

## Basic Properties

**Definition:** A topological space  $M$  is called a *manifold* if it satisfies the following:

- $M$  is Hausdorff (points can be separated by open sets);
- $M$  is second countable (the basis for the topology of  $M$  is countable);
- $M$  is locally Euclidean (every point in  $M$  has a neighborhood homeomorphic to  $\mathbb{R}^n$  for some  $n$ ).

In particular, the third condition says that for every  $p \in M$ , there is  $U \in \mathcal{O}_p$  and a homeomorphism  $\varphi: U \rightarrow \mathbb{R}^n$ . The value of  $n$  is called the *dimension* of the manifold  $M$ .

**Definition:** Let  $M$  be an  $n$ -manifold. A *chart* on  $M$  is a pair  $(U, \varphi)$  such that  $U \subseteq M$  is open,  $\varphi: U \rightarrow \mathbb{R}^n$  is a homeomorphism.

A family of charts  $\mathcal{A} = \{(U_i, \varphi_i)\}_{i \in I}$  is known as an *atlas* if

$$M = \bigcup_{i \in I} U_i.$$

To understand the smooth structure of a manifold, we consider a point  $p \in M$  and two charts  $(U, \varphi_U)$  and  $(V, \varphi_V)$  such that  $p \in U$  and  $p \in V$ . The functions  $\varphi_U: U \rightarrow \mathbb{R}^n$  and  $\varphi_V: V \rightarrow \mathbb{R}^n$  are homeomorphisms, meaning that  $\varphi_V \circ \varphi_U^{-1}: \varphi_U(U \cap V) \rightarrow \mathbb{R}^n$  defined on the (nonempty)  $U \cap V$  is also a homeomorphism.

In particular, we develop the smooth structure by making sure all such pairs  $\varphi_V \circ \varphi_U^{-1}$  are *diffeomorphisms*. To do this, we need to first develop the derivative in  $\mathbb{R}^n$ .

**Definition:** Let  $f: \mathbb{R}^n \rightarrow \mathbb{R}^m$  be a function. We say  $f$  is *differentiable* at  $p \in \mathbb{R}^n$  if there is a linear map  $L \in \text{Hom}(\mathbb{R}^n, \mathbb{R}^m)$  such that

$$\frac{\|f(p+h) - f(p) - Lh\|}{\|h\|} \rightarrow 0$$

as  $h \rightarrow 0$ .

The *derivative* of  $f$  is the association  $f \mapsto L$  for each  $p \in \mathbb{R}^n$ . We write  $D_p f$  to denote this map. Note that we consider elements of  $\text{Mat}_n(\mathbb{R})$  as points in  $\mathbb{R}^{n^2}$  with the standard topology on  $\mathbb{R}^{n^2}$ .

A function  $f$  is called a *diffeomorphism* if it is continuously differentiable and has a continuously differentiable inverse.

**Definition:** If  $(U, \varphi_U)$  and  $(V, \varphi_V)$  are charts such that  $U \cap V \neq \emptyset$ , the function  $\varphi_V \circ \varphi_U^{-1}: \mathbb{R}^n \rightarrow \mathbb{R}^n$  is known as the *transition map* between  $\varphi_U$  and  $\varphi_V$ .

A smooth structure for  $M$  is an atlas  $\{(U_i, \varphi_i)\}_{i \in I}$  such that for all  $i, j$ , the transition maps  $\varphi_j \circ \varphi_i^{-1}: \mathbb{R}^n \rightarrow \mathbb{R}^n$  are diffeomorphisms where defined.

If  $\{(U_i, \varphi_i)\}_{i \in I}$  is a *maximal* smooth atlas — i.e., any other smooth atlas that contains  $\{(U_i, \varphi_i)\}_{i \in I}$  is equal to  $\{(U_i, \varphi_i)\}_{i \in I}$  — then we call  $\{(U_i, \varphi_i)\}_{i \in I}$  a *smooth structure* for  $M$ .

**Note:** From now on, we use “manifold” to refer to smooth manifolds, and will say *topological* manifolds if the manifold does not necessarily admit a smooth structure.

**Definition:** A map  $f: M \rightarrow N$  between manifolds is called *smooth* if for any chart  $(U, \varphi_U)$  in  $M$  and corresponding chart  $(V, \varphi_V)$  in  $N$ , the map  $\varphi_V \circ f \circ \varphi_U^{-1}: \mathbb{R}^n \rightarrow \mathbb{R}^k$  is continuously differentiable.

The function  $f$  is a *diffeomorphism* if  $f$  is a smooth bijection with smooth inverse, and we say the manifolds  $M$  and  $N$  are diffeomorphic if they admit a diffeomorphism.

## More on Smooth Maps

Generally speaking, we will refer to charts on a dimension  $n$  smooth manifold by  $(U, \varphi) = (U; x_1, \dots, x_n)$ , where  $x_i: U \rightarrow \mathbb{R}$  are the coordinates of  $U$ . Additionally, if  $(\mathbb{R}^n; e_1, \dots, e_n)$  are the identity chart on  $\mathbb{R}^n$ , and the  $e_i$  are standard coordinates on  $\mathbb{R}^n$ , then the coordinate maps satisfy

$$x_i = e_i \circ \varphi.$$

**Definition:** Let  $(U; x_1, \dots, x_n)$  be a chart on a manifold  $M$  of dimension  $n$ . If  $f: M \rightarrow \mathbb{R}$  is a  $C^\infty$  function, we define the *partial derivative* of  $f$  with respect to  $x_i$  at  $p$  to be

$$\frac{\partial f}{\partial x_i}(p) = \frac{\partial (f \circ \varphi^{-1})}{\partial e_i}(\varphi(p)).$$

In particular,

$$\frac{\partial f}{\partial x_i} \circ \varphi^{-1} = \frac{\partial (f \circ \varphi^{-1})}{\partial e_i}$$

as functions on  $\phi(U)$ .

**Proposition:** The coordinate functions  $x_1, \dots, x_n$  satisfy  $\frac{\partial x_i}{\partial x_j} = \delta_{ij}$ , where  $\delta_{ij}$  is the Kronecker delta.

*Proof.* For any  $p \in U$ , we calculate

$$\begin{aligned} \frac{\partial x_i}{\partial x_j}(p) &= \frac{\partial (x_i \circ \varphi^{-1})}{\partial e_j}(\varphi(p)) \\ &= \frac{\partial ((e_i \circ \varphi))}{\partial e_j}(\varphi(p)) \\ &= \frac{\partial e_i}{\partial e_j}(\varphi(p)) \\ &= \delta_{ij}. \end{aligned}$$

□

## Examples

There are a couple special examples of (smooth) manifolds.

- (i) Open subsets of  $\mathbb{R}^n$  are always manifolds.
- (ii) The general linear group,  $GL_n(\mathbb{R})$  of  $n \times n$  invertible matrices, viewed as a subset of  $Mat_n(\mathbb{R}) \cong \mathbb{R}^{n^2}$ , is a manifold. Furthermore, it is an open subset of  $\mathbb{R}^{n^2}$ , as considering the map  $\det: Mat_n(\mathbb{R}) \rightarrow \mathbb{R}$  given by  $A \mapsto \det(A)$ , we see that  $GL_n(\mathbb{R}) = \det^{-1}(\mathbb{R} \setminus \{0\})$ .
- (iii) The special linear group,  $SL_n(\mathbb{R}) \subseteq GL_n(\mathbb{R})$ , consisting of  $n \times n$  matrices with determinant 1, is also a smooth manifold. Furthermore, this manifold is a closed subset of  $\mathbb{R}^{n^2}$ , as it is equal to  $\det^{-1}(\{1\})$ .
- (iv) The  $n$ -sphere,  $S^n$ , given by

$$S^n = \left\{ (x_0, \dots, x_n) \left| \sum_{i=0}^n x_i^2 = 1 \right. \right\}$$

is a manifold in  $\mathbb{R}^n$ . That it is a smooth manifold is quite a bit less obvious.

Now, in low dimensions, we know that  $S^2 \cong \hat{\mathbb{C}} = \mathbb{C} \cup \{\infty\}$ , and that the continuously differentiable transformation  $z \mapsto \frac{1}{z}$  takes the neighborhood basis of  $\infty$  to deleted neighborhoods of 0, and takes

the neighborhood basis of 0 to the neighborhood basis of  $\infty$ . This is our desired smooth structure.

In the case of the general  $S^n$ , we use two stereographic projections to construct our smooth structure. The first stereographic projection is via the north pole,  $N_p$ , and maps points on  $S^n \setminus \{N_p\}$  bijectively to  $\mathbb{R}^n$ ; this is a chart that is defined everywhere on  $S^n$  except  $N_p$ . Similarly, we may use a stereographic projection originating from the south pole,  $S_p$ , so as to create another chart defined everywhere except  $S_p$ . These two stereographic projections are our desired smooth structure, as these two charts are all that is necessary to cover  $S^n$ .

- (v) The real projective plane, consisting of lines through the origin in  $\mathbb{R}^{n+1}$ , can be expressed as

$$\mathbb{RP}^n = (\mathbb{R}^{n+1} \setminus \{0\})/\mathbb{R}^\times.$$

We will show that this is a manifold by constructing a family of charts mapping to  $\mathbb{R}^n$ .

Consider a point  $(r_0, \dots, r_n) \in \mathbb{R}^{n+1} \setminus \{0\}$ . If  $r_0 \neq 0$ , then by dividing, we may associate this point's equivalence class in  $\mathbb{RP}^n$  to

$$(1, r_1/r_0, \dots, r_n/r_0) \in \{1\} \times \mathbb{R}^n,$$

so we may associate all points of the form  $[(r_0, \dots, r_n)]$  with  $r_0 \neq 0$  with a chart  $(U_0, \varphi_0)$  that maps  $\mathbb{RP}^n$  to  $\mathbb{R}^n$ .

Similarly, we may define  $U_k$  via

$$U_k = \{[(r_0, \dots, r_n)] \mid r_k \neq 0\}$$

with corresponding chart

$$\begin{aligned} \varphi_k: U_k &\rightarrow \mathbb{R}^n \\ [(r_0, \dots, r_n)] &\mapsto \frac{1}{r_k}(r_0, \dots, \widehat{r_k}, \dots, r_n), \end{aligned}$$

where  $\widehat{r_k}$  denotes the exclusion of the  $r_k$  coordinate. Varying  $k$  from 0 to  $n$ , we see that

$$\mathbb{RP}^n = \bigcup_{k=0}^n U_k,$$

the chart functions  $\varphi_k: U_k \rightarrow \mathbb{R}^n$  are homeomorphisms (as they are just division and projections). Furthermore, the transition maps  $\varphi_j \circ \varphi_i^{-1}$  are coordinate-wise rational functions defined by

$$(u_1, \dots, u_n) \mapsto \left( \frac{u_1}{u_i}, \dots, \frac{1}{u_i}, \dots, \frac{u_n}{u_i} \right),$$

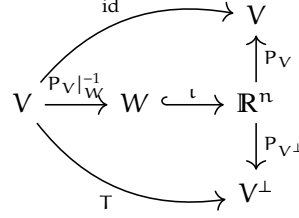
where the  $\frac{1}{u_i}$  is at position  $j$ .

- (vi) We now turn to a very important example from algebraic geometry: the Grassmannian,  $\text{Gr}(k, n)$ , consisting of all the  $k$ -dimensional subspaces of  $\mathbb{R}^n$ .

This is a  $k(n - k)$ -dimensional manifold; we need to understand what the smooth structure is. To do this, we let  $\langle \cdot, \cdot \rangle$  be an inner product on  $\mathbb{R}^n$ , and for any  $V \in \text{Gr}(k, n)$ , we consider maps in  $\text{Hom}(V, V^\perp)$ , where  $V^\perp$  denotes the orthogonal complement of  $V$ .

Now, we see that if  $W \in \text{Gr}(k, n)$  is any other  $k$ -dimensional subspace, the orthogonal  $P_V: \mathbb{R}^n \rightarrow V$  restricted to  $W$  is a linear isomorphism if and only if  $W \not\subseteq V^\perp$ , or that  $W \cap V^\perp = \{0\}$ .

We see that if  $W$  is such that  $P_V|_W: W \rightarrow V$  is a linear isomorphism, the inverse  $(P_V|_W)^{-1}: V \rightarrow W$  is well-defined; so, we may make a correspondence between  $\text{Hom}(V, V^\perp)$  and  $\text{Gr}(k, n)$  by noting that any such  $T \in \text{Hom}(V, V^\perp)$  has a corresponding graph  $(v, T(v))$ , so we take  $v \mapsto P_V|_W^{-1}(v)$ , then project onto  $V^\perp$  by taking  $T(P_V|_W^{-1}(v)) = T(v)$ . We depict it as a diagram below.



Defining  $U_V = \{W \in \text{Gr}(k, n) \mid W \cap V^\perp = \{0\}\}$ , we may define the chart from  $U_V$  onto  $\text{Hom}(V, V^\perp)$  by  $\varphi_V = P_{V^\perp} \circ P_V|_W^{-1}$ . The family  $\{(U_V, \varphi_V) \mid V \in \text{Gr}(k, n)\}$  is our smooth atlas.

## Inverse and Implicit Function Theorems

In order to replace manifolds with linear maps, we need to understand smooth maps on  $\mathbb{R}^n$ . The most important theorems in this regard are the inverse function theorem and the implicit function theorem.

**Theorem (Inverse Function Theorem):** Let  $f: U \subseteq \mathbb{R}^n \rightarrow \mathbb{R}^n$  be a continuously differentiable function. If  $D_p f$  is invertible as a linear map, then  $f$  has a local, continuously differentiable inverse  $f^{-1}: V \rightarrow W$ , where  $p \in W \subseteq U$  and  $f(p) \in V \subseteq \mathbb{R}^n$ .

Additionally,  $D_p(f^{-1})$  is given by the inverse of the derivative's corresponding linear map evaluated at  $p$ ,  $D_p(f^{-1}) = (D_p f(f^{-1}(p)))^{-1}$ .

The proof uses the contraction mapping theorem. Recall that if  $X$  is a complete metric space, and  $f: X \rightarrow X$  is a strict uniform contraction — that is, there exists  $0 \leq \lambda < 1$  such that  $d(f(x), f(y)) \leq \lambda d(x, y)$  for all  $x, y \in X$  — then  $f$  has a unique fixed point.

We begin with a technical lemma.

**Lemma:** If  $U(0, r) \subseteq V$  for some  $r > 0$  where  $V$  is a normed vector space,  $g: V \rightarrow V$  is a uniform contraction, and  $f = \text{id} + g$ , then the following hold:

- $(1 - \lambda)\|x - y\| \leq \|f(x) - f(y)\|$  (in particular,  $f$  is injective);
- if  $g(0) = 0$ , then

$$U(0, (1 - \lambda)r) \subseteq f(U(0, r)) \subseteq U(0, (1 + \lambda)r).$$

*Proof of Lemma.* To see the first item, we notice that by the triangle inequality,

$$\begin{aligned}
 \|x - y\| - \|f(x) - f(y)\| &\leq \|x - y\| - \|x - y\| + \|g(x) - g(y)\| \\
 &\leq \lambda\|x - y\|,
 \end{aligned}$$

so  $(1 - \lambda)\|x - y\| \leq \|f(x) - f(y)\|$ , and  $f$  is injective. Furthermore, we see that if  $g(0) = 0$ , then

$$\begin{aligned}
 f(U(0, r)) &= U(0, r) + g(U(0, r)) \\
 &\subseteq U(0, r) + \lambda U(0, r) \\
 &= U(0, (1 + \lambda)r).
 \end{aligned}$$

Finally, if  $y \in U(0, (1 - \lambda)r)$ , then we want to find  $x$  such that  $y = f(x) = x + g(x)$ ; equivalently, we see that we want  $x$  such that  $x = y - g(x)$ . Since the function  $F(x) = y - g(x)$  is a translation of a uniform contraction,  $F(x)$  is a contraction, so there is a fixed point, meaning  $y \in f(U(0, r))$ .  $\square$

**Note:** We will use  $|\cdot|$  to denote the norm on  $\mathbb{R}^n$ .

*Proof of the Inverse Function Theorem.* By using a series of affine maps — first by translating  $p$  to 0, then translating  $f(p)$  to 0, then inverting  $D_0f$  as per our assumption, we may safely assume that  $p = f(p) = 0$  and  $D_0f = \text{Id}$ .

Set  $g = f - \text{Id}$ . We will show that  $g$  is a contraction in a sufficiently small ball. Fixing  $x, y \in \mathbb{R}^n$ , consider the map  $\mathbb{R} \rightarrow \mathbb{R}^n$  given by  $t \mapsto g(x + t(y - x))$ . Notice that by the Fundamental Theorem of Calculus,

$$|g(y) - g(x)| \leq |y - x| \sup_{0 \leq t \leq 1} |g'(x + t(y - x))|.$$

Furthermore, since  $g'(0) = 0$  by the fact that  $D_0f = \text{Id}$  and  $(\text{Id})' = \text{Id}$ , and since  $f$  is continuously differentiable, there is  $r > 0$  such that

$$|g(y) - g(x)| \leq \frac{1}{2}|y - x|$$

for all  $x, y \in U(0, r)$ . Thus,  $g$  is a strict contraction on  $U(0, r)$ . By the previous lemma, we see that

$$U(0, r/2) \subseteq f(U(0, r));$$

by setting  $U = U(0, r) \cap f^{-1}(U(0, r/2))$ , we see that the map  $f|_U: U \rightarrow V := U(0, r/2)$  is a bijection. The inverse function  $f^{-1}: V \rightarrow U$  thus exists.

Now, we let  $h = f^{-1}$ ,  $x \in U$ ,  $y \in V$  such that  $h(x) = y$ , and  $A = D_x f$ . We will show that  $A^{-1} = D_y h$ , which is enough to show that  $h$  is continuously differentiable, as we assume the map  $x \mapsto D_x f$  is continuous, and inversion is continuous in  $GL_n(\mathbb{R})$ .

For sufficiently small vectors  $s$  and  $k$ , since  $f$  and  $h$  are bijections, we have

$$h(y + k) = x + s,$$

so

$$f(x + s) = y + k.$$

Furthermore, by unraveling the definitions of  $f = g + \text{Id}$ ,  $s$ , and  $k$ , and the fact that  $g$  is a uniform contraction on  $U$ , we get

$$\begin{aligned} |s - k| &= |(f(x + s) - f(x)) - s| \\ &= |(x + s + g(x + s)) - (x + g(x)) - s| \\ &= |g(x + s) - g(x)| \\ &\leq \frac{|s|}{2}. \end{aligned}$$

In particular, since

$$\begin{aligned} |s| &\leq |s - k| + |k| \\ &\leq |k| + \frac{|s|}{2}, \end{aligned}$$

we see that  $|s|/2 \leq |k|$ . We calculate

$$\begin{aligned} |h(y + k) - h(y) - A^{-1}k| &= |x + s - x - A^{-1}(f(x + s) - f(x))| \\ &= |s - A^{-1}(f(x + s) - f(x))| \\ &\leq \|A^{-1}\|_{\text{op}} |As - f(x + s) - f(x)|. \end{aligned}$$

Thus, since  $|s|/2 \leq |k|$ ,

$$\frac{|h(y+k) - h(y) - A^{-1}k|}{|k|} \leq \frac{2\|A^{-1}\|_{\text{op}}|As - f(x+s) - f(x)|}{|s|} \rightarrow 0,$$

so  $D_y h = A^{-1}$ . □

One of the primary uses of the inverse function theorem is to prove the implicit function theorem.

**Theorem (Implicit Function Theorem):** Let  $f: \mathbb{R}^n \times \mathbb{R}^m \rightarrow \mathbb{R}^m$  be continuously differentiable, and let  $a \in \mathbb{R}^n$ ,  $b \in \mathbb{R}^m$ . Assume

- $f(a, b) = 0$ ;
- the map  $y \mapsto f(a, y)$  defined on  $\mathbb{R}^m \rightarrow \mathbb{R}^m$  is invertible in a neighborhood of  $b$  — i.e.,  $D_b(y \mapsto f(a, y))$  as a linear map has rank  $m$ .

Then, there exists a continuously differentiable function  $g: U \rightarrow V$ , where  $U \in \mathcal{O}_a$  and  $V \in \mathcal{O}_b$  such that  $f(x, g(x)) = 0$  on  $U$ .

Essentially, the theorem says that we can solve  $f(x, y) = 0$  on a neighborhood of  $(a, b)$  by a function only depending on  $x$ . This means that about  $(a, b)$  in the graph  $\Gamma(f)$ , there is a coordinate representation as an  $m$ -manifold given by  $g$ .

*Proof of the Implicit Function Theorem.* Define a function  $F: \mathbb{R}^{n+m} \rightarrow \mathbb{R}^{n+m}$  by

$$F(x, y) = (x, f(x, y)).$$

Since  $f$  is continuously differentiable, this function  $F$  is also continuously differentiable, so we may define  $U \in \mathcal{O}_a$ ,  $V \in \mathcal{O}_b$ , and  $W \in \mathcal{O}_{F(a,b)}$  such that

$$F: U \times V \rightarrow W$$

is continuously differentiable with continuously differentiable inverse (owing to the Inverse Function Theorem), so that  $G = F^{-1} = (G_1, G_2)$  is defined on  $W$ . We see that

$$(x, y) = F(G_1(x, y), f(G_1(x, y), G_2(x, y))),$$

meaning that  $G_1(x, y) = x$ , and  $y = f(x, G_2(x, y))$ . Since at  $b$ ,  $f(a, b) = 0$ , we have that  $g(x) = G_2(x, 0)$  is the desired function. □

## Constructing $C^\infty$ Maps on Manifolds

**Definition:** A function  $f: U \rightarrow \mathbb{R}$ , where  $U \subseteq \mathbb{R}^n$  is open, is called  $C^\infty$  if the partial derivatives of all orders,

$$\frac{\partial^{|\alpha|} f}{\partial x_1^{\alpha_1} \cdots \partial x_n^{\alpha_n}}$$

are continuous. Here,  $\alpha = (\alpha_1, \dots, \alpha_n)$  is a *multi-index*, where the  $\alpha_i$  are positive integers for each  $i$ , and  $|\alpha|$  is defined by  $|\alpha| = \sum_{i=1}^n \alpha_i$ .

We are concerned now with constructing  $C^\infty$  functions on  $C^\infty$ -manifolds.<sup>1</sup> In order to do this, we introduce the bump functions.

<sup>1</sup>A  $C^\infty$  manifold is one where all the transition functions  $\varphi_j \circ \varphi_i^{-1}: \varphi_i(U_i \cap U_j) \rightarrow \varphi_j(U_i \cap U_j)$  are  $C^\infty$  functions.

**Definition:** The *bump function* that is equal to 1 on  $B(0, 1)$  and is zero outside  $U(0, 2)$  is given by

$$h(x) = \begin{cases} e^{-1/x} & x > 0 \\ 0 & x \leq 0 \end{cases}$$

$$b(x) = \frac{h(4 - |x|^2)}{h(4 - |x|^2) + h(|x|^2 - 1)}. \quad (*)$$

**Lemma:** Let  $M$  be a  $C^\infty$  manifold. Let  $U \in \mathcal{O}_p$ , and let  $f: U \rightarrow \mathbb{R}$  be an arbitrary  $C^\infty$  function defined on  $U$ .

Then, there exists  $V \in \mathcal{O}_p$  with  $\bar{V} \subseteq U$ , and a  $C^\infty$  function  $\tilde{f}$  defined on  $M$  such that

$$\tilde{f}(q) = \begin{cases} f(q) & q \in V \\ 0 & q \notin U. \end{cases}$$

*Proof.* Let  $(W, \varphi)$  be a chart centered at  $p$  with  $\varphi(p) = 0$  and  $U(0, 3) \subseteq \varphi(W)$ . Let  $\bar{b} = b \circ \varphi$ , where  $b$  is the bump function defined in  $(*)$ . Then,  $\bar{b}$  is a  $C^\infty$  function on  $W$ , and is 0 outside  $\varphi^{-1}(U(0, 2)) \subseteq W$ .

We define  $\bar{b}$  to be equal to zero on  $W^c$ . Thus, if we define  $V = \varphi^{-1}(U(0, 1))$ , then  $V \in \mathcal{O}_p$ ,  $\bar{V} \subseteq U$ , and  $\bar{b}$  is equal to 1 on  $V$ . Letting

$$\tilde{f}(q) = \begin{cases} \bar{b}(q)f(q) & q \in W \\ 0 & q \notin W, \end{cases}$$

we see that  $\tilde{f}$  satisfies the required property.  $\square$

Given an atlas  $\{(U_i, \varphi_i)\}$ , we want to be able to “glue” functions together by using these charts. A fundamental construction for this purpose is known as a partition of unity.

**Definition:** Let  $X$  be a topological space.

- An open cover  $\{U_i\}_{i \in I}$  is called *locally finite* if, for every  $x \in X$ , there is some  $V \in \mathcal{O}_x$  such that  $V \cap U_i = \emptyset$  for all but finitely many  $i$ .
- Another open cover  $\{V_j\}_{j \in J}$  is called a *refinement* of another open cover  $\{U_i\}_{i \in I}$  if for all  $j \in J$ , there exists some  $i \in I$  such that  $V_j \subseteq U_i$ .
- We say  $X$  is *paracompact* if, for any open cover of  $X$ , there is a locally finite refinement.

**Proposition:** Let  $M$  be a topological manifold. Then, for any open cover  $\{U_i\}_{i \in I}$  of  $M$ , there is a countable, locally finite refinement  $\{V_k\}_{k=1}^\infty$  with the  $\bar{V}_k$  compact. In particular,  $M$  is paracompact.

Additionally, we may select the coordinate maps  $\psi_k: V_k \rightarrow \mathbb{R}^n$  such that  $\psi_k(V_k) = U(0, 3)$ , and  $\{\psi_k^{-1}(U(0, 1))\}_{k=1}^\infty$  is an open cover of  $M$ .

*Proof.* Since  $M$  is a locally Euclidean and second countable, there is a countable basis of pre-compact open sets  $\{O_\ell\}_{\ell=1}^\infty$ . In particular, we may select an exhaustion of  $M$  by pre-compact sets by defining

$$E_1 = O_1$$

$$E_k = O_1 \cup O_2 \cup \cdots \cup O_{\ell_k},$$

where  $\ell_k$  is some sufficiently large index as follows. Since  $\bar{E}_k$  is compact, there is a sufficiently large  $\ell$  such that  $\bar{E}_k \subseteq O_1 \cup \cdots \cup O_\ell$ . Defining  $\ell_{k+1}$  to be the smallest index greater than  $\ell_k$  that satisfy this

property, we define

$$E_{k+1} = O_1 \cup \cdots \cup O_{\ell_{k+1}}.$$

For arbitrary  $k$ , each  $\overline{E_k}$  is compact, and  $\overline{E_k} \subsetneq E_{k+1}$ , and  $\bigcup_{k=1}^{\infty} E_k = M$ . Note that if  $M$  is compact, this process terminates in a finite number of steps.

Now, let  $\{U_i\}_{i \in I}$  be an arbitrary open cover of  $M$ , and fix  $k \geq 1$ . For each  $p \in \overline{E_k} \setminus E_{k-1}$ , select  $i_p$  such that  $p \in U_{i_p}$ , and select a chart  $(V_p, \psi_p)$  about  $p$  that satisfies  $\psi_p(p) = 0$ ,  $\psi_p(V_p) = U(0, 3)$ , and  $V_p \subseteq U_{i_p} \cap (E_{k+1} \setminus \overline{E_{k-2}})$ , where we set  $E_{-1} = E_0 = \emptyset$ . Finally, set  $W_p = \psi_p^{-1}(U(0, 1))$ .

Since  $\overline{E_k} \setminus E_{k-1}$  is compact, we may select a finite number of such  $p$  such that the open sets  $W_p$  cover  $\overline{E_k} \setminus E_{k-1}$ . Applying this process to all  $k$ , and lining up the charts  $(V_p, \psi_p)$  corresponding to the finite number of points  $p$  chosen at each stage, we have the locally finite refinement of  $\{U_i\}_{i \in I}$  with each  $\overline{V_k}$  compact,  $\psi_k(V_k) = U(0, 3)$ , and  $\{\psi_k^{-1}(U(0, 1))\}$  an open cover of  $M$ .  $\square$

**Definition:** Let  $M$  be a  $C^\infty$  manifold. A family  $\{f_k\}_{k=1}^{\infty}$  of at most countably many  $C^\infty$  functions on  $M$  is called a *partition of unity* on  $M$  if it satisfies:

- for each  $k$ ,  $f_k(p) \geq 0$  for all  $p \in M$ , and the family  $\{\text{supp}(f_k)\}_{k=1}^{\infty}$  is locally finite;
- at all points  $p$  on  $M$ ,  $\sum_{k=1}^{\infty} f_k(p) = 1$ .

If  $\{\text{supp}(f_k)\}_{k=1}^{\infty}$  is a refinement of an open cover  $\{U_i\}_{i \in I}$ , then we say the partition of unity is *subordinate* to the open cover.

**Theorem:** Let  $M$  be a  $C^\infty$  manifold, and let  $\{U_i\}_{i \in I}$  be an open cover of  $M$ . Then, there exists a partition of unity  $\{f_k\}_{k=1}^{\infty}$  that is subordinate to  $\{U_i\}_{i \in I}$ .

*Proof.* Let  $\{V_k\}_{k=1}^{\infty}$  be a locally finite refinement of  $\{U_i\}_{i \in I}$  such that the charts  $(V_k, \psi_k)$  have  $\psi_k(V_k) = U(0, 3)$ .

For each  $k$ , using the bump function  $(*)$ , define

$$\widetilde{b}_k(q) = \begin{cases} b \circ \psi_k(q) & q \in V_k \\ 0 & q \notin V_k. \end{cases}$$

Then,  $\widetilde{b}_k$  is a  $C^\infty$  function defined on  $M$ , and since  $\text{supp}(\widetilde{b}_k) \subseteq V_k$ , we may set

$$f = \sum_{k=1}^{\infty} \widetilde{b}_k.$$

The function  $f$  is a  $C^\infty$  function defined on the whole of  $M$ . If we let  $W_k = \psi_k^{-1}(U(0, 1))$ , then since  $\{W_k\}_{k \geq 1}$  is an open cover of  $M$ , for any  $q \in M$ , there exists  $j$  such that  $\widetilde{b}_j(q) = 1$ . Thus,  $f$  never equals 0, so we if we set

$$f_k = \frac{\widetilde{b}_k}{f},$$

the family  $\{f_k\}_{k \geq 1}$  is a partition of unity subordinate to  $\{U_i\}_{i \in I}$ .  $\square$



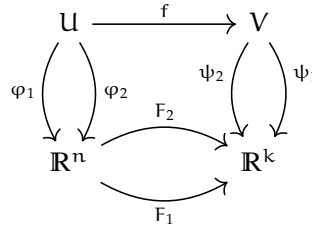
## The Tangent Space

Smooth manifolds are able to be embedded into some Euclidean space,<sup>II</sup> so we start by considering them as such.

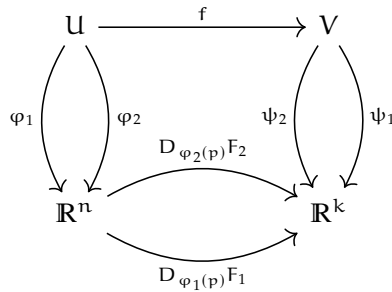
**Definition:** If  $f: M \rightarrow N$  is a smooth map between an  $n$ -dimensional manifold  $M$  and a  $k$ -dimensional manifold  $N$ , the *derivative* of  $f$  at  $p$ , defined for charts  $(U, \varphi)$  and  $(V, \psi)$ , where  $f(U) \subseteq V$ , is defined by  $D_p f = D_{\varphi(p)} F$  for  $F: \mathbb{R}^n \rightarrow \mathbb{R}^k$ , where  $F$  is defined by

$$F = \psi \circ f \circ \varphi^{-1}.$$

**Remark:** This definition is independent of the coordinate representation for a neighborhood of  $p$  in  $M$ .



To see this, notice that by applying differentials, we obtain the following diagram.



Since  $F_1(\varphi_1(p)) = (\psi_1 \circ \psi_2^{-1}) \circ F_2 \circ (\varphi_2 \circ \varphi_1^{-1})(\varphi_1(p))$ , the chain rule gives that

$$D_{\varphi_1(p)} F_1 = D_{F_2(\varphi_2(p))} (\psi_1 \circ \psi_2^{-1}) \circ D_{\varphi_2(p)} F_2 \circ D_{\varphi_1(p)} (\varphi_2 \circ \varphi_1^{-1}).$$

Since the requisite transformations  $\psi_1 \circ \psi_2^{-1}$  and  $\varphi_2 \circ \varphi_1^{-1}$  are diffeomorphisms, we thus obtain that any two such linear transformations are able to be obtained by a series of coordinate changes, meaning that they're independent of the choice of coordinates.

One of the issues with this strategy, though, is that embeddings may carry different properties (though at high enough dimensions, any two embeddings are diffeomorphic to each other). For instance, embeddings  $S^1 \hookrightarrow \mathbb{R}^3$  form the field of knot theory, which is a very intricate field.

As a result, we want to be able to define tangent spaces, derivatives, and the like without having to refer to coordinates. In order to do this, we need to discuss germs of functions.

**Definition:** Let  $g: M \rightarrow N$  map  $p \mapsto g(p)$ . We define an equivalence relation on the space of functions  $f: M \rightarrow N$  with  $f(p) = g(p)$  by taking  $f_1 \sim f_2$  whenever  $f_1 = f_2$  on some open neighborhood  $A \in \mathcal{O}_p$ . The equivalence class  $[g]_p$  is known as the *germ* of  $g$  at  $p$ .

We denote by  $\mathcal{C}_p$  the space of germs of  $C^\infty$  functions  $f: M \rightarrow \mathbb{R}$  at  $p$ .

**Remark:** Often, books will use  $\mathcal{O}_p$  to refer to the space of germs at  $p$ . We will use  $\mathcal{C}_p$  for this purpose though, as we have defined  $\mathcal{O}_p$  to refer to the system of open neighborhoods at  $p$ .

<sup>II</sup>This is actually a very deep theorem.

**Proposition:** The space  $\mathcal{C}_p$  with the operations

- $[g] + [h] = [g + h]$ ;
- $\alpha[g] = [\alpha g]$ ;
- $[g] \cdot [h] = [g \cdot h]$

forms an algebra over  $\mathbb{R}$ .

**Definition:** Let  $W_p$  be the space of germs of smooth maps  $\gamma: \mathbb{R} \rightarrow M$  that send  $0 \mapsto p$ . The *tangent space*  $T_p M$  is defined by  $W_p / \sim$ , where we define the equivalence relation  $[g_1] \sim [g_2]$  for two germs at  $p$   $g_1: M \rightarrow \mathbb{R}$  and  $g_2: M \rightarrow \mathbb{R}$  by

$$(\varphi \circ g_1)'(0) = (\varphi \circ g_2)'(0)$$

for all  $\varphi \in \mathcal{C}_p$ .

**Definition:** The tangent space of a germ  $[f]: M \rightarrow N$  acts as

$$D_p f([ \gamma ]) = [ f \circ \gamma ]$$

for any germ  $[ \gamma ]: \mathbb{R} \rightarrow M$  with  $\gamma(0) = p$ .

**Theorem (Chain Rule):** Let  $[f]: M \rightarrow N$  and  $[g]: N \rightarrow L$  be germs of  $p$  and  $f(p)$  respectively. Then,

$$D_{f(p)} g \circ D_p f = D_p (g \circ f).$$

*Proof.* If  $[ \gamma ]: \mathbb{R} \rightarrow M$  is a germ with  $\gamma(0) = p$ , then

$$\begin{aligned} D_{f(p)} g (D_p f([ \gamma ])) &= D_{f(p)} g ([ f \circ \gamma ]) \\ &= [ g \circ f \circ \gamma ] \\ &= D_p (g \circ f) ([ \gamma ]). \end{aligned}$$

□

**Definition:** Let  $f: M \rightarrow N$  be a smooth map between  $n$ -dimensional manifolds. We say  $x \in M$  is a *regular point* of  $f$  if  $D_x f$  is nonsingular.

The point  $y \in N$  is called a *regular value* if  $f^{-1}(y)$  (set-theoretic inverse) only contains regular points.

## Notations

- A general normed space  $V$  will have its norm denoted by  $\|\cdot\|$ . If  $V = \mathbb{R}^n$ , then we denote the norm by  $|\cdot|$ .
- We denote topological spaces by  $(X, \tau)$ .
- $U(x, r) = \{y \in V \mid \|x - y\| < r\}$ .
- $B(x, r) = \{y \in V \mid \|x - y\| \leq r\}$ .
- $\mathcal{N}_p$ : neighborhood system centered at  $p \in X$ .
- $\mathcal{O}_p$ : system of *open* neighborhoods centered at  $p \in X$ .
- When we say a number  $n$  is positive, we mean that  $n \geq 0$ . Similarly, a sequence  $(a_n)_n$  is decreasing (increasing) if  $a_n \geq a_{n+1}$  ( $a_n \leq a_{n+1}$ ).