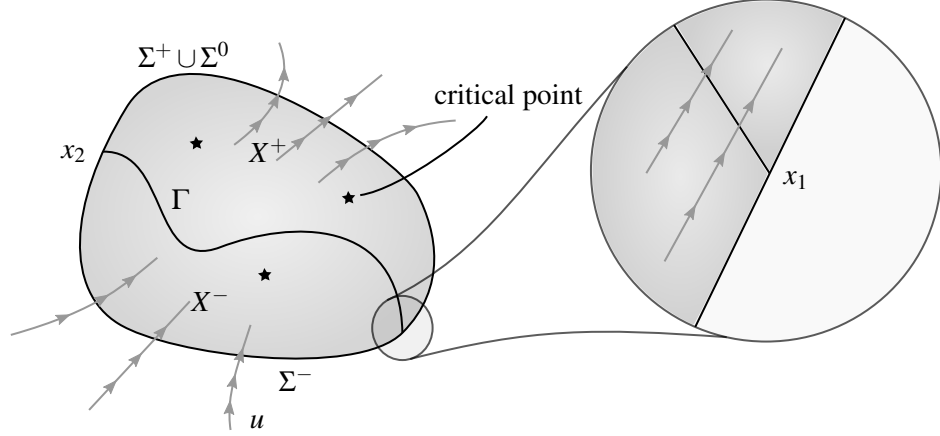


Figure 3.1: The situation at hand.

We now focus our attention on X^+ . Since no essential critical points of f lie on $\Sigma^+ \setminus \gamma$ it follows for the boundary type numbers that

$$\mu_k^+ = \text{Ind}_{\Gamma^+,k}(f) + \text{Ind}_{\gamma^+,k}(f) \quad (3.2)$$

where δ_{ij} denotes the Kronecker delta. Analogously we have on X^- that

$$v_k^- = \text{Ind}_{\Gamma^-,k}(-f) + \text{Ind}_{\gamma^-,k}(-f). \quad (3.3)$$

In addition we have on Γ that the emergent critical points of f on X^+ are the entrant critical points of $-f$ on X^- , that is

$$\text{Ind}_{\Gamma^+,0}(f) = \text{Ind}_{\Gamma^-,1}(-f) \quad \text{and} \quad \text{Ind}_{\Gamma^+,1}(f) = \text{Ind}_{\Gamma^-,0}(-f). \quad (3.4)$$

Using equations (3.2), (3.3) and (3.4) we obtain

$$\mu_0^+ - \text{Ind}_{\gamma^+,0}(f) = v_1^- \quad \text{and} \quad \mu_1^+ = v_0^- - \text{Ind}_{\gamma^-,0}(-f). \quad (3.5)$$

Consider the Morse inequality for f on X^+

$$M^+ + \mu_1^+ - \mu_0^+ = -\chi(X^+) = -\chi(X) \quad (3.6)$$

and the Morse inequality for $-f$ on X^-

$$M^- + v_1^- - v_0^- = -\chi(X^-) = -\chi(X). \quad (3.7)$$

We now add equations (3.6) and (3.7) and insert relations (3.5) to obtain

$$M^- + M^+ - \text{Ind}_{\gamma^+,0}(f) - \text{Ind}_{\gamma^-,0}(-f) = -2\chi(X) = -2.$$

Since $\text{Ind}_{\gamma^+,0}(f) + \text{Ind}_{\gamma^-,0}(-f) \leq 2$ by equation (3.1) and $M^\pm \geq 0$ we must in fact have $M^\pm = 0$ from which the claim follows.

The claim remains to be shown in the case that f is not strongly Morse on X^+ and X^- . In this case let $E^+, E^- \subseteq B_\delta$ be as in corollary 1.20 applied separately to the domains X^+ and X^- . Since E^\pm are residual in B_δ we can in particular pick a $\varepsilon \in E^+ \cap E^-$ by the Baire category theorem. It follows from the slanted angles at which Γ approaches γ that if the points x_1, x_2 are essential critical points of f that they then are in fact regular. Hence we obtain that

$$\text{Ind}_{\gamma^+,k}(f^\varepsilon) = \text{Ind}_{\gamma^+,k}(f) \quad \text{and} \quad \text{Ind}_{\gamma^-,k}(-f^\varepsilon) = \text{Ind}_{\gamma^-,k}(-f).$$

By the same corollary u^ε has no essential stagnation points on $\Sigma^+(u)$ and $-u$ has no essential stagnation points on $\Sigma^-(u)$. The claim then follows by the calculations above where we replace f with f^ε and then note that $M^\varepsilon = M$. \square

A generalisation of this result

We could also have used tools from complex analysis to show proposition 3.1. In fact, using complex analysis [2] gives a more refined result for which we require the next definition.

Definition 3.2 (Number of entrant / emergent boundary components, [2]). Let J^\pm denote the number of connected components of Σ^\pm which are proper subsets of a component of Σ . Consider a disjoint decomposition of the boundary $\Sigma = \Sigma_{\geq 0} \sqcup \Sigma_{\leq 0}$ such that $\Sigma_{\geq 0} \subseteq \Sigma^{\geq 0}$ and $\Sigma_{\leq 0} \subseteq \Sigma^{\leq 0}$. Let now $J^{\geq 0}$ denote the minimal number of connected components of $\Sigma_{\geq 0}$ which are proper subsets of a component of Σ .

We state a consequence of a result from [2, Theorem 2.1 and 2.2]:

Proposition 3.3 (Special case of [2, Theorem 2.1 and 2.2]). *Let $X \subseteq \mathbb{R}^d$ be a bounded domain with a boundary consisting of simple closed $C^{1,\alpha}$ curves. Let $u: X \rightarrow \mathbb{R}$ be a harmonic vector field, nonzero on each component. Then we have the relation*

$$M \leq -\chi(X) + \frac{J^+ + J^-}{2} \tag{3.8}$$

where M denotes the number of stagnation points of u , counting multiplicities. If in addition we assume that there are no irregular stagnation points then we have

$$M \leq -\chi(X) + J^{\geq 0}. \tag{3.9}$$

For a proof we refer the reader to [2, Theorem 2.1] and [2, Theorem 2.2]. Here one sets $\underline{\alpha} = n$ to be the outer unit normal and $D = \chi(X)$ to be the Euler characteristic.

If we set X to be homeomorphic to the ball, that is $\chi(X) = 1$, and require the entrant boundary to be simply connected, that is $J^\pm = J^{\geq 0} = 1$, we then obtain from proposition 3.3 that $M \leq 0$ and f has no non-degenerate critical point.

The case of holes in the domain

If we set $J^\pm = J^{\geq 0} = 1$ in relations (3.8) or (3.9) we obtain the condition on the number of interior stagnation points

$$M \leq -\chi(X) + 1. \quad (3.10)$$

This indicates that if we allow for holes in the domain X it is possible to have a vector field with simply connected entrant boundary and interior stagnation points. In fact we will give two examples where we have equality in equation (3.10) for the cases $\chi(X) = 0$ and $\chi(X) = -1$. For this define two differential operators in $d = 2$ dimensions by

$$\nabla^\perp f = \text{Curl } f := \begin{bmatrix} -\partial_2 f \\ \partial_1 f \end{bmatrix} \quad (3.11)$$

and

$$\text{curl } u := -\partial_1 u_2 + \partial_2 u_1.$$

The next proposition gives us a recipe to generate harmonic vector fields.

Proposition 3.4. *Let $\psi: \mathbb{R}^2 \supseteq X \rightarrow \mathbb{R}$ be harmonic then $u = \nabla^\perp \psi$ is a harmonic vector field.*

Proof. We have

$$\text{div } u = \text{div } \nabla^\perp \psi = 0$$

and one calculates

$$\text{curl } u = \text{curl } \nabla^\perp \psi = -\Delta \psi = 0$$

from which the claim follows. □

The function ψ is also called a *stream function*. The next example is our first example of a harmonic vector fields in $d = 2$ dimensions with an interior stagnation points for which we have inflow on one simply connected boundary component and outflow on another simply connected boundary component.

Example 3.5 (Flow through tube with hole and stagnation point). Consider the stream function

$$\begin{aligned} \psi: \mathbb{R}^2 \setminus \{-e_1, e_1\} &\rightarrow \mathbb{R} \\ x &\mapsto \Phi_2(x - e_1) + x_1 \end{aligned} \quad (3.12)$$

where

$$\Phi_2 = \log(|\cdot|) \quad (3.13)$$

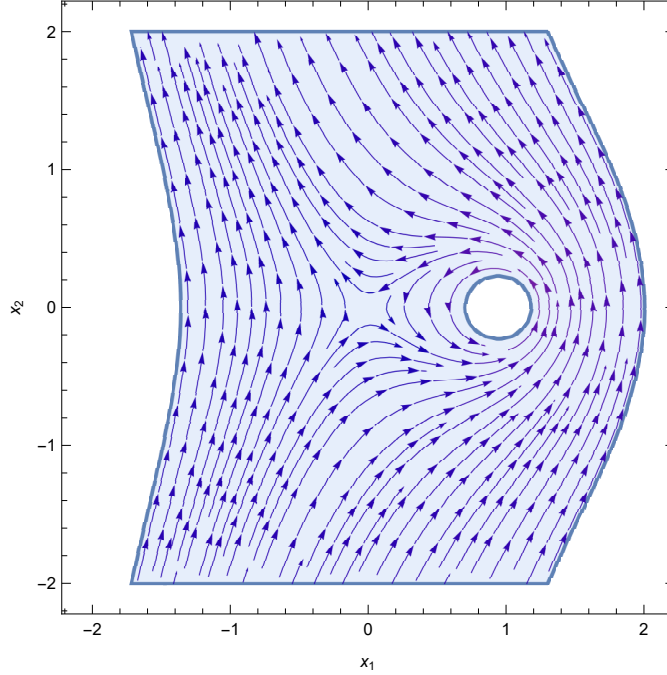


Figure 3.2: A plot of $u = \nabla^\perp \psi$ in the region $\psi^{-1}([-0.5, 2]) \cap (\mathbb{R} \times [-2, 2])$. Here ψ is given by equation (3.12).

is a multiple of the fundamental solution of the Laplace equation on \mathbb{R}^2 and e_i is the i -th unit vector. A plot of the streamlines in figure 3.2 indicates that $u = \nabla^\perp \psi$ fulfils the requirements on the domain

$$X = \psi^{-1}([-0.5, 2]) \cap (\mathbb{R} \times [-2, 2]).$$

Indeed, an elementary calculation reveals that the origin is a stagnation point of u .

Example 3.5 highlights the importance of the requirement in proposition 3.1 that the domain be simply connected. We now give a similar example, this time with two holes in the domain and two interior stagnation points.

Example 3.6 (Flow through tube with two holes and stagnation points). We consider the stream function

$$\begin{aligned} \psi: \mathbb{R}^2 \setminus \{-e_1, e_1\} &\rightarrow \mathbb{R} \\ x &\mapsto \Phi_2(x - e_1) - \Phi_2(x + e_1) + x_1 \end{aligned} \quad (3.14)$$

A plot of the streamlines in figure 3.3 indicates that $u = \nabla^\perp \psi$ on the domain

$$X = \psi^{-1}([-0.7, 0.7]) \cap (\mathbb{R} \times [-2, 2])$$

has the desired properties.

3 Connected entrant boundaries in \mathbb{R}^2

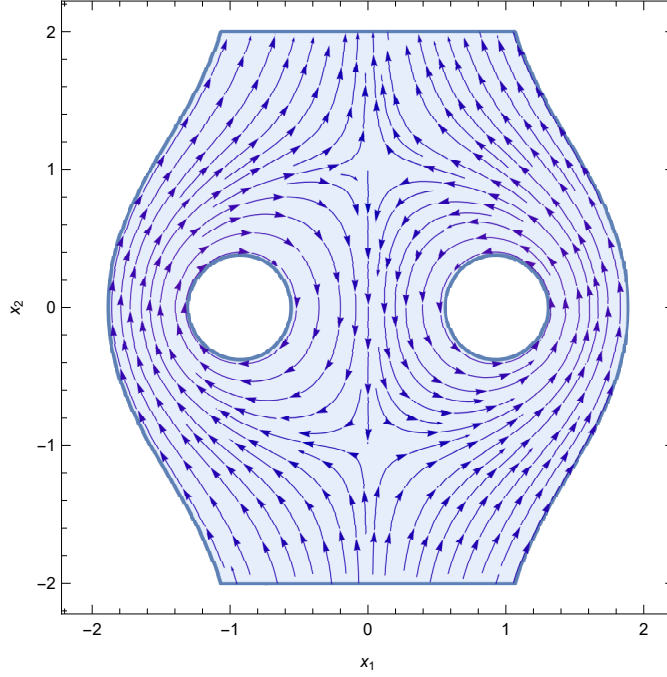


Figure 3.3: A plot of $u = \nabla^\perp \psi$ in the region $\psi^{-1}([-0.7, 0.7]) \cap (\mathbb{R} \times [-2, 2])$. Here ψ is given by equation (3.14).

The case of $d = 4$ dimensions

We ask whether there exists a harmonic vector field on a simply connected domain with connected entrant boundary and with interior stagnation point in a dimension higher than $d = 2$. Indeed, in $d = 4$ dimensions we can readily give an example of such a harmonic vector field.

Example 3.7 (Connected entrant boundary in $d = 4$ dimensions). Consider as domain $X = B_1 \subseteq \mathbb{R}^4$ the unit ball and the harmonic function

$$\begin{aligned} f: X &\rightarrow \mathbb{R} \\ x &\mapsto x_1^2 + x_2^2 - x_3^2 - x_4^2. \end{aligned} \tag{3.15}$$

This has a critical point at the origin. We will show in proposition 3.8 that the entrant boundary Σ^- is in fact connected.

Proposition 3.8 (Simply connected entry boundary in example 3.7). *The harmonic function given by equation (3.15) has simply connected entrant boundary.*

Proof. First observe that the boundary $\Sigma = S^3$ can be away from the equator locally parametrised by the coordinates $\bar{x} = (x_2, x_3, x_4)$ for which we have $|\bar{x}| \leq 1$. By the condition

$$\sum_i x_i^2 = 1 \tag{3.16}$$

on the boundary $\Sigma = S^3$ we have that x_1 is then uniquely determined up to sign. Thus we have have defined parametrisations

$$\begin{aligned} \phi_{\pm}: \mathbb{R}^3 \supseteq B_1 &\rightarrow \Sigma \subseteq \mathbb{R}^4 \\ \bar{x} &\mapsto x = (x_1, \bar{x}) \text{ such that } \pm x_1 \geq 0 \end{aligned} \quad (3.17)$$

with inverses $\psi_{\pm} = (\phi_{\pm})^{-1}$. We now calculate the gradient of f

$$\nabla f = 2 \begin{bmatrix} x_1 & x_2 & -x_3 & -x_4 \end{bmatrix}^{\top}$$

and the outer unit normal to the boundary Σ is given by

$$n = \begin{bmatrix} x_1 & \cdots & x_4 \end{bmatrix}^{\top}.$$

Thus we have $x \in \Sigma^{\pm}$ iff

$$0 < \pm \nabla f \cdot n = \pm 2(x_1^2 + x_2^2 - x_3^2 - x_4^2).$$

Using condition (3.16) we obtain the equivalent condition

$$0 < \pm 1 - 2(x_3^2 + x_4^2)$$

Define the cylinder

$$C = \{\bar{x} \in \mathbb{R}^3 : x_3^2 + x_4^2 < 1/2\} = \mathbb{R} \times B_{1/\sqrt{2}} \subseteq \mathbb{R}^3$$

If we return to our parametrisation (3.17) we see that we have $\bar{x} \in B_1 \cap C$ iff $\phi_{\pm}(\bar{x}) \in \Sigma^+$ and hence

$$B_1 \cap C = \psi_{\pm}(\Sigma^+)$$

and

$$B_1 \setminus C = \psi_{\pm}(\Sigma^-).$$

Since ϕ_+ is a homeomorphism onto the northern hemisphere and ϕ_- a homeomorphism onto the southern hemisphere and the surface S^2 corresponds to the equatorial sphere the claim then follows. The situation is depicted in figure 3.4. \square

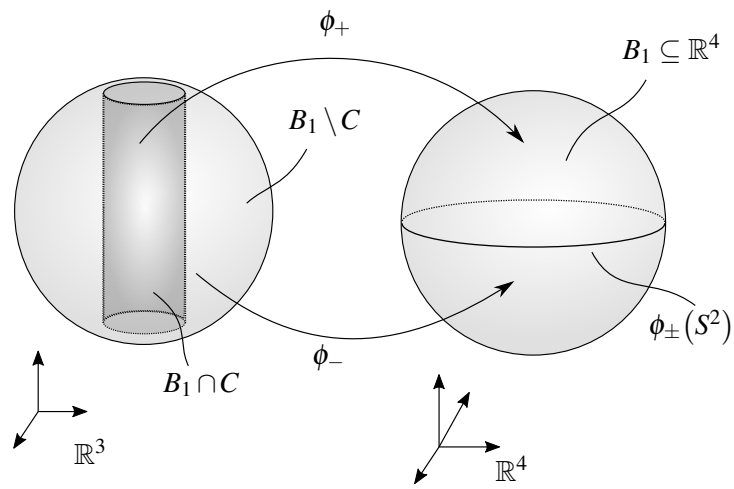


Figure 3.4: Visualisation of the situation in the proof of proposition 3.8.

4 Simply connected entrant boundaries in \mathbb{R}^3

In the following chapter we will discuss question 1.2 in the case of $d = 3$ dimensions. That is, we are looking for a harmonic function with interior stagnation point on a simply connected domain and connected entrant boundary. We will first give a negative answer in the case of a cylinder. After that we will use Morse theory to essentially argue that the number of interior stagnation points of such an example must be an even number. Finally we will give an example of a function and a domain with the desired properties.

A negative result for the cylinder

The following proof comes from [31] and is a negative answer to question 1.2 for the cylinder.

Proposition 4.1. *Let $X = [0, 1] \times \overline{U} \subseteq \mathbb{R}^3$ be a cylinder where $U \subseteq \mathbb{R}^2$ is an open set. Let further $f: X \rightarrow \mathbb{R}$ be harmonic such that the sides $[0, 1] \times \partial U = \Sigma^0$ are the tangential boundary, the lid $\{0\} \times U = \Sigma^+$ is the entrant boundary and the lid $\{1\} \times U = \Sigma^-$ is the emergent boundary. Then f cannot have an interior critical point.*

Proof. Assume not. Since

$$\Delta(\partial_1 f) = \partial_1(\Delta f) = 0$$

we have by the maximum principle that $\partial_1 f$ attains its minimum on the boundary Σ . Since $\partial_1 f(x) = 0$ for some interior point by assumption and $\partial_1 f > 0$ on the lids $\{x_1 = 0\} \cup \{x_1 = 1\}$ there exists a point $x \in (0, 1) \times \partial U$ such that $\partial_1 f(x)$ is minimal on X . But then we have by Hopf's lemma that

$$0 < \nabla(\partial_1 f) \cdot n = \partial_1(\nabla f \cdot n) = 0,$$

a contradiction. □

A condition on the interior type numbers

Mimicking the proof of proposition 3.1 in two dimensions we obtain a condition on the type numbers for a harmonic function with interior stagnation point and simply connected entrant boundary.

4 Simply connected entrant boundaries in \mathbb{R}^3

Proposition 4.2. *Let $X \subset \mathbb{R}^3$ be a compact manifold with corners. Let $f: X \rightarrow \mathbb{R}$ be a Morse harmonic function. Assume that the strictly entrant boundary Σ^- is non-empty and simply connected and that $\gamma = \partial\Sigma^-$ is a one-dimensional manifold with corners homeomorphic to the circle $S^1 \subseteq \mathbb{R}^2$. Then we have that*

$$M_1 - M_2 = 0.$$

Proof. As in the two dimensional case we split the domain X with a surface Γ such that $\partial\Gamma = \gamma = \partial\Sigma^-$. Denote the two arising domains by X^+ and X^- where $\partial X^- \cap \Sigma^+ \subseteq \gamma$ and $\partial X^+ \cap \Sigma^- \subseteq \gamma$. Since by proposition 1.15 there are finitely many interior critical points in X we can also assume that no interior critical points lie on Γ . Furthermore we assume that Γ approaches γ at a slanted angle. For the following argumentation we require that f is strongly Morse on both X^+ and X^- so assume for a moment that this is the case. By assumption we have that γ is homeomorphic to the circle \mathbb{R}/\mathbb{Z} . Since f is non-degenerate the the number of maxima and minima of f on γ must be equal and thus

$$\text{Ind}_{\gamma^+,0}(f) + \text{Ind}_{\gamma^-,1}(-f) = \text{Ind}_{\gamma^+,1}(f) + \text{Ind}_{\gamma^-,0}(-f) \quad (4.1)$$

We now turn our attention to X^+ . Since no essential critical points lie on Σ^+ it follows for the boundary type numbers that

$$\mu_k^+ = \text{Ind}_{\Gamma^+,k}(f) + \text{Ind}_{\gamma^+,k}(f). \quad (4.2)$$

Analogously we have on X^- that

$$v_k^- = \text{Ind}_{\Gamma^-,k}(-f) + \text{Ind}_{\gamma^-,k}(-f). \quad (4.3)$$

In addition we have that the emergent critical points on $\Gamma = \Gamma^+$ of f on X^+ are the entrant critical points on $\Gamma = \Gamma^-$ of $-f$ on X^- , that is

$$\begin{aligned} \text{Ind}_{\Gamma^+,0}(f) &= \text{Ind}_{\Gamma^-,2}(-f) \\ \text{Ind}_{\Gamma^+,1}(f) &= \text{Ind}_{\Gamma^-,1}(-f) \\ \text{Ind}_{\Gamma^+,2}(f) &= \text{Ind}_{\Gamma^-,0}(-f) \end{aligned} \quad (4.4)$$

Using equations (4.2), (4.3) and (4.4) we obtain

$$\begin{aligned} \mu_0^+ - v_2^- &= \text{Ind}_{\gamma^+,0}(f) \\ \mu_1^+ - v_1^- &= \text{Ind}_{\gamma^+,1}(f) - \text{Ind}_{\gamma^-,1}(-f) \\ \mu_2^+ - v_0^- &= -\text{Ind}_{\gamma^-,0}(-f) \end{aligned} \quad (4.5)$$

We observe the Morse inequalities for f

$$M_2^+ + \mu_2^+ - M_1^+ - \mu_1^+ + \mu_0^+ = \chi(X^+) = \chi(X). \quad (4.6)$$

and the Morse inequalities for $-f$

$$M_1^- + v_2^- - M_2^- - v_1^- + v_0^- = \chi(X^-) = \chi(X) \quad (4.7)$$

where the M_k continue to denote the interior type numbers of f . We now subtract equation (4.7) from (4.6) and insert relations (4.5) to obtain then with equation (4.1)

$$\begin{aligned} 0 &= M_1^- - M_2^- + M_1^+ - M_2^+ + \text{Ind}_{\gamma^+,0}(f) + \text{Ind}_{\gamma^-,1}(-f) - \text{Ind}_{\gamma^+,1}(f) - \text{Ind}_{\gamma^-,0}(-f) \\ &= M_1 - M_2 \end{aligned}$$

from which the claim follows.

The claim remains to be shown in the case that f is not strongly Morse on X^+ and X^- . In this case let $E^+, E^- \subseteq B_\delta$ be as in corollary 1.20 applied separately to the domains X^+ and X^- . Since E^\pm are residual in B_δ we can in particular pick a $\varepsilon \in E^+ \cap E^-$ by the Baire category theorem. Since x_1, x_2 are non-degenerate critical points of f due to the slanted angle at which Γ approaches γ we obtain that

$$\text{Ind}_{\gamma,k}(f^\varepsilon) = \text{Ind}_{\gamma,k}(f) \quad \text{and} \quad \text{Ind}_{\gamma,k}(-f^\varepsilon) = \text{Ind}_{\gamma,k}(-f)$$

By the same corollary we can assume that f^ε has no essential critical points on $\Sigma^+(f)$ and $-f^\varepsilon$ has no essential critical points on $\Sigma^-(f)$. The claim then follows by the calculations above where we replace f with f^ε and then note that $M_1^\varepsilon = M_1$ and $M_2^\varepsilon = M_2$. \square

An example

Based on example 3.7 in $d = 4$ dimensions of a harmonic vector field with interior stagnation point the author argued that it would be simplest to construct such a vector field in $d = 3$ dimensions in a similar manner. More specifically we choose as domain the ball and polynomials as our harmonic function. In choosing the ball as domain we also take into account the result from proposition 4.1 which is a negative result to question 1.2 for the cylinder. Based on the result from proposition 4.2 we see that the number of stagnation points must be at least two. The author then implemented a Mathematica routine to generate harmonic polynomials with two stagnation points and a plotting function to inspect what occurs. Indeed, this approach yielded a function with the desired properties as we shall discuss in this section.

Example 4.3 (A harmonic function with interior critical point and simply connected entrant boundary). Consider the domain $X = \bar{B}_r \subseteq \mathbb{R}^3$ with $r > 0$ sufficiently large, and the harmonic function

$$\begin{aligned} f: X &\rightarrow \mathbb{R} \\ x &\mapsto \frac{x_1^2}{2} - \frac{x_1^3}{3} - \frac{x_2^2}{2} + x_1x_2^2 + x_2x_3 \end{aligned} \tag{4.8}$$

This induces the harmonic vector field

$$\begin{aligned} u: X &\rightarrow \mathbb{R}^3 \\ x &\mapsto \nabla f(x) = \begin{bmatrix} x_1(1 - x_1) + x_2^2 \\ x_2(2x_1 - 1) + x_3 \\ x_2 \end{bmatrix} \end{aligned}$$

4 Simply connected entrant boundaries in \mathbb{R}^3

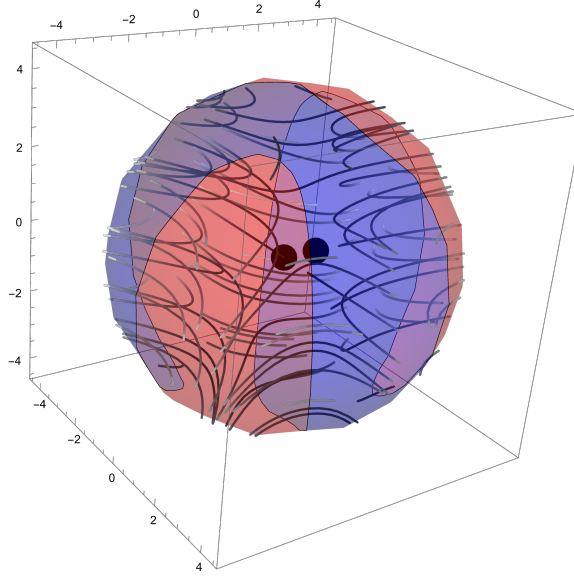


Figure 4.1: A stream plot of the function u . The interior stagnation points are highlighted in black. Σ^+ is shaded red, Σ^- blue.

It follows from setting $u(x) = 0$ that $x_2 = 0$ and then $x_3 = 0$ and $x_1 \in \{0, 1\}$. Thus we have that $x \in \{0, e_1\}$ are the sole possible zeroes of u . Conversely one sees that these are zeroes of u . Hence f has two interior critical points for $r > 1$. Figure 4.1 shows a stream plot of u with the two interior stagnation points highlighted as black dots. The boundary of the domain is shaded in blue for Σ^- and in red for Σ^+ . The stereographic projection of the boundary is plotted in figure 4.2. This plot indicates that the entrant boundary and the emergent boundary are simply connected. Indeed, we will show this in theorem 4.4.

The remainder of this section will be devoted to the proof of the following theorem:

Theorem 4.4. *The harmonic function given by equation (4.8) on the sphere has interior stagnation points and connected emergent and entrant boundaries for sufficiently large $r > 0$.*

Before we proceed to the proof we require some definitions from algebraic geometry. For an introduction this subject we refer the reader to [10], [12] or [13]. For polynomials $p_1, \dots, p_k \in \mathbb{R}[x_1, \dots, x_d]$ and a set $U \subseteq \mathbb{R}^d$ we denote the variety generated by these polynomials on U by $V_U(p_1, \dots, p_k)$. In the case that $U = \mathbb{R}^d$ we write $V(\dots) = V_U(\dots)$.

Definition 4.5 (Smoothness, [13, §5]). We call a k dimensional algebraic variety $V_U(p_1, \dots, p_n)$ *smooth* or *non-singular* if the the Jacobian

$$[\nabla p_1 \quad \dots \quad \nabla p_n]^\top$$

is of rank $d - k$ on $V_U(p_1, \dots, p_n)$. This criterion of smoothness is also called the *Jacobi criterion*.

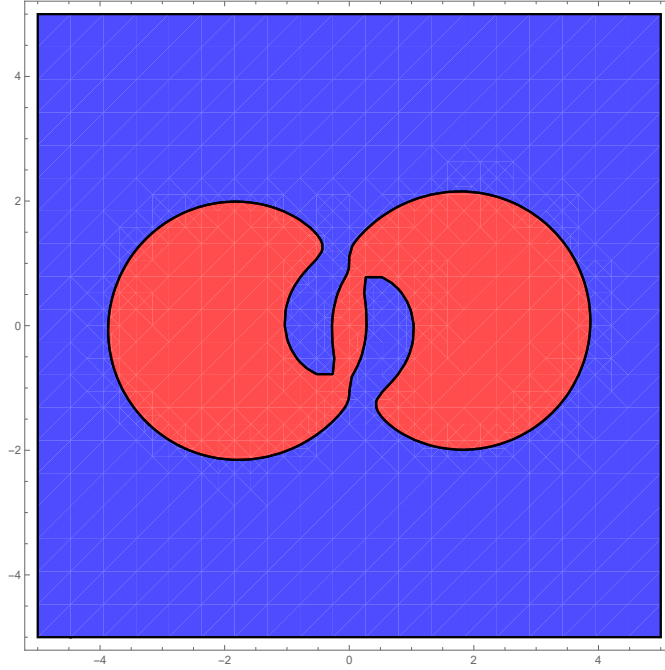


Figure 4.2: Stereographic projection of the surface Σ . Σ^+ is shaded red, Σ^- blue.

By the implicit function theorem this means that the variety $V_U(p_1, \dots, p_n)$ in fact defines a $d - k$ dimensional submanifold of \mathbb{R}^d .

The proof of theorem 4.4 requires lemmas 4.6 and 4.9 which we will show later on.

Proof of theorem 4.4. It was already discussed in example 4.3 that f has an interior critical point at the origin and is harmonic. For the connectedness of the entrant and emergent boundaries we calculate

$$rn \cdot u(x) = x_1^2(1 - x_1) + x_2^2(3x_1 - 1) + 2x_2x_3 =: p_1(x) \quad (4.9)$$

and define further

$$P_2(r, x) := x_1^2 + x_2^2 + x_3^2 - r^2. \quad (4.10)$$

Thus we have that the tangential boundary $\Sigma^0 = V(p_1, P_2(r, \cdot))$ is precisely the variety generated by the polynomials p_1 and $P_2(r, \cdot)$ for a fixed radius $r > 0$. In lemma 4.6 we will show that the variety $V(p_1, P_2(r, \cdot))$ is in fact smooth and in lemma 4.9 we will then show that it is in fact connected. Thus Σ^0 then defines a simple closed curve on Σ and the stereographic projection of Σ^0 defines a simple closed planar curve. This is indicated by the black curve in figure 4.2. By the Jordan curve theorem this curve then splits the plane into two connected regions, one of which is simply connected. The preimage of these connected regions under the stereographic projections then corresponds precisely to the entrant and emergent boundaries. From this it follows that the entrant and emergent boundaries are simply connected which proves the theorem. \square

4 Simply connected entrant boundaries in \mathbb{R}^3

From now onwards we assume that p_1 and P_2 are given by equations 4.9 and 4.10. We first show the smoothness which was required in the proof of theorem 4.4.

Lemma 4.6 (Smoothness). *There exists $R > 0$ such that for every $r > R$ the variety $V(p_1, P_2(r, \cdot))$ is smooth.*

Proof. One calculates

$$T := [\nabla p_1(x) \quad \frac{1}{2} \nabla_x P_2(r, x)] = \begin{bmatrix} -3x_1^2 + 3x_2^2 + 2x_1 & x_1 \\ 6x_1x_2 - 2x_2 + 2x_3 & x_2 \\ 2x_2 & x_3 \end{bmatrix}$$

By the Jacobi criterion it is sufficient to show that this matrix is of full rank on $V(p_1, P_2(r, \cdot))$. This is equivalent to showing that

$$\begin{aligned} 0 \neq \det \begin{bmatrix} T_{11} & T_{12} \\ T_{21} & T_{22} \end{bmatrix} &= -9x_1^2x_2 + 3x_2^3 + 4x_1x_2 - 2x_1x_3 =: h_1(x), \\ 0 \neq \det \begin{bmatrix} T_{21} & T_{22} \\ T_{31} & T_{32} \end{bmatrix} &= 6x_1x_2x_3 - 2x_2x_3 + 2x_3^2 - 2x_2^2 =: h_2(x) \text{ or} \\ 0 \neq \det \begin{bmatrix} T_{31} & T_{32} \\ T_{11} & T_{12} \end{bmatrix} &= 2x_1x_2 + 3x_1^2x_3 - 3x_2^2x_3 - 2x_1x_3 =: h_3(x) \end{aligned}$$

for any $x \in V(p_1, P_2(r, \cdot))$. This in turn is equivalent to showing that

$$V(p_1, P_2(r, \cdot), h_1, h_2, h_3) = \emptyset. \quad (4.11)$$

Indeed, consider the variety

$$V(p_1, h_1, h_2, h_3). \quad (4.12)$$

Maple calculates the Gröbner basis with lexicographic order $x_1 < x_2 < x_3$

$$72x_1^8 - 198x_1^7 + 228x_1^6 - 153x_1^5 + 56x_1^4 - 5x_1^3, \quad (4.13)$$

$$72x_1^5x_2 - 126x_1^4x_2 + 102x_1^3x_2 - 51x_1^2x_2 + 5x_1x_2, \quad (4.14)$$

$$-24x_1^7 + 42x_1^6 - 2x_1^5 - 23x_1^4 + 7x_1^3 + 10x_1x_2^2, \quad (4.15)$$

$$48x_1^4x_2 - 60x_1^3x_2 + 13x_1^2x_2 + 15x_2^3, \quad (4.16)$$

$$24x_1^4x_2 - 30x_1^3x_2 + 29x_1^2x_2 - 10x_1x_2 + 5x_1x_3, \quad (4.17)$$

$$72x_1^7 - 126x_1^6 + 6x_1^5 + 69x_1^4 - 31x_1^3 + 10x_1^2 - 10x_2^2 + 20x_2x_3, \quad (4.18)$$

$$-72x_1^7 + 414x_1^6 - 654x_1^5 + 399x_1^4 - 97x_1^3 + 10x_1^2 - 30x_2^2 + 20x_3^2. \quad (4.19)$$

For an introduction to Gröbner bases we refer the reader to for example [7]. We will however only use the fact that the polynomials (4.13)-(4.19) generate the variety (4.12). We see from the basis vector (4.13) that for $x \in V(p_1, h_1, h_2, h_3)$ the coordinate x_1 can take only finitely many values. It then follows with (4.14) that also x_2 can take only finitely many values and finally with (4.15) that x_3 can also take only finitely many values. So the variety (4.12) contains finitely many points. Thus if we choose R so large that all of these points are contained in the ball B_R then we have that (4.11) holds for all $r > R$. \square

We now define p_2 to be the dehomogenisation of P_2 , that is

$$p_2 := P_2(1, \cdot).$$

Analogously let P_1 denote the homogenisation of p_1 , that is

$$P_1(\varepsilon, x) := \varepsilon^3 p_1(x/\varepsilon).$$

By rescaling the variety $V(p_1, P_2(r, \cdot))$ we obtain

$$V(p_1, P_2(r, \cdot)) = rV(x \mapsto p_1(rx), p_2) = rV(P_1(\varepsilon, \cdot), p_2) = r\mathcal{V}_\varepsilon \quad (4.20)$$

where we set $\varepsilon = 1/r$ and $\mathcal{V}_\varepsilon := V(P_1(\varepsilon, \cdot), p_2)$. Motivated by taking the limit $r \rightarrow \infty$ we inspect the variety \mathcal{V}_0 closer. The next proposition is required in the proof of lemma 4.9. It essentially states that the varieties $\mathcal{V}_\varepsilon \rightarrow \mathcal{V}_0$ converge as $\varepsilon \rightarrow 0$ outside of singular points. We will thus also need a notion of convergence of subsets on a metric space.

Definition 4.7 (Hausdorff metric, tubular neighbourhood). The *Hausdorff metric* for two sets $A, B \subseteq X$ is given by

$$d_H(A, B) = \max \left\{ \sup_{x \in A} \text{dist}(x, B), \sup_{y \in B} \text{dist}(y, A) \right\} \quad (4.21)$$

where

$$\text{dist}(x, B) = \inf_{y \in B} d(x, y) \quad (4.22)$$

is the smallest distance from x to B . For a given $\delta > 0$ and a subset $A \subseteq \mathbb{R}^d$ we call the union of δ balls

$$\text{Tub}_\delta(A) = \bigcup_{x \in A} B_\delta(x) \quad (4.23)$$

a *tubular neighbourhood* of A .

Proposition 4.8 (Convergence of \mathcal{V}_ε at smooth points). *Let $U \subseteq \mathbb{R}^3$ be an open set such that \mathcal{V}_0 is smooth in an open neighbourhood of \overline{U} . Let further $\eta > 0$. Then there exists a $\delta > 0$ such that for all $\varepsilon < \delta$ we have that the Hausdorff distance satisfies*

$$d_H(\mathcal{V}_\varepsilon \cap U, \mathcal{V}_0 \cap U) < \eta$$

and additionally $\mathcal{V}_\varepsilon \cap U$ is isotopic to $\mathcal{V}_0 \cap U$.

Proof. Consider the mapping

$$F = \begin{bmatrix} P_1 \\ P_2 \end{bmatrix} : \mathbb{R}^4 \rightarrow \mathbb{R}^2.$$

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Since $V(P_1(0, \cdot), p_2)$ is smooth on an open neighbourhood of \overline{U} we have by the Jacobi criterion that

$$DF(0, \cdot) = \left[\begin{array}{c|c} D_\varepsilon P_1(0, \cdot) & D_x P_1(0, \cdot) \\ \hline 0 & Dp_2 \end{array} \right] \quad (4.24)$$

is of full rank on \overline{U} . By the implicit function theorem there exists at every point $x \in \overline{U}$ open neighbourhoods $\Omega_x \subseteq \mathbb{R}^4$ of $(0, x)$ and $\omega_x \subseteq \mathbb{R}^3$, a coordinate permutation $I \in O(4)$ and a continuously differentiable mapping $g_x: \omega_x \rightarrow \mathbb{R}$ such that

$$V(P_1, p_2) \cap \Omega_x = \{I(y, g_x(y)) : y \in \omega_x\}.$$

Since $D_x F(0, x)$ is of full rank we can assume (possibly after shrinking the open sets) that I does not permute the ε -coordinate. Thus we can write $y = (\varepsilon, y_1, y_2) \in \omega_x$. We can also assume that $\Omega_x = B_{\delta_x} \times W_x \subseteq \mathbb{R}^4$ for some open $W_x \subseteq \mathbb{R}^3$ and some $\delta_x > 0$. Hence we also obtain that $\omega_x = B_{\delta_x} \times w_x$ for some open $w_x \subseteq \mathbb{R}^2$ and we can define our isotopy on Ω_x as

$$\begin{aligned} \varphi_x: B_{\delta_x} \times w_x &\rightarrow W_x \\ y &\mapsto \text{proj}_{\mathbb{R}^4 \rightarrow W_x} I(y, g_x(y)). \end{aligned}$$

Note that $\varphi_x(\{\varepsilon\} \times w_x) = \mathcal{V}_\varepsilon \cap W_x$. From this it also follows that we can choose δ_x such that

$$d_H(\mathcal{V}_\varepsilon \cap W_x, \mathcal{V}_0 \cap W_x) < \eta.$$

Now for $x \in \overline{U}$ the Ω_x form an open cover of \overline{U} . By compactness there exists a finite subcover. Set $\delta > 0$ to be the minimum of all δ_x for the Ω_x in this finite subcover and the claim follows. \square

The next lemma shows the connectedness of the variety $V(p_1, P_2(r, \cdot))$. Because the proof is quite lengthy, a part of the proof has been split off into proposition 4.10 which will be proved later on.

Lemma 4.9 (Connectedness). *There exists an $r > 0$ such that the planar variety $V(p_1, P_2(r, \cdot))$ has one connectivity component.*

Proof. By lemma 4.6 there exists a $R > 0$ such that for all $r > R$ we have that the variety $V(p_1, P_2(r, \cdot))$ is smooth and by equation (4.20) \mathcal{V}_ε is also smooth for $\varepsilon < 1/R$. We inspect \mathcal{V}_0 closer. Observe that

$$P_1(0, x) = -x_1^3 + 3x_1x_2^2$$

which is the monkey saddle embedded into \mathbb{R}^3 . We thus define curves

$$\tilde{\alpha}^\pm := \left\{ t \begin{bmatrix} \pm\sqrt{3} & 1 \end{bmatrix}^\top : t \in \mathbb{R} \right\}$$

and $\tilde{\alpha}^0 := \{0\} \times \mathbb{R}$. We then define $\alpha^\bullet := (\tilde{\alpha}^\bullet \times \mathbb{R}) \cap S^2$. Setting $A := \alpha^- \cup \alpha^+ \cup \alpha^0$ we have the relation

$$\mathcal{V}_0 = V(P_1(\varepsilon, \cdot), p_2) = A.$$

Thus \mathcal{V}_0 consists of six smooth arcs originating at the singularity e_3 and ending at the singularity $-e_3$. Similar to the classical beach ball. Now consider for $\rho > 0$ the open sets $W_\rho := B_\rho \times \mathbb{R} \subseteq \mathbb{R}^3$ and $U_\rho := \mathbb{R}^3 \setminus W_\rho$. Since \mathcal{V}_0 is smooth in a neighbourhood of \bar{U}_ρ we obtain from proposition 4.8 that in a certain sense \mathcal{V}_ε is obtained from \mathcal{V}_0 by a small deformation on U_ρ . Thus in order to show connectedness of \mathcal{V}_ε for sufficiently small $\varepsilon > 0$ we have to inspect what happens around the points $\pm e_3$. Now observe that we have the symmetry

$$p_1(x_1, -x_2, -x_3) = p_1(x) \quad (4.25)$$

and thus it suffices to inspect what happens around the point e_3 . For this parametrise the neighbourhood $S^2 \cap (B_{1/2} \times \mathbb{R}_{\geq 0})$ of e_3 by the diffeomorphism

$$\begin{aligned} \psi: B_{1/2} &\rightarrow S^2 \cap (B_{1/2} \times \mathbb{R}_{\geq 0}) \\ \tilde{x} &\mapsto x = \begin{bmatrix} \tilde{x} & \sqrt{1 - |\tilde{x}|^2} \end{bmatrix}^\top. \end{aligned}$$

We set

$$\tilde{\mathcal{V}}_\varepsilon := \psi^{-1}(\mathcal{V}_\varepsilon \cap (B_{1/2} \times \mathbb{R}_{\geq 0})) = V_{B_{1/2}} \left(x \mapsto P_1 \left(\varepsilon, x_1, x_2, \sqrt{1 - x_1^2 - x_2^2} \right) \right) = V_{B_{1/2}} \left(\tilde{P}_1(\varepsilon, \cdot) \right)$$

where we defined

$$\tilde{P}_1(\varepsilon, x) := P_1 \left(\varepsilon, x_1, x_2, \sqrt{1 - x_1^2 - x_2^2} \right) = -x_1^3 + 3x_1x_2^2 + \varepsilon \left(x_1^2 - x_2^2 + x_2 \sqrt{1 - x_1^2 - x_2^2} \right).$$

In a similar manner we define $\tilde{\alpha}^\bullet := \psi^{-1}(\alpha^\bullet)$, $\tilde{U}_\rho := \psi^{-1}(U_\rho)$, $\tilde{W}_\rho := \psi^{-1}(W_\rho)$ and $\tilde{A} := \psi^{-1}(A)$. Now let the sets W and $C \subseteq W$ be as in proposition 4.10. Pick $\rho > 0$ so small that $\tilde{W}_{2\rho} \subseteq W$. Now we can pick η smaller than the minimum distance between two arcs of $\tilde{\mathcal{V}}_0$ on \tilde{U}_ρ . We also assume that η is smaller than the Hausdorff distance between $(\tilde{\alpha}^0 \cup \tilde{\alpha}^-) \cap \tilde{U}_\rho$ and C . Now choose δ as in proposition 4.8. We can assume that $0 < \varepsilon < \delta$. We thus have a situation as in figure 4.3. Number the arcs lying close to $A \cap U_\rho$ as in figure 4.4. Since $\tilde{\gamma}$ by proposition 4.10 splits $\tilde{W}_{2\rho}$ and lies in $C \cap \tilde{\mathcal{V}}_\varepsilon$ we must have that $\tilde{\gamma}$ in fact connects arcs 3 and 6. As the variety is smooth we must also have that arcs 1 and 2 are connected and analogously that arcs 4 and 5 are connected. By equation (4.25) the situation around $-e_3$ is analogous but mirrored. We thus obtain analogous connections between the six arcs at $-e_3$ which is summarised in figure 4.5. Thus we in fact have that \mathcal{V}_ε is connected. The claim then follows from relation (4.20). \square

The following proposition is part of the proof of lemma 4.9:

Proposition 4.10. *Let \tilde{U}_ρ , $\tilde{\alpha}^\bullet$, \tilde{A} , $\tilde{\mathcal{V}}_\varepsilon$ and \tilde{P}_1 be as in the proof of lemma 4.9. There exists an open cube $W \subseteq \mathbb{R}^2$ containing the origin and a set $C \subseteq W$ such that C has positive Hausdorff distance to the set $(\tilde{\alpha}^0 \cup \tilde{\alpha}^-) \cap \tilde{U}_\rho$ for any $\rho > 0$ and such that for any sufficiently small $\varepsilon > 0$ there is an arc $\tilde{\gamma}$ entirely contained in $C \cap \tilde{\mathcal{V}}_\varepsilon$ splitting W into two parts.*

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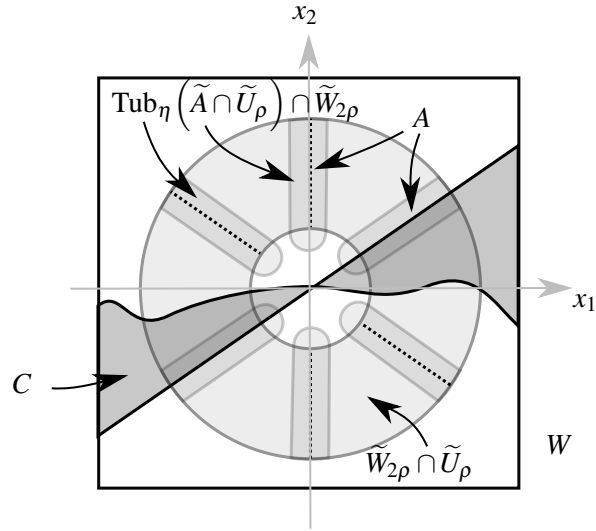


Figure 4.3: An overview of the situation around e_3 .

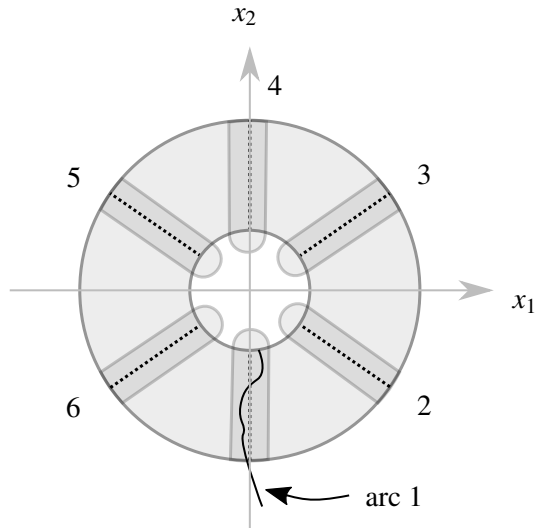


Figure 4.4: The numbering of the arcs around e_3 .

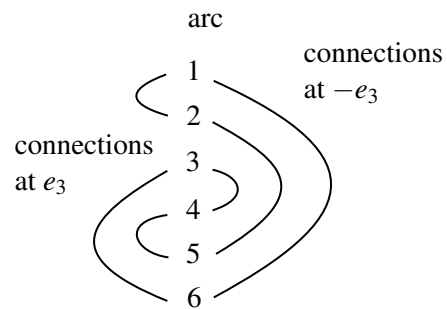


Figure 4.5: The connection of the arcs at $\pm e_3$.

Proof. We borrow notation from the proof of lemma 4.9. Let $W \subseteq \mathbb{R}^2$ be an open cube around the origin which we fix later. Define polynomials

$$\tilde{q}_1(x) := -x_1^3 + 3x_1x_2^2 \quad (4.26)$$

$$\tilde{q}_2(x) := x_1^2 - x_2^2 + x_2\sqrt{1 - x_1^2 - x_2^2} \quad (4.27)$$

and observe that

$$\tilde{P}_1(\varepsilon, \cdot) = \tilde{q}_1 + \varepsilon\tilde{q}_2. \quad (4.28)$$

By equation (4.26) \tilde{q}_1 is a monkey saddle and $V_W(\tilde{q}_1) = \tilde{A}$ is similar to figure 4.6a. The signs in the figure indicate the sign of \tilde{q}_1 in a given region. From equation (4.27) we obtain that $\nabla\tilde{q}_2(0) = e_2$ and $\tilde{q}_2(0) = 0$. Hence we observe that the $V_W(\tilde{q}_2)$ looks similar to figure 4.6b for a sufficiently small neighbourhood W . More concretely we choose W so small that the arc $\tilde{\beta} = V_W(\tilde{q}_2)$ has positive distance to $\tilde{A} \cap \tilde{U}_\rho$ for any $\rho > 0$ and such that a given vertical line in W intersects $\tilde{\beta}$ in precisely one point. Now we claim that the set C consisting of the vertical lines between $\tilde{\alpha}^+$ and $\tilde{\beta}$ fulfils the claim.

We first show that there exists a curve $\tilde{\gamma}$ through the origin which is entirely contained in $C \cap \tilde{\mathcal{V}}_\varepsilon$. For this note that we have $\tilde{P}_1(\varepsilon, 0) = 0$ and $\nabla_x \tilde{P}_1(\varepsilon, x)|_{x=0} = \varepsilon e_2$ and thus there exists locally around the origin a parametrisation $\tilde{\gamma}(t) = (t, \tilde{\gamma}_2(t))$. By a similar argument there also exists locally a parametrisation $\tilde{\beta}(t) = (t, \tilde{\beta}_2(t))$. We see that $\tilde{\gamma}$ lies locally below $\tilde{\alpha}^+$ and thus we need to show that $\tilde{\gamma}_2$ also lies locally above $\tilde{\beta}_2$ on the right half plane and locally below $\tilde{\beta}_2$ on the left half plane. We calculate derivatives

$$\begin{aligned} D\tilde{q}_1|_{x=0} &= 0 \\ D^2\tilde{q}_1|_{x=0} &= 0 \\ D^3\tilde{q}_1|_{x=0}(v, v, v) &= -6v_1^3 + 18v_1v_2^2 \end{aligned}$$

and

$$\begin{aligned} D\tilde{q}_2|_{x=0} &= e_2^\top \\ D^2\tilde{q}_2|_{x=0} &= \begin{bmatrix} 2 & \\ & -2 \end{bmatrix} \\ D^3\tilde{q}_2|_{x=0}(v, v, v) &= 3v_1^2v_2 + v_2^3 \end{aligned}$$

and now by relation (4.28)

$$\begin{aligned} Dh|_{x=0} &= \varepsilon D_x \tilde{q}_2 \\ D^2h|_{x=0} &= \varepsilon D_x^2 \tilde{q}_2 \\ D^3h|_{x=0}(v, v, v) &= -6v_1^3 + 18v_1v_2^2 + \varepsilon(3v_1^2v_2 + v_2^3). \end{aligned} \quad (4.29)$$

where we wrote $h(x) = \tilde{P}_1(\varepsilon, x)$ for brevity. We have $0 = h \circ \tilde{\gamma}$ and thus

$$0 = \partial_t(h \circ \tilde{\gamma})|_{t=0} = \left(Dh|_{\tilde{\gamma}} \tilde{\gamma}'\right)_{t=0} = \varepsilon \tilde{\gamma}_2'(0) \quad (4.30)$$

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so $\tilde{\gamma}_2'(0) = 0$ and in particular $\tilde{\gamma}'(0) = e_1$. Taking another derivative we get

$$\begin{aligned} 0 &= \partial_t^2(h \circ \tilde{\gamma})|_{t=0} \\ &= \left(D^2h|_{\tilde{\gamma}}(\tilde{\gamma}, \tilde{\gamma}) + Dh|_{\tilde{\gamma}}\tilde{\gamma}'' \right)_{t=0} \\ &= \left(D^2h|_{x=0}(e_1, e_1) + Dh|_{x=0}\tilde{\gamma}'' \right)_{t=0} \\ &= \varepsilon(2 + \tilde{\gamma}_2'')(0) \end{aligned} \tag{4.31}$$

so $\tilde{\gamma}''(0) = -2e_2$. The third derivative then yields

$$\begin{aligned} 0 &= \partial_t^3(h \circ \tilde{\gamma})|_{t=0} \\ &= \left(D^3h|_{\tilde{\gamma}}(\tilde{\gamma}, \tilde{\gamma}, \tilde{\gamma}) + 3D^2h|_{\tilde{\gamma}}(\tilde{\gamma}, \tilde{\gamma}') + Dh|_{\tilde{\gamma}}\tilde{\gamma}''' \right)_{t=0} \\ &= \left(D^3h|_{x=0}(e_1, e_1, e_1) - 6D^2h|_{x=0}(e_1, e_2) + Dh|_{x=0}\tilde{\gamma}''' \right)_{t=0} \\ &= (-6 + \varepsilon(\tilde{\gamma}_2'''))(0) \end{aligned}$$

so $\tilde{\gamma}_2'''(0) = 6/\varepsilon$. Analogously we observe that it follows from $0 = \tilde{q}_2 \circ \tilde{\beta}$ that

$$0 = \varepsilon \partial_t \left(\tilde{q}_2 \circ \tilde{\beta} \right) |_{x=0} = \varepsilon \left(D\tilde{q}_2|_{\tilde{\gamma}}\tilde{\beta}' \right)_{t=0} \tag{4.32}$$

and

$$0 = \varepsilon \partial_t^2 \left(\tilde{q}_2 \circ \tilde{\beta} \right) |_{x=0} = \varepsilon \left(D^2\tilde{q}_2|_{\tilde{\gamma}}(\tilde{\beta}', \tilde{\beta}') + D\tilde{q}_2|_{\tilde{\gamma}}\tilde{\beta}'' \right)_{t=0}. \tag{4.33}$$

By the relations (4.29), equation (4.32) is identical to equation (4.30) and equation (4.33) is identical to equation (4.31) with $\tilde{\gamma}$ replaced by $\tilde{\beta}$. Now equations (4.30) and (4.31) determined $\tilde{\gamma}'(0)$ and $\tilde{\gamma}''(0)$ uniquely and thus we have that $\tilde{\gamma}(0) = \tilde{\beta}(0)$, $\tilde{\gamma}'(0) = \tilde{\beta}'(0)$ and $\tilde{\gamma}''(0) = \tilde{\beta}''(0)$. For the third derivative we observe that

$$\begin{aligned} 0 &= \partial_t^3 \left(\tilde{q}_2 \circ \tilde{\beta} \right) |_{t=0} \\ &= \left(D^3\tilde{q}_2|_{\tilde{\gamma}}(\tilde{\beta}', \tilde{\beta}', \tilde{\beta}') + 3D^2\tilde{q}_2|_{\tilde{\gamma}}(\tilde{\beta}', \tilde{\beta}'') + D\tilde{q}_2|_{\tilde{\gamma}}\tilde{\beta}''' \right)_{t=0} \\ &= \left(D^3\tilde{q}_2|_{x=0}(e_1, e_1, e_1) - 6D^2\tilde{q}_2|_{x=0}(e_1, e_2) + D\tilde{q}_2|_{x=0}\tilde{\beta}''' \right)_{t=0} \\ &= \tilde{\beta}_2'''(0) \end{aligned}$$

so $\tilde{\beta}_2'''(0) = 0$. Thus we obtain

$$\partial_t^k(\tilde{\gamma}_2 - \tilde{\beta}_2)|_{t=0} = 0$$

for $k \leq 2$ and

$$\partial_t^3(\tilde{\gamma}_2 - \tilde{\beta}_2)|_{t=0} = 6/\varepsilon > 0.$$

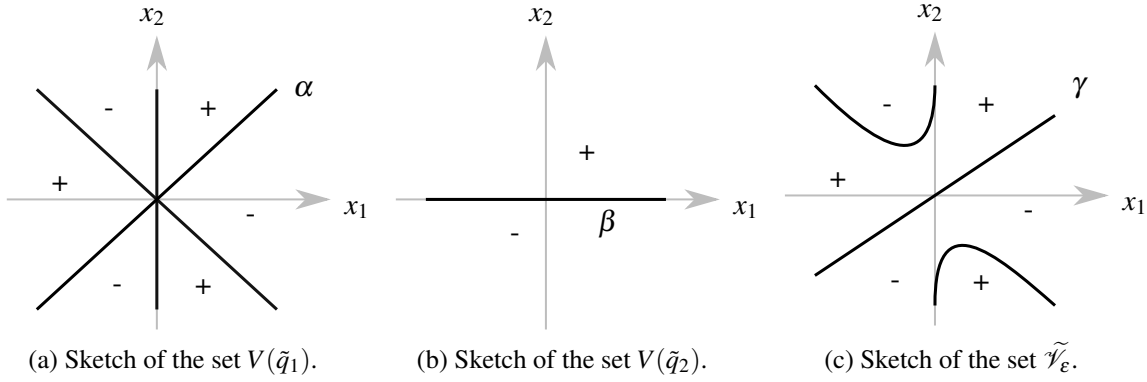


Figure 4.6: Sketches of varieties.

Hence we indeed have that $\tilde{\gamma}_2 > \tilde{\beta}_2$ in a sufficiently small neighbourhood of the origin for $t > 0$ and also that $\tilde{\gamma}_2 < \tilde{\beta}_2$ in a sufficiently small neighbourhood for $t < 0$.

Now that we have established that $\tilde{\gamma}$ lies locally in C it remains to be shown that $\tilde{\gamma}$ indeed reaches the boundary ∂W . For this let $\tilde{\gamma}: [0, b) \rightarrow C$ be a maximally extended parametrisation of $\tilde{\gamma}$. Since C is compact there exists a sequence $t_k \rightarrow b$ such that $x_k = \tilde{\gamma}(t_k) \rightarrow x$ is convergent. Then we have by continuity that also $h(x) = 0$ so also $x \in \mathcal{V}_\epsilon$. As \mathcal{V}_ϵ is smooth we have that $Dh(x)$ is of full rank. Thus by the implicit function theorem we must in fact have that $b < \infty$ and the parametrisation of $\tilde{\gamma}$ can be extended beyond the point b . But this means that $x \in \partial C$. Again by smoothness x cannot lie in the origin. Now note that $\tilde{P}_1(\epsilon, \cdot) = \tilde{q}_1 < 0$ on the arc $\tilde{\beta}$ and that $\tilde{P}_1(\epsilon, \cdot) = \tilde{q}_2 > 0$ on the arc $\tilde{\alpha}^+$. So $\tilde{\gamma}$ cannot intersect ∂C on $\tilde{\beta}$ or on $\tilde{\alpha}$. Thus we must have that $x \in \partial W$ and hence $\tilde{\gamma}$ splits W in the right half plane into two parts. On the left half plane the argumentation is analogous. Then $\tilde{\gamma}$ divides the plane into two parts which yields the claim. For clarity the idea of the proof is also depicted in figure 4.7. Also note that as a consequence $\tilde{\mathcal{V}}_\epsilon$ looks similar to figure 4.6c. \square

An example with positive distance between the entrant and emergent boundaries

In the previous example we showed that Σ^+ is separated from Σ^- by the curve $\Sigma^0 = V(p_1, P_2(r, \cdot))$. In the following we will show that it is possible to thicken this curve Σ^0 without losing the fundamental properties of the solution. More concretely, we construct a harmonic function f_ρ for which the entrant and emergent boundaries are simply connected, have positive distance from one another and such that f_ρ has an interior stagnation point. For this we use the notation from the previous example. We need a preliminary result:

Proposition 4.11 (Existence of a cutoff function). *Let Σ and Σ^0 be as in example 4.3. For every $\rho > 0$ there exists a cutoff function $\theta_\rho: \Sigma \rightarrow [0, 1]$ such that*

1. $\theta_\rho = 1$ outside of the tubular neighbourhood $\text{Tub}_\rho(\Sigma^0)$,

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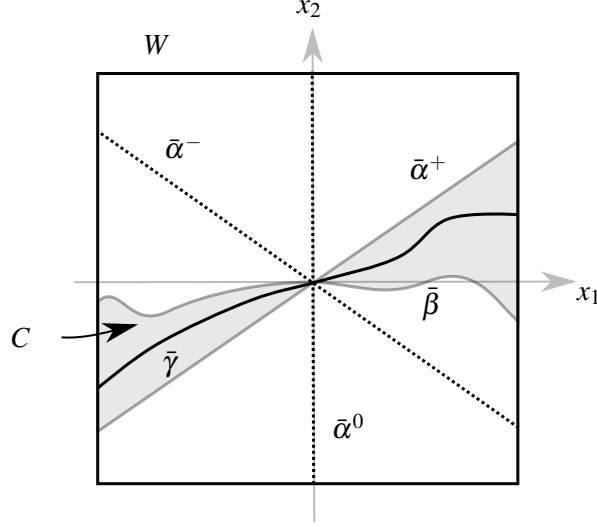


Figure 4.7: An overview of the situation in proposition 4.10.

2. θ_ρ has support contained in $\Sigma \setminus \Sigma^0$ and
3. $\langle \theta_\rho p_1 \rangle_\Sigma = 0$, where $\langle h \rangle_X := \int_X h$ denotes the mean of a function $h: X \rightarrow Y$.

Proof. Let $\theta_\lambda^+: \Sigma \rightarrow [0, 1]$ be a family of cutoff functions smoothly depending on λ such that $\theta_\lambda^+ = 1$ outside of $\text{Tub}_\lambda(\Sigma^0) \cup \Sigma^-$ and θ_λ^+ has support contained in Σ^+ . Analogously we let $\theta_\lambda^-: \Sigma \rightarrow [0, 1]$ be a family of cutoff functions smoothly depending on λ such that $\theta_\lambda^- = 1$ outside of $\text{Tub}_\lambda(\Sigma^0) \cup \Sigma^+$ and θ_λ^- has support contained in Σ^- . We can also assume that both θ_λ^+ and θ_λ^- are monotonously increasing in λ . Set

$$\tilde{\theta}_\rho = \theta_\rho^+ + \theta_{\lambda(\rho)}^- \quad (4.34)$$

where $\lambda: \mathbb{R}_{\geq 0} \rightarrow \mathbb{R}_{\geq 0}$ is a suitably chosen map. By construction the support of $\tilde{\theta}_\rho$ lies outside of the set $\Sigma \setminus \Sigma^0$ so $\tilde{\theta}_\rho$ fulfils condition 2. For condition 3 we calculate

$$\langle \tilde{\theta}_\rho p_1 \rangle_\Sigma = \langle \theta_\rho^+ p_1 \rangle_{\Sigma^+} + \langle \theta_{\lambda(\rho)}^- p_1 \rangle_{\Sigma^-} \quad (4.35)$$

Now we have that $p_1 < 0$ on Σ^- and that $p_1 > 0$ on Σ^+ . Thus $\langle \theta_\rho^+ p_1 \rangle_{\Sigma^+} > 0$ is monotonically increasing with ρ and

$$\langle \theta_\rho^+ p_1 \rangle_{\Sigma^+} \longrightarrow \langle p_1 \rangle_{\Sigma^+} =: c^+$$

as $\rho \rightarrow 0$. Analogously $\langle \theta_\lambda^- p_1 \rangle_{\Sigma^-} < 0$ is monotonically and continuously decreasing with λ and

$$\langle \theta_\lambda^- p_1 \rangle_{\Sigma^-} \longrightarrow \langle p_1 \rangle_{\Sigma^-} =: c^-$$

as $\lambda \rightarrow 0$. It follows from the divergence theorem that

$$0 = r \int_X \Delta f = \int_\Sigma r \nabla f \cdot n = \langle p_1 \rangle_\Sigma = c^+ + c^-$$

where $n\Sigma \rightarrow S^2$ is the outer unit normal. It then follows that for each $\rho > 0$ there exists a $\lambda(\rho) > 0$ such that

$$\langle \theta_\rho^+ p_1 \rangle_{\Sigma^+} = \langle \theta_{\lambda(\rho)}^- p_1 \rangle_{\Sigma^-}$$

so by equation (4.35) $\tilde{\theta}_\rho$ also fulfils condition 3. In fact we can also assume that $\lambda(\rho) \rightarrow 0$ as $\rho \rightarrow 0$. Now choose $\tilde{\lambda}(\rho)$ such that $\max(\tilde{\lambda}, \lambda(\tilde{\lambda})) < \rho$. This defines a function $\tilde{\lambda} : \mathbb{R}_{\geq 0} \rightarrow \mathbb{R}_{\geq 0}$ and we set $\theta_\rho := \tilde{\theta}_{\tilde{\lambda}(\rho)}$. Property 1 then follows from the fact that $\tilde{\theta}_\rho = 1$ outside of the neighbourhood $\text{Tub}_{\max(\rho, \lambda(\rho))}(\Sigma^0)$ by equation 4.34. \square

With the help of this cutoff function θ_ρ we can now formulate our main result in this section:

Example 4.12 (Thickening Σ^0). Let f and X be as in example 4.3 and the cutoff function θ_ρ be as in the previous proposition. Consider now the solution f_ρ to the system

$$\begin{aligned} \Delta f_\rho &= 0 && \text{on } X, \\ \nabla f_\rho \cdot n &= \theta_\rho(\nabla f \cdot n) && \text{on } \Sigma, \\ \langle f_\rho \rangle_X &= \langle f \rangle_X \end{aligned}$$

where $n : \Sigma \rightarrow S^2$ is the outer unit normal. By definition of f_ρ the entrant and emergent boundaries are simply connected and have positive distance from one another. We will show in proposition 4.13 that there exists $\rho > 0$ such that f_ρ has an interior critical point.

Proposition 4.13 (Structural stability). *Let x be a non-degenerate interior critical point of f . Then there exist $P > 0$ and $\varepsilon > 0$ such that for all $\rho \leq P$ the function f_ρ from example 4.12 has an interior critical point in $\bar{B}_\varepsilon(x)$.*

Proof. To simplify notation we only show this for the interior critical point of f at the origin $x = 0$. Define $g_\rho := f_\rho - f$. By linearity g_ρ is a solution the system

$$\begin{aligned} \Delta g_\rho &= 0 && \text{on } X, \\ \nabla g_\rho \cdot n &= (\theta_\rho - 1)(\nabla f \cdot n) && \text{on } \Sigma, \\ \langle g_\rho \rangle_X &= 0 \end{aligned}$$

To simplify notation we write $x \lesssim y$ instead of $x \leq cy$ for some constant $c \geq 1$ which is independent

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of ρ . We have that

$$\begin{aligned}
\|Dg_\rho\|_{L^2(X;\mathbb{R}^d)}^2 &\stackrel{\text{divergence Theorem}}{=} \int_{\Sigma} g_\rho (\nabla g_\rho \cdot n) \\
&\stackrel{\text{Cauchy-Schwarz}}{\leq} \|g_\rho\|_{L^2(\Sigma)} \|\nabla g_\rho \cdot n\|_{L^2(\Sigma)} \\
&\stackrel{\text{trace theorem}}{\lesssim} \|g_\rho\|_{W^{1,2}(X)} \|\nabla g_\rho \cdot n\|_{L^2(\Sigma)} \\
&\stackrel{\text{Poincaré-Wirtinger}}{\lesssim} \|Dg_\rho\|_{L^2(X;\mathbb{R}^d)} \|\nabla g_\rho \cdot n\|_{L^2(\Sigma)}
\end{aligned}$$

and thus together with dominated convergence

$$\|Dg_\rho\|_{L^2(X;\mathbb{R}^d)} \lesssim \|\nabla g_\rho \cdot n\|_{L^2(\Sigma)} = \|(\theta_\rho - 1)(\nabla f \cdot n)\|_{L^2(\Sigma)} \longrightarrow 0$$

as $\rho \rightarrow 0$. As a consequence of this we obtain on the one hand that for a compactly contained open set $\{0\} \Subset U \Subset X$ with smooth boundary we have

$$\begin{aligned}
\|Dg_\rho\|_{L^\infty(U;\mathbb{R}^{d \times d})} &\stackrel{\text{mean value property}}{\lesssim} \|Dg_\rho\|_{L^1(X;\mathbb{R}^{d \times d})} \\
&\stackrel{\text{Cauchy-Schwarz}}{\lesssim} \|Dg_\rho\|_{L^2(X;\mathbb{R}^{d \times d})} \longrightarrow 0
\end{aligned} \tag{4.36}$$

as $\rho \rightarrow 0$. It also follows for a compactly contained open set $U \Subset V \Subset X$ with smooth boundary that

$$\begin{aligned}
\|D^2 g_\rho\|_{L^\infty(U;\mathbb{R}^{d \times d})} &\stackrel{\text{mean value property}}{\lesssim} \|D^2 g_\rho\|_{L^1(V;\mathbb{R}^{d \times d})} \\
&\stackrel{\text{Cauchy-Schwarz}}{\lesssim} \|D^2 g_\rho\|_{L^2(V;\mathbb{R}^{d \times d})} \\
&\stackrel{\text{interior regularity}}{\lesssim} \|Dg_\rho\|_{L^2(X;\mathbb{R}^d)} \longrightarrow 0
\end{aligned} \tag{4.37}$$

as $\rho \rightarrow 0$.

We would like to apply a fixed point theorem. For this we define a mapping

$$F_\rho(y) = y - D^2 f|_0^{-1} Df_\rho(y)$$

where we used the fact that $D^2f|_0$ is bijective by non-degeneracy. We denote by $\|\cdot\|_{\text{Op}}$ the operator norm induced by $L^\infty(U; \mathbb{R}^d)$, that is

$$\|h\|_{\text{Op}} = \sup_{y \in L^\infty(U; \mathbb{R}^d) \setminus \{0\}} \frac{\|hy\|_{L^\infty(U; \mathbb{R}^d)}}{\|y\|_{L^\infty(U; \mathbb{R}^d)}}$$

for some function $h \in L^\infty(U; \mathbb{R}^{d \times d})$. Set $U = B_\varepsilon \subseteq \mathbb{R}^3$ to be an open ball around the origin with radius $\varepsilon > 0$. We calculate the derivative

$$DF_\rho = \text{Id} - D^2f|_0^{-1} D^2f_\rho$$

and take the operator norm

$$\frac{1}{c} \|DF_\rho\|_{\text{Op}} \leq \|D^2f|_0 - D^2f_\rho\|_{\text{Op}} \leq \|D^2f|_0 - D^2f\|_{\text{Op}} + \|D^2g_\rho\|_{\text{Op}} \quad (4.38)$$

for some constant $c \geq 1$ independent of ρ . Now we have by continuity that

$$\|D^2f|_0 - D^2f\|_{\text{Op}} \lesssim \|D^2f|_0 - D^2f\|_{L^\infty(U; \mathbb{R}^{d \times d})} \longrightarrow 0$$

as $\varepsilon \rightarrow 0$. Pick $\varepsilon > 0$ such that $\|D^2f|_0 - D^2f\|_{\text{Op}} \leq 1/(4c)$. Now we have for $\rho \rightarrow 0$ that

$$\|D^2g_\rho\|_{\text{Op}} \lesssim \|D^2g_\rho\|_{L^\infty(U; \mathbb{R}^{d \times d})} \longrightarrow 0$$

by equation (4.37). Thus there exists a $P > 0$ such that $\|D^2g_\rho\|_{\text{Op}} \leq 1/(4c)$ for all $\rho \leq P$. By equation (4.38) it then follows that $\|DF_\rho\|_{\text{Op}} \leq 1/2$ for all $\rho \leq P$. Since we have by equation (4.36) that

$$|F_\rho(0)| = |D^2f|_0^{-1} Df_\rho(0)| \lesssim |Df_\rho(0)| = |Dg_\rho(0)| \leq \|Dg_\rho\|_{L^\infty(U; \mathbb{R}^d)} \longrightarrow 0$$

as $\rho \rightarrow 0$ we can also additionally choose $P > 0$ such that for all $\rho \leq P$ we have that $|F_\rho(0)| \leq \varepsilon/2$. We then have for all $\rho \leq P$ that $F_\rho(\overline{B}_\varepsilon) \subseteq \overline{B}_\varepsilon$ and F_ρ is a contraction. It then follows from fixed point theorems that for every $\rho \leq P$ the function F_ρ has a fixed point, say $y_\rho \in \overline{B}_\varepsilon$. This then fulfils by the construction of F_ρ the equation

$$y_\rho = F_\rho(y_\rho) = y_\rho - D^2f|_0^{-1} Df_\rho(y_\rho)$$

which implies that $Df_\rho(y_\rho) = 0$ and y_ρ is an interior critical point. \square

5 No in- or outflow in \mathbb{R}^2

In the second part of this thesis we will discuss harmonic vector fields without inflow or outflow through the boundary. More generally we will first consider harmonic vector fields without boundary critical points. Here we will show in proposition 5.1 that in $d = 2$ dimensions there is a strong relation between the number of critical points and the domain topology. We will then discuss briefly how this relates to the Poincaré-Hopf index theorem. After that we will give examples which illustrate these results.

A condition on the number of stagnation points

Our first result relates the number of critical points with the domain topology. We shall give two proofs of this result, one involving Morse theory and the other involving the argument principle. The reason for this is that the result follows quickly from the argument principle. However, the techniques of the proof involving Morse theory generalise more readily to $d = 3$ dimensions.

Proposition 5.1. *Let $X \subset \mathbb{R}^2$ be a compact manifold with corners and Betti numbers $b_0 = 1$, and b_1 and let $u: X \rightarrow \mathbb{R}^2$ be a strongly Morse harmonic vector field without boundary stagnation points. Then we have the relation $M = -\chi(X)$ where M denotes the number of stagnation points and $\chi(X)$ is the Euler characteristic of X .*

Proof. We slit the domain X such that it is homeomorphic to the disk as is depicted in figure 5.1. Denote the slit by Γ . Since the number of interior stagnation points is finite by proposition 1.15, we can choose Γ in such a way that it does not contain any interior stagnation points. We write denote the boundary of Γ by $\gamma = \partial\Gamma = \Gamma \cap \Sigma$ and define points $\{x_1, \dots, x_{2b_1}\} = \gamma$. Note that there are $2b_1$ many such points. Without loss of generality we can assume that Γ and u form an acute angle at each point of γ . The situation is depicted in figure 5.1. For the following argumentation we require that u is strongly Morse on the new domain \tilde{X} so assume for a moment that this is the case. Since each x_j is either an essential critical point of u or of $-u$ on the slit domain \tilde{X} we have that

$$\text{Ind}_{\gamma,0}(u) + \text{Ind}_{\gamma,0}(-u) = 2b_1. \quad (5.1)$$

Since there are no stagnation points on Σ we have the relations

$$\mu_k = \text{Ind}_{\Gamma,k}(u) + \text{Ind}_{\gamma,k}(u) \quad \text{and} \quad \nu_k = \text{Ind}_{\Gamma,k}(-u) + \text{Ind}_{\gamma,k}(-u) \quad (5.2)$$

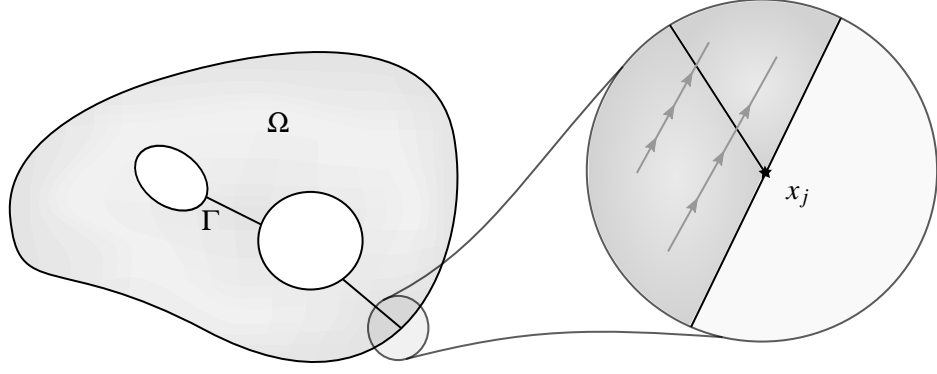


Figure 5.1: How we slit the domain.

for all $k \in \{0, 1\}$. All entrant stagnation points of u on Γ are also emergent stagnation points of $-u$ on Γ (and vice versa) and hence we have the relations

$$\text{Ind}_{\Gamma,0}(u) = \text{Ind}_{\Gamma,1}(-u) \quad \text{and} \quad \text{Ind}_{\Gamma,1}(u) = \text{Ind}_{\Gamma,0}(-u). \quad (5.3)$$

Equations (5.2) and (5.3) yield

$$\mu_0 - \text{Ind}_{\gamma,0}(u) = \nu_1 \quad \text{and} \quad \mu_1 = \nu_0 - \text{Ind}_{\gamma,0}(-u). \quad (5.4)$$

Since \tilde{X} is now simply connected u is by proposition 1.1 the gradient of a harmonic function f on this new domain. For this f we have the Morse inequalities

$$M + \mu_1 - \mu_0 = -\chi(\tilde{X}) = -1 \quad (5.5)$$

and for $-f$ the Morse inequalities

$$M + \nu_1 - \nu_0 = -\chi(\tilde{X}) = -1. \quad (5.6)$$

Adding equations (5.5) and (5.6) and using the relation (5.4) and then (5.1) we obtain

$$-2 = 2M - \text{Ind}_{\gamma,0}(u) - \text{Ind}_{\gamma,0}(u) = 2M - 2b_1$$

from which the claim follows.

The claim remains to be shown in the case that u is not strongly Morse on \tilde{X} . In this case let u^ε for $\varepsilon \in E$ be a strongly Morse function as in corollary 1.20. Since the $x_1, \dots, x_{2b_1} \in \gamma$ are non-degenerate stagnation points of u due to the slanted angle at which Γ approaches γ we obtain that

$$\text{Ind}_{\gamma,k}(u^\varepsilon) = \text{Ind}_{\gamma,k}(u) \quad \text{and} \quad \text{Ind}_{\gamma,k}(-u^\varepsilon) = \text{Ind}_{\gamma,k}(-u) \quad (5.7)$$

By the same corollary u^ε has no stagnation points on Σ . The claim then follows by the calculations above where we replace u with u^ε and then note that $M^\varepsilon = M$. \square

We now give an alternative and simpler proof of proposition 5.1 using the argument principle.

Alternative proof. As before we slit the domain such that it is homeomorphic to a disk. By proposition 1.1 u is the gradient of a harmonic function f on this new domain \tilde{X} . Let $h \in \text{Hol}(\tilde{X})$ be the holomorphic function given by $h = \nabla f$. Let γ traverse the boundary of the slit domain such that the domain lies to the left of γ . We now determine the change of argument $\arg h$ along γ . For this consider first the slits. Since ∇f is continuously differentiable along the slit and γ traverses the slit once in one direction and once in the other, the contribution to the change of $\arg h$ from the slits vanishes. On the other hand as γ traverses the boundary Σ the contribution to the change in argument of $\arg h$ is 2π for every hole in the domain since $h \cdot \gamma' = u \cdot \gamma'$ does not change sign as γ traverses a hole in clockwise direction. Similarly the contribution to the change in argument of $\arg h$ is -2π for the outer boundary component which is traversed counterclockwise. Since we have b_1 holes in the domain the total change of $\arg h$ as γ traverses Σ is $2\pi(b_1 - 1)$. Since h has no poles it follows from the argument principle (see for example [9, Chapter VIII]) that

$$2\pi(b_1 - 1) = \int_{\gamma} d\arg(h(z)) = 2\pi M$$

from which the claim follows. \square

We say that u has no *inflow* on a boundary subset $S \subseteq \Sigma$ if $\Sigma^- \cap S = \emptyset$ and that it has no *outflow* if $\Sigma^+ \cap S = \emptyset$. Armed with this definition we can give the following corollary.

Corollary 5.2. *Let X be a compact manifold with corners and $u: X \rightarrow \mathbb{R}^2$ a strongly Morse harmonic vector field without inflow or outflow on Σ . Then we have the relation $M = -\chi(X)$ where M is the number of stagnation points and $\chi(X)$ is the Euler characteristic of X .*

This corollary could also have been proved using the Poincaré-Hopf index theorem. For this define:

Definition 5.3 ([5, Definition 1.1.1]). The *Poincaré-Hopf index* $\text{Ind}_{\text{PH},x}(f)$ of an isolated interior stagnation point x of u is the degree of the Gauss map $u/|u|: S_{\varepsilon}^{d-1}(x) \rightarrow S^{d-1}$ for sufficiently small $\varepsilon > 0$. The *total index* $\text{Ind}_{\text{PH}}(u)$ is the sum of indexes $\text{Ind}_{\text{PH},x}(f)$ for every interior stagnation point x of u .

Note that in $d = 2$ dimensions a point x with Morse index k has Poincaré-Hopf index $(-1)^k$. Thus we have for a harmonic vector field in $d = 2$ dimensions that $M = -\text{Ind}_{\text{PH}}(u)$ and thus corollary 5.2 also follows from the Poincaré-Hopf index theorem:

Theorem 5.4 (Poincaré-Hopf index theorem, [23, §6]). *Let $u: X \rightarrow \mathbb{R}^d$ be a vector field on a manifold with corners without inflow. Then we have that the total index $\text{Ind}_{\text{PH}}(u)$ equals the Euler characteristic $\chi(X)$.*

For a proof we refer the reader for instance to [23, §6].

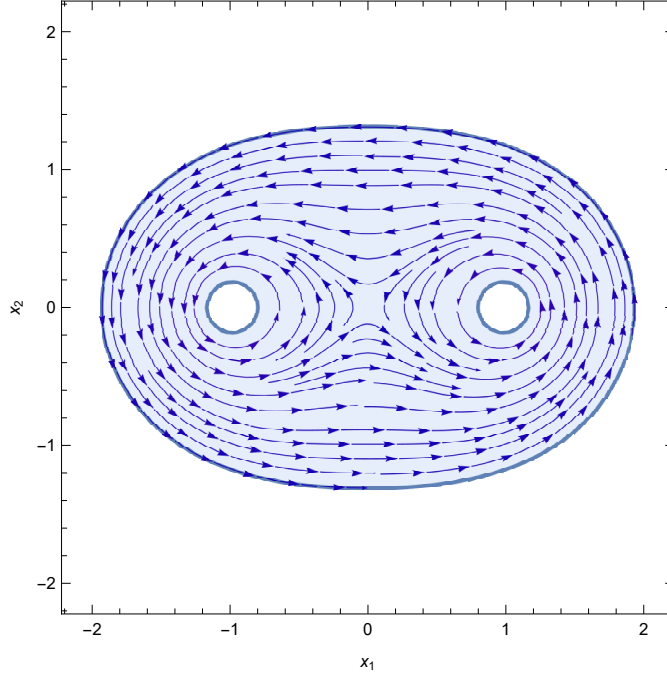


Figure 5.2: A plot of $u = \nabla^\perp \psi$ in the domain $\psi^{-1}([-1, 1])$. Here ψ is given by equation (5.8).

Examples of harmonic vector fields

We would like to illustrate the previous results with examples. We first give an example of a harmonic vector field in $d = 2$ dimensions without inflow or outflow and with one stagnation point.

Example 5.5 (No in- or outflow). Consider the stream function

$$\begin{aligned} \psi: \mathbb{R}^2 \setminus \{-e_1, e_1\} &\rightarrow \mathbb{R} \\ x &\mapsto \Phi_2(x - e_1) + \Phi_2(x + e_1) \end{aligned} \quad (5.8)$$

where Φ_2 is as in example 3.5. A plot of the streamlines in figure 5.2 indicates that $u = \nabla^\perp \psi$ in the domain $X = \psi^{-1}([-1, 1])$ has the desired properties. Indeed, since ψ is constant on each component of Σ the function u has neither inflow nor outflow. It follows from $\psi(-x) = \psi(x)$ that $u(-x) = -u(x)$ and thus the origin $x = 0$ is a stagnation point. By proposition 5.1 it is in fact the sole stagnation point of u on X .

In a second example given by [31] we start with the domain rather than the function.

Example 5.6 (No in- or outflow). Set $X = \overline{B_4} \setminus (B_1(2e_1) \cup B_1(-2e_1))$ to be the domain. We let the stream function ψ be determined by the system

$$\begin{aligned} \Delta \psi &= 0 \quad \text{on } \text{int}(X), \\ \psi &= 0 \quad \text{on the outer ring } 4S^1, \\ \psi &= 1 \quad \text{on the inner rings } S^1(-2e_1) \cup S^1(2e_1), \end{aligned} \quad (5.9)$$

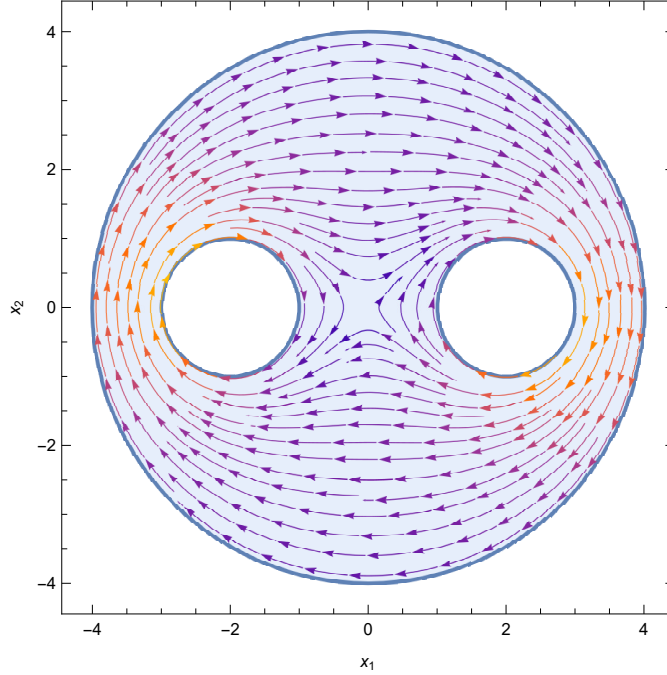


Figure 5.3: A plot of $u = \nabla^\perp \psi$ where ψ is the numerical solution to (5.9).

and set $u = \nabla^\perp \psi$. A numerical solution to this system is plotted in figure 5.3. Again, it follows from symmetry that the origin is a stagnation point and from proposition 5.1 that it is in fact the sole stagnation point of u .

Our third example highlights the importance of assuming that u be Morse in corollary 5.2.

Example 5.7 (Stagnation points on the boundary). In this example given by [31] we again start by fixing the domain. Let $X = \overline{B}_4 \setminus (B_1(2e_1) \cup B_1(-2e_1))$ be the domain as before. We let the stream function ψ be determined by the system

$$\begin{aligned} \Delta \psi &= 0 && \text{on } \text{int}(X), \\ \psi &= 0 && \text{on the outer ring } 4S^1, \\ \psi &= -1 && \text{on the left inner ring } S^1(-2e_1), \\ \psi &= 1 && \text{on the right inner ring } S^1(2e_1), \end{aligned} \tag{5.10}$$

and then set $u = \nabla^\perp \psi$. The numerical solution to this system is plotted in figure 5.4. Here we obtain from the symmetry $\psi(-x_1, x_2) = \psi(x_1, x_2)$ that $\psi = 0$ on the x_2 -axis. Since also $\psi = 0$ on $4S^1$ we have two stagnation points at $\pm 4e_2$. This function again has no in- or outflow through the boundary. The domain contains two holes so $\chi(X) = -1$. Now u has no interior stagnation point, seemingly contradicting corollary 5.2. But since the two stagnation points at $\pm 4e_2$ lie on the boundary u is in fact not Morse and thus we cannot apply corollary 5.2. This shows the importance of the assumption that u is Morse. Proposition 5.8 essentially states that in this case

5 No in- or outflow in \mathbb{R}^2

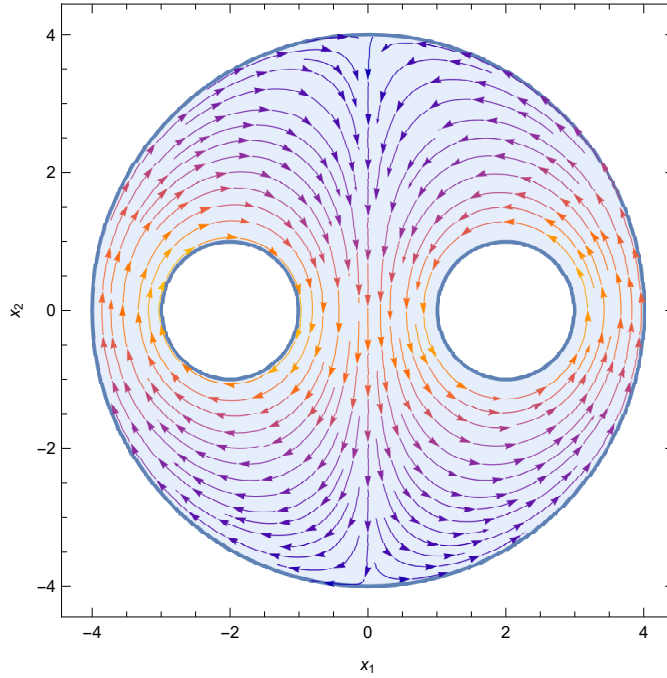


Figure 5.4: A plot of $u = \nabla^\perp \psi$ where ψ is the numerical solution to (5.10).

the stagnation points of u on the boundary count half as much as stagnation points in the interior. This explains why there are two critical points in this example.

Proposition 5.8 (Critical points on the boundary, [2, Theorem 1.1]). *Let $X \subseteq \mathbb{R}^2$ be bounded with piecewise $C^{1,\alpha}$ boundary. Let further $f: X \rightarrow \mathbb{R}$ be harmonic, not constant on each connectivity component and constant on each boundary component. Then there exist finitely many critical points $x_1, \dots, x_k \in X$ of u with multiplicities m_1, \dots, m_k and we have that*

$$\sum_{x_j \in \text{int}(X)} m_j + \frac{1}{2} \sum_{x_j \in \Sigma} m_j = -\chi(X).$$

Proof. The proof uses complex analysis techniques and can be found in [2]. □

6 No in- or outflow in \mathbb{R}^3

In \mathbb{R}^3 our results to question 1.3 remain unsatisfactory. Nonetheless we will state them in this final chapter. The question from [20, p.198] remains if it is possible to have a harmonic vector field in \mathbb{R}^3 with interior stagnation point and no in- or outflow through the boundary. This can be generalised to the question if it is possible to have a harmonic vector field $u: \mathbb{R}^3 \supseteq X \rightarrow \mathbb{R}^3$ with interior critical points and without critical points on the boundary. We remark that the boundary Σ cannot have a component homeomorphic to the sphere S^2 as a direct consequence of the hairy ball theorem. We can also give a nontrivial condition on the interior critical points of such a u using the techniques of previous proofs:

Proposition 6.1. *Let $X \subseteq \mathbb{R}^3$ be a compact manifold with corners and Betti numbers b_0, b_1 and b_2 . Let $u: X \rightarrow \mathbb{R}^3$ be a strongly Morse harmonic vector field without boundary critical points. Then the following relation for the interior type numbers of u holds:*

$$M_1 = M_2.$$

Proof. As in the two dimensional case we cut the domain X with a surface Γ such that the slit domain is homeomorphic to a ball with bubbles. Since the number of interior stagnation points of u is finite by proposition 1.15, we can choose Γ in such a way that it does not contain any stagnation points. We also denote the arcs at which Γ meets Σ by $\gamma_1, \dots, \gamma_{b_1} \subseteq \partial\Gamma$. Note that there are b_1 many such curves. We can assume that Γ and the γ_j are manifolds with corners and that Γ approaches each γ_j at a slanted angle. The cut now yields a new domain \tilde{X} which is a covering space of X . On this covering space we denote the cover of the cut Γ and the sets γ_j by Γ^i and γ_j^i with $i \in (1, 2)$. Since this new domain \tilde{X} is homeomorphic to a ball with bubbles the vector field $u = \nabla f$ is the gradient of a harmonic function f by proposition 1.1. For the following argumentation we require that u is strongly Morse on \tilde{X} , so assume for a moment that this is the case. Now we have that each γ_j is homeomorphic to the circle $S^1 \subseteq \mathbb{R}^2$. Since f is non-degenerate the number of maxima and minima of f on $\gamma_j^1 \cup \gamma_j^2$ must be equal and thus

$$\sum_i \left(\text{Ind}_{\gamma_j^1, 0}(f) + \text{Ind}_{\gamma_j^1, 1}(-f) \right) = \sum_i \left(\text{Ind}_{\gamma_j^2, 1}(f) + \text{Ind}_{\gamma_j^2, 0}(-f) \right). \quad (6.1)$$

Since on Γ all entrant stagnation points of u are also emergent stagnation points of $-u$ (and vice versa) we have the relations

$$\begin{aligned} \text{Ind}_{\Gamma^1, 0}(\pm u) &= \text{Ind}_{\Gamma^2, 2}(\mp u) \\ \text{Ind}_{\Gamma^1, 1}(\pm u) &= \text{Ind}_{\Gamma^2, 1}(\mp u) \\ \text{Ind}_{\Gamma^1, 2}(\pm u) &= \text{Ind}_{\Gamma^2, 0}(\mp u). \end{aligned} \quad (6.2)$$

6 No in- or outflow in \mathbb{R}^3

As there are no boundary critical points on Σ it follows for the boundary type numbers that

$$\begin{aligned}\mu_k &= \sum_i \left(\text{Ind}_{\Gamma^i, k} + \sum_j \text{Ind}_{\gamma_j^i, k} \right) (f) \\ \nu_k &= \sum_i \left(\text{Ind}_{\Gamma^i, k} + \sum_j \text{Ind}_{\gamma_j^i, k} \right) (-f).\end{aligned}\tag{6.3}$$

Equations (6.3) and (6.2) yield

$$\begin{aligned}\mu_0 - \nu_2 &= \sum_{i,j} \text{Ind}_{\gamma_j^i, 0} (f) \\ \mu_1 - \nu_1 &= \sum_{i,j} \left(\text{Ind}_{\gamma_j^i, 1} (f) - \text{Ind}_{\gamma_j^i, 1} (-f) \right) \\ \mu_2 - \nu_0 &= - \sum_{i,j} \text{Ind}_{\gamma_j^i, 0} (-f)\end{aligned}\tag{6.4}$$

For f we have the Morse inequalities

$$M_2 + \mu_2 - M_1 - \mu_1 + \mu_0 = -\chi(\tilde{X})\tag{6.5}$$

and for $-f$ the Morse inequalities

$$M_1 + \nu_2 - M_2 - \nu_1 + \nu_0 = -\chi(\tilde{X}).\tag{6.6}$$

Subtracting equation (6.6) from (6.5) and using the relation (6.4) we obtain together with equation (6.1) that

$$\begin{aligned}0 &= 2(M_2 - M_1) + \sum_{i,j} \left(\text{Ind}_{\gamma_j^i, 0} (f) - \text{Ind}_{\gamma_j^i, 1} (f) + \text{Ind}_{\gamma_j^i, 1} (-f) - \text{Ind}_{\gamma_j^i, 0} (-f) \right) \\ &= 2(M_2 - M_1)\end{aligned}$$

from which the claim follows.

The claim remains to be shown in the case that f is not strongly Morse on X^+ and X^- . In this case let f^ε for $\varepsilon \in E$ be a strongly Morse function as in corollary 1.20. Since x_1, x_2 are non-degenerate critical points of f due to the slanted angle at which Γ approaches each γ_j we obtain that

$$\text{Ind}_{\gamma_j, k} (f^\varepsilon) = \text{Ind}_{\gamma_j, k} (f) \quad \text{and} \quad \text{Ind}_{\gamma_j, k} (-f^\varepsilon) = \text{Ind}_{\gamma_j, k} (-f)\tag{6.7}$$

By the same corollary we can assume that f^ε has no critical points on Σ . The claim then follows by the calculations above where we replace f with f^ε and then note that $M_1^\varepsilon = M_1$ and $M_2^\varepsilon = M_2$. \square

As a consequence we obtain the following:

Corollary 6.2. *Let X be a compact manifold with corners and $u: X \rightarrow \mathbb{R}^d$ a strongly Morse harmonic vector field without inflow or outflow on the boundary Σ . Then we have that*

$$M_1 = M_2.$$

Symbols

d	Dimensions $d = 2$ or $d = 3$
X	Compact domain in \mathbb{R}^d , often assumed to be a manifold with corners.
$f: X \rightarrow \mathbb{R}$	A harmonic function.
$u: X \rightarrow \mathbb{R}^d$ or T^*X	A harmonic vector field.
X_j	A stratification of X as given in definition 1.5. Often but not always assumed to be given by equation (1.1)
\prec	We write $X_j \prec X_k$ if $X_j \subseteq \overline{X}_k$. See definition 1.5 for details.
\lesssim	We write $X_j \lesssim X_k$ if $X_j \prec X_k$ and an additional condition holds. See definition 1.5 for details.
Σ	Boundary $\Sigma = \partial X$
$\Sigma^-, \Sigma^{\leq 0}$	(Strictly) entrant boundary. See definition 1.8.
$\Sigma^+, \Sigma^{\geq 0}$	(Strictly) emergent boundary. See definition 1.8.
Σ^0	Tangential boundary. See definition 1.8.
Σ^{irr}	Irregular boundary. See definition 1.10.
$B_r(x), B_r$	Ball of radius r around the point x / the origin.
$S^{d-1}(x), S^{d-1}$	$(d-1)$ -dimensional sphere around x / the origin.
e_j	j -th unit vector in \mathbb{R}^d .
u_j	Projection of u to the cotangent bundle T^*X_j . See equation (1.7).
π_j	Orthogonal projection onto the cotangent bundle T^*X_j . See equation (1.6).
Cr_j	Set of essential stagnation points. See definition 1.10.
$\text{Ind}_{j,k}$	k -th type number on the stratum X_j . See equation (1.8).
Ind_k	k -th type number. See equation (1.13).
M_k	k -th interior type numbers. See equation (1.10).
M	Total number of stagnation points. See equation (1.11).
μ_k	k -th boundary type numbers of f . See equation (1.12).
ν_k	k -th boundary type numbers of $-f$. See definition 1.10.
u^ε	modification to u as in equation (1.15)
A	submanifold, can be thought of as the zero section of T^*X
b_k	Betti number as defined in equation (2.1)
$\chi(X)$	Euler characteristic.
∇^\perp	Orthogonal gradient. Given by equation (3.11).
Φ_2	Multiple of the fundamental solution of the Laplace equation on \mathbb{R}^2 . Given by equation (3.13).

Symbols

$V_U(\dots), V(\dots)$	Algebraic variety.
$d_H(A, B)$	Hausdorff metric. See equation (4.21).
$\text{dist}(x, A)$	Distance between x and A . See equation (4.22)
$\text{Tub}_\delta(A)$	Tubular neighbourhood of A . See equation (4.23).
$\langle h \rangle_X$	Mean $\int_X h$ of a function $h: X \rightarrow Y$.
\lesssim	$x \lesssim y$ means there exists a constant $c \geq 1$ such that $x \leq cy$.

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