

Tree comparison

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Abstract

We introduce a new type of metric comparison which is closely related to the Alexandrov comparison and continuity of optimal transport between regular measures.

1 Introduction

We will denote by $|a - b|_X$ the distance between points a and b in the metric space X .

Tree comparison. Fix a tree T with n vertexes.

Let (a_1, \dots, a_n) be a point array in a metric space X labeled by the vertexes of T . We say that (a_1, \dots, a_n) satisfies the *T-tree comparison* if there is a point array $(\tilde{a}_1, \dots, \tilde{a}_n)$ in the Hilbert space \mathbb{H} such that

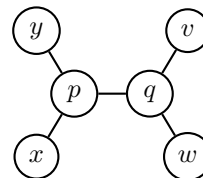
$$|\tilde{a}_i - \tilde{a}_j|_{\mathbb{H}} \geq |a_i - a_j|_X$$

for any i and j and the equality holds if a_i and a_j are adjacent in T .

We say that a metric space X satisfies the *T-tree comparison* if every n -points array in X satisfies the *T-tree comparison*.

Instead of the Hilbert space \mathbb{H} we may use infinite dimensional sphere or infinite dimensional hyperbolic space. In this case we will it defines *spherical* and *hyperbolic* tree comparisons.

Encoding of trees. To encode the labeled tree on the diagram, we will use notation $p/xy(q/vw)$. It means that we choose p as the root; p has two children leafs to x , y and one child q with two children leafs v and w . Taking another root for the same tree, we get different encodings, for eaxample $q/vw(p/xy)$ or $x/(p/y(q/vw))$.



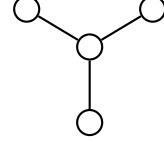
If we do not need the labeling of vertexes, it is sufficient to write the number of leafs in the brackets; this way we can write $2(2)$ instead of $p/xy(q/vw)$ since the root (p) has 2 leafs (x and y) and yet another child (q) which has 2 leafs (v and w). The same tree can be encoded as $(1(2))$ meaning that the root x has no leafs, p has 1 leaf y and one child q with 2 leafs v and w . Every vertex which is not the root and not a leaf corresponds to a pair of brackets in this notation.

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Using the described notation, we could say that a metric space *satisfies the 2(2)-tree comparison*, meaning that it satisfies the tree comparison on the diagram. We could also say “*applying the $p/xy(q/vw)$ -tree comparison...*” meaning that we apply the comparison for these 6 points labeled as on the diagram.

Monopolar trees. A vertex of a tree of degree at least two will be called *pole*.

Recall that *Alexandrov space* with nonnegative curvature is defined as complete length space with curvature bounded below in the sense of Alexandrov; the latter is equivalent to the 3-tree comparison; that is, the comparison for the tripod-tree on the diagram.



Using the introduced notation, a theorem in [1] can be restated the following way: *If a complete length-metric space satisfies 3-tree comparison, then it also satisfies n -tree comparison for every positive integer n ; in other words it satisfies all monopolar tree comparisons.*

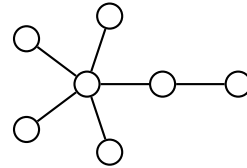
Bipolar trees. Consider the bipolar trees 3(1) and 2(2) shown on the diagram.



The following theorem states that the corresponding comparisons also follow from Alexandrov’s comparison.

1.1. Theorem. *Any Alexandrov space with nonnegative curvature satisfies 3(1)-tree and 2(2)-tree comparisons.*

The 4(1)-tree comparison turns out to be related to the so called *transport continuity property*, briefly TCP. A compact Riemannian manifold M is TCP if for any two regular measures with density functions bounded away from zero and infinity the generalized solution of Monge–Ampère equation provided by optimal transport is a genuine solution.



A necessary condition for TCP was given by Xi-Nan Ma, Neil Trudinger and Xu-Jia Wang in [8]. A key step in the understanding this condition was made by Grégoire Loeper in [7]. The manifolds satisfying this condition will be called *cost-convex*. We define it in the Section 3.

1.2. Theorem. *If a Riemannian manifold satisfies 4(1)-tree comparison then it is cost-convex; moreover it satisfies all bipolar tree comparisons.*

It is straightforward to check that the spherical 4(1)-tree comparison implies the strict cost-convexity, which in turns implies TCP; see [3].

The following question remains open.

1.3. Question. *Is it true that Riemannian manifold is cost-convex if and only if it satisfies 4(1)-tree comparison.*

All tree comparisons. Finally we consider spaces satisfying *all tree comparisons*.

Recall that a map $f: W \rightarrow X$ between metric spaces is called *submetry* if for any $w \in W$ and $r \geq 0$, we have

$$f[B(w, r)_W] = B(f(w), r)_X,$$

where $B(w, r)_W$ denotes the ball with center w and radius r in the space W . In other words submetry is a map which is 1-Lipschitz and 1-co-Lipschitz at the same time. Note that by the definition, any submetry is onto.

1.4. Theorem. *A separable metric space X satisfies all tree comparisons if and only if X is isometric to a target space of submetry defined on a subset of the Hilbert space.*

The following proposition provides a source of examples of spaces satisfying all tree comparisons. For example, since $\mathbb{S}^n = \text{SO}(n)/\text{SO}(n-1)$, any round sphere has this property.

1.5. Proposition. *Suppose G is a compact Lie group with bi-invariant metric, so the action $G \times G \curvearrowright G$ defined by $(h_1, h_2) \cdot g = h_1 \cdot g \cdot h_2^{-1}$ is isometric. Then for any closed subgroup $H < G \times G$, the bi-quotient space $G//H$ satisfies all tree comparisons*

From proposition above and Theorem 1.2, it follows that the bi-quotient space $G//H$ is cost-convex and equivalently CTIL and MTW, see Section 3. This makes it closely related to the result of Young-Heon Kim and Robert McCann in [5].

2 Digressions

On matrix inequality. The comparison for monopolar trees has an algebraic corollary which was first used Urs Lang and Viktor Schroeder in [6] and later rediscovered by Karl-Theodor Sturm in [?]. Namely, given a point array p, x_1, \dots, x_n in a metric space X consider the matrix M with the components

$$m_{i,j} = \frac{1}{2} \cdot (|x_i - p|^2 + |x_j - p|^2 - |x_i - x_j|^2).$$

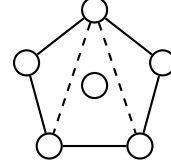
If $p/x_1, \dots, x_n$ -tree comparison holds then

$$\mathbf{s} \cdot M \cdot \mathbf{s}^\top \geq 0$$

for any vector $\mathbf{s} = (s_1, \dots, s_n)$ with nonnegative components.

However, this condition is not sufficient for $p/x_1, \dots, x_n$ -tree comparison with $n \geq 5$. (In general, is not easy to describe tree comparisons using a system of inequalities.)

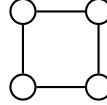
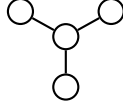
An example can be constructed by perturbing the configuration on the plane as on the diagram — if the diameter of diagram is 1, then increasing the distances between the pairs of points connected by dashed lines by $\varepsilon = 10^{-9}$ and decreasing the distances between the pairs of points connected by solid lines by $\delta = 10^{-6}$ does the job. The obtained metric 6-point metric space satisfies the matrix inequality with center at each point, but does not satisfy the tree comparison with pole at the central point.



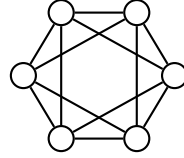
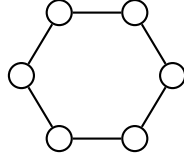
On graph comparison. Analogously to the tree comparison one can define graph comparison for any graph by stating that there is model configuration such that the distance between pairs of adjacent points is at most as big and nonadjacent is at least as big.

2.1. Exercise. *Show that if a graph is a tree then the graph comparison defined above is equivalent to the tree comparison defined at the beginning of the paper.*

Note that nonnegative and nonpositive curvature can be defined using the comparison for following two graphs on 4 vertexes:



By Reshetnyak majorization theorem, the nonpositive curvature could be also defined using the comparison for cycle; for example the 6-cycle, the first graph the following diagram.

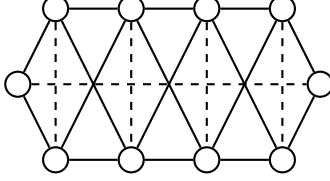


The comparison for the second graph implies that the space is nonnegatively curved. The latter follows since in this graph, a 4-cycle appears as an induced subgraph. On the other hand, this comparison might be stronger and it might be interesting to understand.

(The tree comparison holds for factors spaces of Hilbert space — this was the main motivation to consider this type of comparison. Unfortunately we do not have analogous examples of nonnegatively curved spaces which would guide us to the right definition.)

On colored graph comparison. It is also possible to use graph with (\mp) -colored edges and define comparison by model configuration such that the distances between vertexes adjacent by a $(-)$ -edge does not get larger and by

(+)-edge does not get smaller. For example, the $(2 \cdot n + 2)$ -comparison (which holds in CAT[0] length spaces, see [1]) can be considered as a comparison for the following colored graph, where $(-)$ -edges are marked by solid lines and $(+)$ -edges by dashed lines.



3 Cost-convex manifolds

In this section we review necessary material we learned from [9]; see also the references there in.

Cost-convex functions. Let M be a Riemannian manifold. Consider the *cost function* $\text{cost}: M \times M \rightarrow \mathbb{R}$ defined by

$$\text{cost}(x, y) = \frac{1}{2} \cdot |x - y|_M^2.$$

A function $f: M \rightarrow (-\infty, \infty]$ is called *cost-convex* if for any $p \in M$ such that $f(p) < \infty$ there is $q \in M$ such that

$$f(x) + \text{cost}(q, x) \geq f(p) + \text{cost}(q, p)$$

for any $x \in M$.

If M has nonnegative curvature then any cost-convex function f is (-1) -convex; that is, $f'' \geq -1$, which means that the inequality

$$(f \circ \gamma)'' \geq -1 \tag{1}$$

holds in the barrier sense for any unit speed geodesic γ . On the other hand, the inequality **1** does not imply that f is cost-convex.

Subgradient. Let $f: M \rightarrow (-\infty, \infty]$ be a semiconvex function defined on Riemannian manifold M . Assume $f(p)$ is finite. In this case the differential

$$d_p f: T_p \rightarrow (-\infty, \infty]$$

is defined; it is a convex positive homogeneous function defined on the tangent space T_p .

A tangent vector $v \in T_p M$ is a *subgradient* of f at p , briefly $v \in \underline{\nabla}_p f$ if

$$\langle v, w \rangle \leq d_p f(w)$$

for any $w \in T_p$. Note that the set $\underline{\nabla}_p f$ is a convex subset of T_p .

The subset of tangent vectors $v \in T_p$ such that there is a minimizing geodesic $[p, q]$ in the direction of v with length $|v|$ will be denoted as $\overline{\text{TIL}}_p$. For p, q and v as above, we write $q = \exp_p v$.

3.1. Definition. A Riemannian manifold will be called *cost-convex* if for any point p and any cost-convex function f which is finite at p we have $\nabla_p f \subset \overline{\text{TIL}}_p$ and for $q = \exp_p v$ the inequality

$$\text{cost}(q, p) - \text{cost}(q, x) \geq f(x) - f(p)$$

holds for any $x \in M$.

Note that any cost-convex manifold is nonnegatively curved. According to [3] and Proposition 3.3, if M is TCP then it is cost-convex. The converse is unknown, likely it holds, but there is a slightly stronger version of this condition which implies TCP.

CTIL and MTW. Let us formulate other two conditions on Riemannian manifolds which are together equivalent to the cost-convexity. These two conditions will be used in the proof.

Let M be a Riemannian manifold. The *tangent injectivity locus* at the point $p \in M$ (briefly TIL_p) is defined as the maximal open subset in the tangent space T_p such that for any $v \in \text{TIL}_p$ the geodesic path $\gamma(t) = \exp_p(v \cdot t)$, $t \in [0, 1]$ is minimizing. If the tangent injectivity locus at any point $p \in M$ is convex we say that M satisfies *convexity of tangent injectivity locus* or briefly M is CTIL.

Note that $\overline{\text{TIL}}_p$ defined above is closure of TIL_p in T_p . Therefore, M is CTIL if and only if the set $\overline{\text{TIL}}_p$ is convex for any point $p \in M$.

The second condition is called MTW for Ma–Trudinger–Wang. We will use its reformulation close to the one given by Cédric Villani [9, 2.6]; it can be proved the same way.

Assume $u, v \in T_p$ and $w = \frac{1}{2} \cdot (u + v)$ and $x = \exp_p u$, $y = \exp_p v$ and $q = \exp_p w$. If the three geodesic paths $[p, x]$, $[p, y]$ and $[p, q]$ described by the paths $t \mapsto \exp_p(t \cdot u)$, $t \mapsto \exp_p(t \cdot v)$, $t \mapsto \exp_p(t \cdot w)$ for $t \in [0, 1]$ are minimizing, then $[p, q]$ is called *median* of the hinge $[p_y^x]$. Note that in a CTIL Riemannian manifold, any hinge has a median.

3.2. MTW condition. Assume M be a CTIL Riemannian manifold. Then M is MTW if and only if for a median $[p, q]$ of any hinge $[p_y^x]$ one of the following inequalities

$$\begin{cases} |p - q|_M^2 - |z - q|_M^2 \leq |p - x|_M^2 - |z - x|_M^2, \\ |p - q|_M^2 - |z - q|_M^2 \leq |p - y|_M^2 - |z - y|_M^2. \end{cases}$$

holds for any $z \in M$.

The following statement was proved by Grégoire Loeper in [7], see also [9, Proposition 2.5].

3.3. Proposition. A Riemannian manifold is cost-convex if and only if it is CTIL and MTW.

4 On Kirszbraun's rigidity

In the proof we will use the rigidity case of the generalized Kirszbraun theorem proved by Urs Lang and Viktor Schroeder in [6], see also [1].

4.1. Kirszbraun rigidity theorem. *Let A be an Alexandrov space with non-negative curvature.*

Assume that for two point arrays $p, x_1, \dots, x_n \in A$ and $\tilde{q}, \tilde{x}_1, \dots, \tilde{x}_n \in \mathbb{H}$ we have that

$$|\tilde{q} - \tilde{x}_i| \geq |p - x_i|$$

for any i ,

$$|\tilde{x}_i - \tilde{x}_j| \leq |x_i - x_j|$$

for any pair (i, j) and \tilde{q} lies in the interior of the convex hull \tilde{K} of $\tilde{x}_1, \dots, \tilde{x}_n$.

Then equalities hold in all the inequalities above. Moreover there is an distance preserving map $f: \tilde{K} \rightarrow A$ such that $f(\tilde{x}_i) = x_i$ and $f(\tilde{q}) = p$.

Proof. By the generalized Kirszbraun theorem, there is a short map $f: A \rightarrow \mathbb{H}$ such that $f(x_i) = \tilde{x}_i$. Set $\tilde{p} = f(p)$. By assumptions

$$|\tilde{q} - \tilde{x}_i| \geq |\tilde{p} - \tilde{x}_i|.$$

Since \tilde{q} lies in the interior of K , $\tilde{q} = \tilde{p}$. It follows that the equality

$$|\tilde{q} - \tilde{x}_i| = |p - x_i|.$$

holds for each i .

The remaining part will reduced to the case when A is a Euclidean space; which is left as an exercise.

According to Plaut's theorem (see [1]) there is a dense G-delta set $S \subset A$ of points s such that minimizing geodesics $[s, x_i]$ are uniquely defined and their directions at s lie in a Euclidean subspace E_s of the tangent cone $T_s A$.

Fix $s \in S$ and set $v_i = \log_s x_i$. Note that the gradient exponent

$$\text{gexp}_s: E_s \rightarrow A$$

is a short map and $\text{gexp}_s: v_i \mapsto x_i$ for each i . Note that $|v_i|_{E_s} = |s - x_i|_A$ for any i therefore by triangle inequality

$$|v_i|_{E_s} \geq |p - x_i|_A - |p - s|_A.$$

Passing to the limit map as $s \rightarrow p$ we get (1) a collection of points in a Euclidean space $v_1, \dots, v_n \in E$ such that $|v_i|_E = |x_i - p|_A$ and (2) a short map $g: E \rightarrow A$ such that $g: v_i \rightarrow x_i$ and $g(0) = p$.

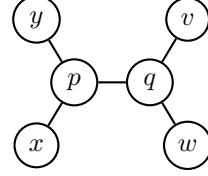
The composition $f \circ g: E \rightarrow \mathbb{H}$ is short and by classical Kirszbraun rigidity it has to be distance preserving on the convex hull \tilde{K}' of v_i . Hence \tilde{K}' is isometric to \tilde{K} and the restriction $g|_{\tilde{K}'}$ is distance preserving. Hence the result. \square

5 Pivotal trees.

Let X be a metric space. A point array (a_1, \dots, a_n) in X together with a choice of a graph with n vertexes labeled by (a_1, \dots, a_n) and a choice of geodesic $[a_i, a_j]$ for every adjacent pair (a_i, a_j) is called *geodesic graph*.

For geodesic trees we will use the same notation as for labeled combinatoric tree in square brackets; for example $[p, xy(q, vw)]$ will denote the geodesic tree with with combinatorics as on the diagram.

Fix a geodesic tree $T = [p_1/x_1 \dots x_k(p_2/x_{k+1} \dots x_n)]$; that is, T has two poles p_1, p_2 and each of the remaining vertexes are adjacent either to p_1 or p_2 — the vertexes x_1, \dots, x_k are connected to p_1 and x_{k+1}, \dots, x_n to p_2 .



Assume X is a nonnegatively curved Alexandrov space; in particular the angle is defined for any geodesic hinge.

A geodesic tree $\tilde{T} = [\tilde{p}_1/\tilde{x}_1 \dots \tilde{x}_k(\tilde{p}_2/\tilde{x}_{k+1} \dots \tilde{x}_n)]$ in the Hilbert space \mathbb{H} will be called *pivotal tree* for T if

- (i) $|\tilde{p}_1 - \tilde{p}_2|_{\mathbb{H}} = |p_1 - p_2|_X$,
- (ii) $|\tilde{p}_i - \tilde{x}_j|_{\mathbb{H}} = |p_i - p_j|_X$ for any edge $[p_i, x_j]$ in T and
- (iii) $\angle[\tilde{p}_j \tilde{x}_k]_{\mathbb{H}} = \angle[\tilde{p}_j \tilde{x}_k]_X$ for any hinge $[p_j \tilde{x}_k] = ([p_j, x_k], [p_j, p_i])$ in T .

5.1. Rigidity lemma. *Let X be a nonnegatively curved Alexandrov space and $T = [p_1/x_1 \dots x_k(p_2/x_{k+1} \dots x_n)]$ be geodesic tree in X . Suppose $\tilde{T} = [\tilde{p}_1/\tilde{x}_1 \dots \tilde{x}_k(\tilde{p}_2/\tilde{x}_{k+1} \dots \tilde{x}_n)]$ is a pivotal tree for T . Assume that*

$$|\tilde{x}_i - \tilde{x}_j|_{\mathbb{H}} \leq |x_i - x_j|_X \quad \text{②}$$

for any pair (i, j) and the convex hull \tilde{K} of $\{\tilde{x}_1, \dots, \tilde{x}_n\}$ intersects the line thru \tilde{p}_1 and \tilde{p}_2 . Then the equality holds in ② for each pair (i, j) .

Proof. Let \tilde{z} be a point on the line $(\tilde{p}_1, \tilde{p}_2)$. Assume that \tilde{z} lies on the half-line from \tilde{p}_1 to \tilde{p}_2 ; otherwise swap the labels of \tilde{p}_1 and \tilde{p}_2 .

Denote by ζ the direction of geodesic $[p_1, p_2]$ at p_1 . Set

$$z = \text{gexp}_{p_1}(|\tilde{z} - \tilde{p}_1| \cdot \zeta),$$

where gexp_{p_1} denotes the gradient exponent at p_1 ; see [2]. By comparison, we have

$$|x_i - z|_X \leq |\tilde{x}_i - \tilde{z}|_{\mathbb{H}^2}$$

for any i .

It remains to apply Kirszbraun rigidity theorem (4.1). □

Recall that X is a nonnegatively curved Alexandrov space.

Assume $[\tilde{p}_1/\tilde{x}_1 \dots \tilde{x}_k(\tilde{p}_2/\tilde{x}_{k+1} \dots \tilde{x}_n)]$ is a pivotal tree in \mathbb{H} for the geodesic tree $[p_1/x_1 \dots x_k(p_2/x_{k+1} \dots x_n)]$ in X . Note that by angle comparison, for any i and j we have

$$|\tilde{x}_i - \tilde{p}_j|_{\mathbb{H}} \geq |x_i - p_j|_X.$$

It follows that the configuration $\tilde{p}_1, \tilde{p}_2, \tilde{x}_1, \dots, \tilde{x}_n \in \mathbb{H}$ satisfies the tree comparison (see Section 1) if

$$|\tilde{x}_i - \tilde{x}_j|_{\mathbb{H}} \geq |x_i - x_j|_X \quad \textcircled{3}$$

for all pairs (i, j) .

Denote by ξ_i the direction of the half-plane containing \tilde{x}_i with the boundary line $(\tilde{p}_1, \tilde{p}_2)$. The direction ξ_i lies in the unit sphere normal to the line $(\tilde{p}_1, \tilde{p}_2)$; we may assume that the dimension of the sphere is $n - 1$.

Note that up to a motion of \mathbb{H} , a pivotal configuration is completely described by the angles $\angle(\xi_i, \xi_j)$. Moreover, the distance $|\tilde{x}_i - \tilde{x}_j|_{\mathbb{H}}$ is determined by $\angle(\xi_i, \xi_j)$ and the function $\angle(\xi_i, \xi_j) \mapsto |\tilde{x}_i - \tilde{x}_j|_{\mathbb{H}}$ is nondecreasing.

Let us denote by $\alpha_{i,j}$ the minimal angle $\angle(\xi_i, \xi_j)$ in a pivotal configuration such that $\textcircled{3}$ holds. Note that the inequality $\textcircled{3}$ is equivalent to

$$\angle(\xi_i, \xi_j) \geq \alpha_{i,j}.$$

5.2. Corollary. *For any geodesic bipolar tree in a nonnegatively curved Alexandrov space the following conditions hold:*

(a) *For any pair i and j , we have*

$$\alpha_{i,j} \leq \pi.$$

(b) *For any triple i, j and k , we have*

$$\alpha_{i,j} + \alpha_{j,k} + \alpha_{k,i} \leq 2 \cdot \pi.$$

In other words, if X is a nonnegatively curved Alexandrov space then

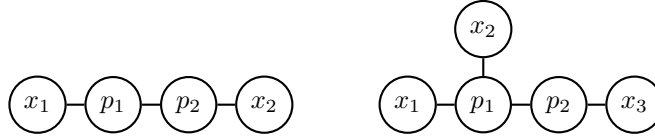
(a) *For any broken geodesic line $[p_1/x_1(p_2/x_2)]$ in X there is a pivotal tree $[\tilde{p}_1/\tilde{x}_1(\tilde{p}_2/\tilde{x}_2)]$ such that*

$$|\tilde{x}_1 - \tilde{x}_2|_{\mathbb{H}} \geq |x_1 - x_2|_X.$$

(b) *For any $[p_1/x_1x_2(p_2/x_3)]$ in X , there is a pivotal tree $[\tilde{p}_1/\tilde{x}_1\tilde{x}_2(\tilde{p}_2/\tilde{x}_3)]$ such that*

$$|\tilde{x}_i - \tilde{x}_j|_{\mathbb{H}} \geq |x_i - x_j|_X.$$

for all i and j .



Proof; (a). Consider the pivotal tree $[\tilde{p}_1/\tilde{x}_1(\tilde{p}_2/\tilde{x}_2)]$ (which is a polygonal path) with $\angle(\xi_1, \xi_2) = \pi$. Note that the points $\tilde{p}_1, \tilde{x}_1, \tilde{p}_2, \tilde{x}_2$ are coplanar and the

points \tilde{x}_1 and \tilde{x}_2 lie on the opposite sides from the line $(\tilde{p}_1, \tilde{p}_2)$. It remains to apply the rigidity lemma.

(b). By (a), we can assume that

$$\alpha_{1,3} + \alpha_{2,3} > \pi. \quad \textcircled{4}$$

Consider the pivotal tree $[\tilde{p}_1/\tilde{x}_1\tilde{x}_2(\tilde{p}_2/\tilde{x}_3)]$ which lies in a 3-dimensional subspace in such a way that the points \tilde{x}_1 and \tilde{x}_2 lie on the opposite sides from the plane containing $\tilde{p}_1, \tilde{p}_2, \tilde{x}_3$, and

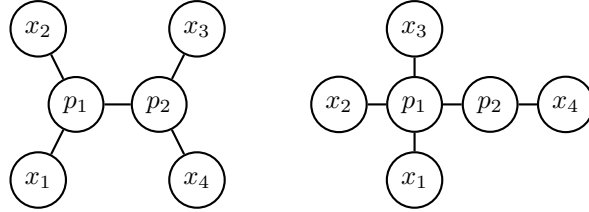
$$\angle(\tilde{\xi}_1, \tilde{\xi}_3) = \alpha_{1,3}, \quad \angle(\tilde{\xi}_2, \tilde{\xi}_3) = \alpha_{2,3}.$$

By $\textcircled{4}$, the convex hull \tilde{K} of $\{\tilde{x}_1, \tilde{x}_2, \tilde{x}_3\}$ intersects the line $(\tilde{p}_1, \tilde{p}_2)$. It remains to apply the rigidity lemma. \square

Note that (a) and (b) implies that nonnegatively curved Alexandrov space satisfies 1(1)-tree and 2(1)-tree comparisons. However, 1(1)-tree comparison follows directly from the triangle inequality.

6 2(2)-tree and 3(1)-tree comparisons

The following theorem generalizes Theorem 1.1. It says in particular, that the comparisons for the following two trees holds in nonnegatively Alexandrov spaces.



6.1. Theorem. *Let X be an nonnegatively curved Alexandrov space. Then for any geodesic 2(2)-tree (or 3(1)-tree) there is a pivotal tree satisfying the corresponding tree comparison.*

In particular, any nonnegatively curved Alexandrov space satisfies the 2(2)-tree comparison as well as 3(1)-tree comparison.

The proofs in the two cases are nearly identical; they differ only by the choice made in the first line.

Proof. Fix a geodesic tree $[p_1/x_1x_2(p_2/x_3x_4)]$ or $[p_1/x_1x_2x_3(p_2/x_4)]$. Define the values $\{\alpha_{i,j}\}$ for each pair i, j as in the previous section.

Recall that p_1 and p_2 are the poles of the tree and each of remaining vertexes x_1, x_2, x_3, x_4 are connected to one of the poles.

Fix a smooth monotonic function $\varphi: \mathbb{R} \rightarrow \mathbb{R}$ such that $\varphi(x) = 0$ if $x \geq 0$ and $\varphi(x) > 0$ if $x < 0$. Consider a configuration of 4 points $\tilde{\xi}_1, \tilde{\xi}_2, \tilde{\xi}_3, \tilde{\xi}_4$ in \mathbb{S}^3 which minimize the *energy*

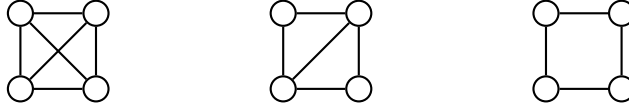
$$E(\tilde{\xi}_1, \tilde{\xi}_2, \tilde{\xi}_3, \tilde{\xi}_4) = \sum_{i < j} \varphi(\angle(\tilde{\xi}_i, \tilde{\xi}_j) - \alpha_{i,j}).$$

Consider the geodesic graph Γ with 4 vertexes $\tilde{\xi}_1, \tilde{\xi}_2, \tilde{\xi}_3, \tilde{\xi}_4$ in \mathbb{S}^3 , where $\tilde{\xi}_i$ is adjacent to $\tilde{\xi}_j$ if $\angle(\tilde{\xi}_i, \tilde{\xi}_j) < \alpha_{i,j}$. If the comparison does not hold then Γ is not empty.

Note that a vertex of Γ can not lie in an open hemisphere with all its adjacent vertexes. Indeed, if it would be the case then we could move this vertex increasing the distances to all its adjacent vertexes. Along this move the energy decreases which is not possible.

Note that by Corollary 5.2, degree of any vertex is at least 2. Indeed existence of a vertex of degree 1 contradicts 5.2a and existence of a vertex of degree 0 contradicts 5.2b.

Therefore the graph Γ is isomorphic to one the following three graphs.



The 6-edge case (that is, the complete graph with 4 vertexes) can not appear by the rigidity lemma (see 5.1).

To do the remaining two cases, note that since the energy is minimal, the angle between the edges at every vertex of degree 2 of Γ has to be π . That is, the pair of edges at such vertex forms a geodesic.

Consider the 5-edge graph on the diagram. By the observation above the both triangles in the graph run along one equator. The latter contradicts Corollary 5.2b.

For the 4-edge graph (that is, for 4-cycle) by the same observation we have 4 points lie on the equator; moving the even pair to the north pole and odd pair to the south pole will decrease the energy, a contradiction. \square

7 4(1)-tree comparison

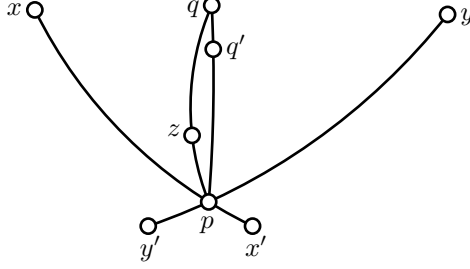
In this section we will prove the first part of Theorem 1.2. Note that according to Proposition 3.3, it is sufficient to show that if a Riemannian manifold M satisfies 4(1)-tree comparison then it is CTIL and MTW. These two conditions will be proved separately.

7.1. Proposition. *Any cost-convex Riemannian manifold is CTIL.*

Proof. Assume the contrary; that is, there is $p \in M$ and $u, v \in \text{TIL}_p$ such that $w = \frac{1}{2} \cdot (u + v) \notin \text{TIL}_p$.

Let τ be the maximal value such that the geodesic $\gamma(t) = \exp_p(w \cdot t)$ is a length-minimizing on $[0, \tau]$. Set $w' = \tau \cdot w$. Note that $\tau < 1$ and $w' \in \partial \text{TIL}_p$.

Set $q = \exp_p w'$. By general position argument, we can assume that there are at least two minimizing geodesics connecting p to q ; see [4]. That is, there is $w'' \in \partial \text{TIL}_p$ such that $w'' \neq w'$ and $\exp_p w' = \exp_p w''$.



Fix small positive real numbers δ, ε and ζ . Consider the points

$$\begin{aligned} q' &= q'(\varepsilon) = \exp_p(1 - \varepsilon) \cdot w', & z &= z(\zeta) = \exp_p(\zeta \cdot w''), \\ x &= \exp_p u, & x' &= x'(\delta) = \exp_p(-\delta \cdot u), \\ y &= \exp_p v, & y' &= y'(\delta) = \exp_p(-\delta \cdot v). \end{aligned}$$

We will show that for some choice of δ, ε and ζ the $p/xx'yy'(q'/z)$ -tree comparison does not hold.

Assume contrary, that is, given any small positive numbers δ, ε and ζ , there is a point array $\tilde{p}, \tilde{x}, \tilde{x}'(\delta), \tilde{y}, \tilde{y}'(\delta), \tilde{q}'(\varepsilon), \tilde{z}(\zeta) \in \mathbb{H}$ as in the definition of T -tree comparison; that is, the distances between the points in this array are at least as big as the distances of corresponding points in M and the equality holds for the pair adjacent in $p/xx'yy'(q'/z)$.

Since δ is small, we can assume that p lies on a necessary unique minimizing geodesic $[x, x']_M$. Hence

$$|x - x'|_M = |x - p|_M + |p - x'|_M.$$

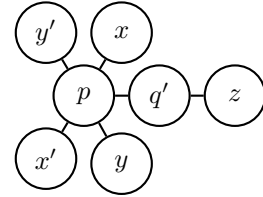
By comparison

$$\begin{aligned} |\tilde{x} - \tilde{x}'|_{\mathbb{H}} &\geq |x - x'|_M, \\ |\tilde{x} - \tilde{p}|_{\mathbb{H}} &= |x - p|_M, \\ |\tilde{x}' - \tilde{p}|_{\mathbb{H}} &= |x' - p|_M. \end{aligned}$$

By triangle inequality,

$$|\tilde{x} - \tilde{x}'|_{\mathbb{H}} = |\tilde{x} - \tilde{p}|_{\mathbb{H}} + |\tilde{x}' - \tilde{p}|_{\mathbb{H}};$$

that is, $\tilde{p} \in [\tilde{x}, \tilde{x}']_{\mathbb{H}}$. The same way we see that $\tilde{p} \in [\tilde{y}, \tilde{y}']_{\mathbb{H}}$.



Fix ε and ζ . Note that as $\delta \rightarrow 0$ we have

$$\begin{aligned} \tilde{x}' &\rightarrow \tilde{p}, & \tilde{y}' &\rightarrow \tilde{p}. \\ \angle[\tilde{p}_{\tilde{y}}^{\tilde{x}'}] &\rightarrow \angle[p_y^x], & \angle[\tilde{p}_{\tilde{x}}^{\tilde{y}'}] &\rightarrow \angle[p_x^y], \\ \angle[\tilde{p}_{\tilde{q}'}^{\tilde{x}'}] &\rightarrow \angle[p_{q'}^x], & \angle[\tilde{p}_{\tilde{q}'}^{\tilde{y}'}] &\rightarrow \angle[p_{q'}^y], \end{aligned}$$

It follows that

$$\angle[\tilde{p}_{\tilde{y}}^{\tilde{x}}] \rightarrow \angle[p_y^x], \quad \angle[\tilde{p}_{\tilde{q}'}^{\tilde{x}}] \rightarrow \angle[p_{q'}^x], \quad \angle[\tilde{p}_{\tilde{q}'}^{\tilde{y}}] \rightarrow \angle[p_{q'}^y].$$

Therefore, passing to a partial limit as $\delta \rightarrow 0$, we get a configuration of 5 points $\tilde{p}, \tilde{x}, \tilde{y}, \tilde{q}' = \tilde{q}'(\varepsilon), \tilde{z} = \tilde{z}(\zeta)$ such that

$$\angle[\tilde{p}_{\tilde{y}}^{\tilde{x}}] = \angle[p_y^x], \quad \angle[\tilde{p}_{\tilde{q}'}^{\tilde{y}}] = \angle[p_{q'}^y], \quad \angle[\tilde{p}_{\tilde{q}'}^{\tilde{x}}] = \angle[p_{q'}^x].$$

In other words, the map sending 4 points $0, u, v, w' \in T_p$ to $\tilde{p}, \tilde{x}, \tilde{y}, \tilde{q} \in \mathbb{H}$ correspondingly is distance preserving.

Note that $q' \rightarrow q$ as $\varepsilon \rightarrow 0$. Therefore, in the limit, we get a configuration $\tilde{p}, \tilde{x}, \tilde{y}, \tilde{q}', \tilde{z} = \tilde{z}(\zeta)$ such that in addition we have

$$\begin{aligned} |\tilde{q}' - \tilde{z}| &= |q - z|, & |\tilde{p} - \tilde{z}| &\geq |p - z|, \\ |\tilde{x} - \tilde{z}| &\geq |x - p|, & |\tilde{y} - \tilde{z}| &\geq |y - z| \end{aligned}$$

Since $w'' \neq w'$, for small values ζ the last three inequalities imply

$$|\tilde{q}' - \tilde{z}| > |q - z|,$$

a contradiction.

7.2. Proposition. *Any cost-convex CTIL Riemannian manifold is MTW.*

Proof. Fix a hinge $[p_y^x]$ in M ; from above M is CTIL. Therefore $[p_y^x]$ has a median; denote it by $[p, q]$. For $\delta > 0$, define $x' = x'(\delta)$ and $y' = y'(\delta)$ as above.

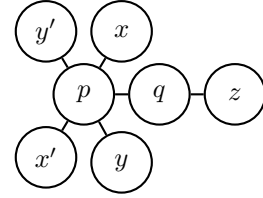
Without loss of generality we can assume that $x, y \in \exp_p(TL_p)$. If δ is small, the latter implies that p lies on unique minimizing geodesics $[x, x']$ and $[y, y']$.

Consider the limit case of $p/xx'yy'(q/z)$ -comparison as $\delta \rightarrow 0$. It gives a configuration of 5 points $\tilde{p}, \tilde{q}, \tilde{x}, \tilde{y}$ and \tilde{z} such that

$$\angle[\tilde{p}_{\tilde{y}}^{\tilde{x}}] = \angle[p_y^x],$$

\tilde{q} is the midpoint of $[\tilde{x}, \tilde{y}]$. In particular,

$$\begin{aligned} 2 \cdot |\tilde{z} - \tilde{q}|_{\mathbb{H}}^2 + |\tilde{q} - \tilde{x}|_{\mathbb{H}}^2 + |\tilde{q} - \tilde{y}|_{\mathbb{H}}^2 &= |\tilde{z} - \tilde{x}|_{\mathbb{H}}^2 + |\tilde{z} - \tilde{y}|_{\mathbb{H}}^2, \\ 2 \cdot |\tilde{p} - \tilde{q}|_{\mathbb{H}}^2 + |\tilde{q} - \tilde{x}|_{\mathbb{H}}^2 + |\tilde{q} - \tilde{y}|_{\mathbb{H}}^2 &= |\tilde{p} - \tilde{x}|_{\mathbb{H}}^2 + |\tilde{p} - \tilde{y}|_{\mathbb{H}}^2, \end{aligned}$$



By the comparison,

$$\begin{aligned}
|\tilde{z} - \tilde{x}|_{\mathbb{H}} &\geq |z - x|_M, & |\tilde{z} - \tilde{y}|_{\mathbb{H}} &\geq |z - y|_M, \\
|\tilde{p} - \tilde{x}|_{\mathbb{H}} &\geq |p - x|_M, & |\tilde{p} - \tilde{y}|_{\mathbb{H}} &\geq |p - y|_M, \\
|\tilde{q} - \tilde{x}|_{\mathbb{H}} &= |q - x|_M, & |\tilde{q} - \tilde{y}|_{\mathbb{H}} &= |q - y|_M, \\
|\tilde{q} - \tilde{z}|_{\mathbb{H}} &= |q - z|_M, & |\tilde{q} - \tilde{p}|_{\mathbb{H}} &= |q - p|_M,
\end{aligned}$$

Therefore

$$\begin{aligned}
2 \cdot |z - q|_M^2 + |q - x|_M^2 + |q - y|_M^2 &\geq |z - x|_M^2 + |z - y|_M^2, \\
2 \cdot |p - q|_M^2 + |q - x|_M^2 + |q - y|_M^2 &\leq |p - x|_M^2 + |p - y|_M^2.
\end{aligned}$$

Hence the condition in 3.2 follows. \square

8 Pull-back convexity

In this section reformulate 4(1)-tree comparison using convexity of certain function on tangent space and use it to prove the second part of Theorem 1.2.

Recall that for a continuous function f defined on metric space we write $f'' \leq \lambda$ if for any unit-speed geodesic γ the function

$$t \mapsto f \circ \gamma(t) - \lambda \cdot \frac{t^2}{2}$$

is a concave real-to-real function.

8.1. Proposition. *If a Riemannian manifold M satisfies 4(1)-tree comparison then it is CTIL and for any $p, q \in M$, we have $f'' \leq 1$, where f is the function $f: \text{TIL}_p \rightarrow \mathbb{R}$ defined by*

$$f(v) = \frac{1}{2} \cdot \text{dist}_q^2 \circ \exp_p(v).$$

The converse also holds; moreover, if $f'' \leq 1$ for any p, q in a CTIL Riemannian manifold M , then M satisfies all bipolar tree comparisons; that is, the $m(n)$ -tree comparison holds for any m and n .

Proof. Note that 4(1)-tree comparison implies 3-tree comparison. Hence M has nonnegative sectional curvature.

Fix $u, v \in \text{TIL}_p$ and $w \in [u, v]$. It is sufficient to show that there is a function $g: \text{T}_p \rightarrow \mathbb{R}$ such that

$$g'' = 1, \quad g(w) = f(w), \quad g(u) \geq f(u) \quad \text{and} \quad g(v) \geq f(v).$$

Fix small $\varepsilon > 0$ and set

$$\begin{aligned}
x &= \exp_p u, & y &= \exp_p v, & z &= \exp_p w, \\
x' &= \exp_p(-\varepsilon \cdot u), & y' &= \exp_p(-\varepsilon \cdot v)
\end{aligned}$$

Apply the $p/xyx'y'(z/q)$ comparison and pass to the limit as $\varepsilon \rightarrow 0$. We obtain a configuration of points $\tilde{p}, \tilde{x}, \tilde{y}, \tilde{z}, \tilde{q} \in \mathbb{H}$, satisfying corresponding comparisons and in addition

$$\angle[\tilde{p}\tilde{x}\tilde{y}] = \angle[p^x_y], \quad \angle[\tilde{p}\tilde{x}\tilde{z}] = \angle[p^x_z], \quad \angle[\tilde{p}\tilde{z}\tilde{y}] = \angle[p^z_y].$$

In particular, from above and Toponogov comparison, we have

$$\begin{aligned} |\tilde{x} - \tilde{y}|_{\mathbb{H}} &= |u - v|_{T_p}, & |\tilde{z} - \tilde{y}|_{\mathbb{H}} &= |w - v|_{T_p}, & |\tilde{x} - \tilde{z}|_{\mathbb{H}} &= |u - w|_{T_p}, \\ |\tilde{q} - \tilde{z}|_{\mathbb{H}} &= |q - z|_M, & |\tilde{q} - \tilde{x}|_{\mathbb{H}} &\geq |q - x|_M, & |\tilde{q} - \tilde{y}|_{\mathbb{H}} &\geq |q - y|_M. \end{aligned}$$

In particular, there is a distance-preserving map $T_p \rightarrow \mathbb{H}$ such that $u \mapsto \tilde{x}$, $v \mapsto \tilde{y}$, $w \mapsto \tilde{z}$ and $0 \mapsto \tilde{p}$. Further, we identify T_p and a subset of \mathbb{H} using this map.

Consider the function $g := \frac{1}{2} \cdot \text{dist}_{\tilde{q}}^2$. Note that $g'' = 1$ and

$$\begin{aligned} g(w) &= \frac{1}{2} \cdot |\tilde{q} - \tilde{z}|^2 = \frac{1}{2} |q - z|^2 = f(w), \\ g(u) &= \frac{1}{2} \cdot |\tilde{q} - \tilde{x}|^2 \geq \frac{1}{2} |q - x|^2 = f(u), \\ g(v) &= \frac{1}{2} \cdot |\tilde{q} - \tilde{y}|^2 \geq \frac{1}{2} |q - y|^2 \geq f(u). \end{aligned}$$

Hence the statement.

Converse. Fix points p and q in M ; set $\tilde{q} = \log_p q \in T_p$. Note that

$$f \leq \tilde{f}, \tag{5}$$

where

$$\tilde{f}(v) = \frac{1}{2} \cdot |v - \tilde{q}|_{T_p}^2.$$

Further note that the inequality 5 is equivalent to the Toponogov comparison for all hinges $[p^x_q]$ in M . It follows that M has nonnegative sectional curvature.

Now fix a bipolar geodesic tree $[p/x_1 \dots x_n(q/y_1 \dots y_m)]$ in M . Set

$$\tilde{p} = 0 = \log_p p, \quad \tilde{q} = \log_p q, \quad \text{and} \quad \tilde{x}_i = \log_p x_i$$

for each i .

Consider the linear map $\psi_1: T_q \rightarrow T_p$ such that for any smooth function h

$$\psi_1: \nabla_q h \mapsto \nabla_{\tilde{q}}(h \circ \exp_p).$$

Since sectional curvature of M is nonnegative, the restriction $\exp_p|_{T_{\text{IL}_p}}$ is short and therefore so is ψ_1 .

In particular there is a linear map $\psi_2: T_q \rightarrow T_p$ such that, the map $\iota: T_q \rightarrow T_p \oplus T_p$ defined by

$$\iota: v \mapsto \psi_1(v) \oplus \psi_2(v)$$

is distance preserving.

Further set

$$h_i = \frac{1}{2} \cdot \text{dist}_{y_i}^2 \quad g_i = h_i \circ \exp_p|_{\text{TIL}_p} \quad \tilde{y}_i = \tilde{q} - \iota(\nabla_q h_i).$$

By construction

$$|\tilde{y}_i - \tilde{q}|_{\text{T}_p \oplus \text{T}_p} = |y_i - q|_M.$$

At the point \tilde{q} the restriction functions $\tilde{g}_i = \frac{1}{2} \cdot \text{dist}_{\tilde{y}_i}^2|_{\text{T}_p \oplus 0}$ and the function g_i have the same value and gradient. Since $g_i'' \leq 1$ and $\tilde{g}_i'' = 1$, we get $\tilde{g}_i \geq g_i$. The latter implies

$$|\tilde{y}_i - \tilde{p}|_{\text{T}_p \oplus \text{T}_p} \geq |y_i - p|_M \quad \text{and} \quad |\tilde{y}_i - \tilde{x}_j|_{\text{T}_p \oplus \text{T}_p} \geq |y_i - x_j|_M.$$

for any i and j .

Since $\text{T}_p \oplus \text{T}_p$ admits an isometric embedding into the Hilbert space, we get the needed configuration. \square

Note that we almost did not use smoothness of manifold M . In fact the Plaut's theorem makes possible to extend the proof above to complete length spaces; that is, we get the following corollary from the proof.

8.2. Corollary. *If a complete length space X satisfies 4(1)-tree comparison then it satisfies any bipolar tree comparisons.*

For the cost-convex manifolds we have somewhat weaker statement.

8.3. Proposition. *A Riemannian manifold M is cost-convex if and only if it is CTIL and for any $p, q \in M$ the function $h: \text{TIL}_p \rightarrow \mathbb{R}$ defined by*

$$h(v) = \frac{1}{2} \cdot |v|^2 - \frac{1}{2} \cdot \text{dist}_q^2 \circ \exp_p(v)$$

has convex sub level sets.

Proof; "only if" part. If M is cost-convex, then Proposition 7.2 it is CTIL.

Fix $p \in M$ and $u, v \in \text{TIL}_p$ and set $x = \exp_p u$ and $y = \exp_p v$.

Consider the cost-convex function

$$f(s) = \min\{\text{cost}(x, p) - \text{cost}(x, s), \text{cost}(y, p) - \text{cost}(y, s)\}.$$

Note that the subgradient of $\nabla_p f$ is the line segment $[u, v]$. From the definition of costconvex manifold (3.1) it follows that if u and v lie in sub level set of h then so is the segment $[u, v]$.

"If" part. Follows from the propositions 7.2 and 7.2. \square

9 All tree comparisons

Proof of Theorem 1.3. The “if” part is left as an exercise; let us prove the “only if” part.

Fix a point array a_1, \dots, a_n in X . Consider the complete graph K_n with $\{1, \dots, n\}$ as the set of vertexes.

Let $\hat{K}_n \rightarrow K_n$ be the universal covering of the complete graph K_n . Denote by \hat{V} the set of vertexes of \hat{K}_n ; given a vertex $\hat{v} \in \hat{V}$ denote by v the corresponding vertex of K_n .

Applying the tree comparison for finite subtrees in \hat{K}_n and passing to a partial limit, we get the following:

(*) There is a map $f: \hat{V} \rightarrow \mathbb{H}$ such that

$$|f(\hat{v}) - f(\hat{w})|_{\mathbb{H}} \geq |a_v - a_w|_X$$

for any two vertexes $\hat{v}, \hat{w} \in \hat{V}$ and the equality holds if (\hat{v}, \hat{w}) is an edge in \hat{K}_n .

This finish the proof if X is finite.

Since X is separable, it contains a countable everywhere dense set $\{a_1, a_2, \dots\}$. Applying the statement above for $X_n = \{a_1, \dots, a_n\}$, we get a submetry from $Y_n = f_n(\hat{V}_n) \subset \mathbb{H}$ to X_n .

It remains to pass to the ulralimit Y of the subspaces Y_n . Clearly Y admits an isometric embedding into \mathbb{H} and it admits submetry on $Y \rightarrow X$. Hence the statement follows. \square

9.1. Proposition. *Suppose G be a compact Lie group with bi-invariant metric, so the action $G \times G \curvearrowright G$ defined by $(h_1, h_2) \cdot g = h_1 \cdot g \cdot h_2^{-1}$ is isometric. Then for any closed subgroup $H < G \times G$, the bi-quotient space $G//H$ satisfies multipolar comparison.*

We present a proof suggested by Alexander Lytchak, it is simplified version of the construction of Chuu-Lian Terng and Gudlaugur Thorbergsson given in [10, Section 4].

Proof of Proposition 1.4. Denote by G^n the direct product of n copies of G . Consider the map $\varphi_n: G^n \rightarrow G//H$ defined by

$$\varphi_n: (\alpha_1, \dots, \alpha_n) \mapsto [\alpha_1 \cdots \alpha_n]_H,$$

where $[x]_H$ denotes the H -orbit of x in G .

Note that φ_n is a quotient map for the action of $H \times G^{n-1}$ on G^n defined by

$$(\beta_0, \dots, \beta_n) \cdot (\alpha_1, \dots, \alpha_n) = (\gamma_1 \cdot \alpha_1 \cdot \beta_1^{-1}, \beta_1 \cdot \alpha_2 \cdot \beta_2^{-1}, \dots, \beta_{n-1} \cdot \alpha_n \cdot \beta_n^{-1}),$$

where $\beta_i \in G$ and $(\beta_0, \beta_n) \in H < G \times G$.

Denote by ρ_n the product metric on G^n rescaled with factor \sqrt{n} . Note that the quotient $(G^n, \rho_n)/(H \times G^{n-1})$ is isometric to $G//H = (G, \rho_1)//H$.

As $n \rightarrow \infty$ the curvature of (G^n, ρ_n) converges to zero and its injectivity radius goes to infinity. Therefore passing to the ultra-limit of G^n as $n \rightarrow \infty$ we get the Hilbert space. It remains to observe that the limit action has the required property. \square

10 Final remarks

The following problem discussed in [1, 7.1] was one of the original motivations to study the tree comparison.

10.1. Problem. *Which finite metric spaces admit isometric embeddings into some Alexandrov spaces with nonnegative curvature.*

The problem is still open. According to [1, 4.1], the $(n-1)$ -tree comparison provides a necessary condition for the problem n -point metric spaces. This condition is sufficient for the 4-point metric spaces. It might be still sufficient for 5-point metric spaces, but not for 6-point metric spaces.

The corresponding example of 6-point metric space was constructed by Sergei Ivanov, see [1]. Theorem 6.1, provides a source for such examples — any 6-point metric space which satisfy all 5-tree comparisons, but does not satisfy 2(2)-tree comparison provide an example. This class of examples includes the example of Sergei Ivanov — in the notations of [1, 7.1] it does not satisfies the comparison for the tree $y/az(q/xb)$.

By Theorem 6.1 and a theorem in [1], 5-tree and 2(2)-tree comparisons provide a necessary condition for 6-point metric spaces. We expect that these conditions are sufficient



Here an other candidate for a sufficient condition.

10.2. Question. *Assume F is a finite metric space which satisfies all tree comparisons. Is it true that F is isometric to a subset of Alexandrov space with nonpositive curvature?*

Note that even for finite metric space the all tree comparison has to be checked for infinite set of trees since one point of the space may be used as a label for several vertexes in the tree.

There is a chance that for 5-point and 6-point metric spaces, this condition is also necessary. Since there are nonnegatively curved Riemannian manifolds which are not cost-convex, Theorem 1.2 implies that this condition can not be necessary for 7-point metric spaces.

For any metric space X with an isometric group action $G \curvearrowright X$ with closed orbits the quotient map $X \rightarrow X/G$ is a submetry. In particular, by Theorem 1.3, if $G \curvearrowright \mathbb{H}$ is an isometric action with closed orbits on the Hilbert space, then the quotient space \mathbb{H}/G satisfies all tree comparisons.

10.3. Question. *Assume X is a metric space satisfying all tree comparisons. Is it always possible to construct an isometric group action with closed orbits on the Hilbert space $G \curvearrowright \mathbb{H}$ such that X is isometric to a subset in \mathbb{H}/G ?*

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