

Differential Geometry

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Course	MSM423 Differential Geometry
Instructor	Dr. Saikat Chatterjee
Prerequisites	MAT413 Analysis on Manifolds
Learning Outcomes	<ul style="list-style-type: none"> • Understanding the classical interpretation of various curvatures of a surface and their relation to geodesics. • Understanding the local and global geometry of smooth manifolds and smooth vector bundles.
Syllabus	<ul style="list-style-type: none"> • Gauss curvature, Gauss curvature formula in terms of first and second fundamental forms. Intrinsic property of the Gauss curvature. (6) • Covariant derivative of a vector field along a curve; Relation between covariant derivative and total curvature of a curve; A geodesic as a curve with vanishing covariant derivative. (6) • Manifolds: Definition, examples, Tangent vector space at a point, Basis of the tangent vector space. Smooth functions on a manifold, maps between Manifolds. Differential of a map. (6) • Sub-manifolds; Regular value theorem. Lie groups, examples; Submersion, Immersion and Embeddings. (6) • Smooth vector bundles, smooth sections, Dual bundles, existence of local sections. (5) • Tangent bundles; Smooth vector fields; Lie bracket of smooth vector fields; Co-tangent bundles; Differential 1-forms. (5) • Differential p-forms. Orientation. Exterior derivative. Closed and exact forms. Integration of a p-form on a p-dim sub manifold. Stokes theorem. (6)

Definition 1 (Curves):

Let I be an open interval in \mathbb{R} . A smooth parametrized curve in \mathbb{R}^n is a smooth map $\gamma : I \rightarrow \mathbb{R}^n$.

The image $\gamma(I) \subseteq \mathbb{R}^n$ is called trace of the curve γ .

Example: $\gamma_1, \gamma_2 : \mathbb{R} \rightarrow \mathbb{R}^2$, defined as $\gamma_1(t) = (\cos(t), \sin(t))$ and $\gamma_2(t) = (\sin(3t), \cos(3t))$ have the same trace, but they are different curves.

Observe: Consider any circle in \mathbb{R}^2 , it is the set of all points in \mathbb{R}^2 satisfying a certain quadratic equation.

It can also be viewed as a trace of some curve.

Definition 2 (Level Set):

Let $U \subseteq \mathbb{R}^n$ be any open set, and $f : U \rightarrow \mathbb{R}$ be any function.

Then for a given constant $c \in \mathbb{R}$, the level set is defined as

$$L_c(f) := \{X \in U \mid f(X) = c\} \subseteq U \subseteq \mathbb{R}^n$$

Example: Let $U = \mathbb{R}^2$, and $f(x, y) = x^2 + y^2$, then

$L_0(f) = (0, 0)$, a point,

$L_1(f) = S^1 = \{(x, y) \in \mathbb{R}^2 \mid x^2 + y^2 = 1\}$, a circle in \mathbb{R}^2 ,

$L_{-1}(f) = \emptyset$.

Definition 3 (Graph):

Let A and B be any sets. Let $f : A \rightarrow B$ be a function, then the graph of f is the function $G_f : A \rightarrow A \times B$, given by

$$G_f(x) = (x, f(x)) \in A \times B$$

Note: Notice that a graph is also a curve, and if f is a smooth function, then G_f is a smooth curve.

Theorem 1 (Implicit Function Theorem (2D Case)):

Let $F : \mathbb{R}^2 \rightarrow \mathbb{R}$ be a continuous function defining a curve $F(x, y) = c$.

Let (x_0, y_0) be a point on the curve.

- If $\frac{\partial F}{\partial x}(x_0, y_0) \neq 0$, then there exists a neighborhood around (x_0, y_0) where we can write $y = f(x)$ for a real valued function $f(x)$. That is, the curve $F(x, y) = c$ behaves like the graph of $y = f(x)$ in that neighborhood.
- If $\frac{\partial F}{\partial y}(x_0, y_0) \neq 0$, then there exists a neighborhood around (x_0, y_0) where we can write $x = g(y)$ for a real valued function $g(y)$. That is, the curve $F(x, y) = c$ behaves like the graph of $x = g(y)$ in that neighborhood.

Example: Consider $S^1 = L_1(x^2 + y^2) = \{(x, y) \mid x^2 + y^2 = 1\}$

Here, $F(x, y) = x^2 + y^2$, and $\frac{\partial F}{\partial x} = 2x \neq 0$ when $x \neq 0$.

Therefore, for any point (x_0, y_0) in S^1 , where such that $x_0 \neq 0$, there exists a neighborhood in which $x = g(y)$.

Note: It is worthwhile to notice that a graph is always a curve. Implicit function theorem gives a condition on when a curve (level set in particular) can be seen as the graph of a curve.

Lecture 02: Curves and Surfaces

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Observe: Consider the level set of $F(x, y) = x^2 + y^2$, $L_1(f) = S^1$. As seen before, since $\frac{\partial F}{\partial x} = 2x \neq 0$ when $x \neq 0$, for any point (x_0, y_0) in S^1 , where $x_0 \neq 0$, we obtain a neighborhood in S^1 such that the curve (level set) can be written as a graph of a function $y = g(x)$.

Let S^{1+} denote $(\mathbb{R} \times \mathbb{R}^+) \cap S^1$, the upper half of the unit circle. Now, for a point in S^{1+} , the corresponding $g(x)$ is $\sqrt{1 - x^2}$.

Now the graph of g , say G_g is a function from $(-1, 1)$ to S^{1+} , and we can easily talk about continuity, differentiability of G_g .

However, notice that G_g is a surjection, and an inverse exists, $G_g^{-1} : S^{1+} \rightarrow (-1, 1)$.

To talk about continuity of G_g^{-1} we need to define a topology on S^{1+} , and the subspace topology is the most obvious choice.

This G_g^{-1} happens to be continuous when we consider the subspace topology on S^{1+} . Further, open subsets of S^{1+} homeomorphic to the open subsets of \mathbb{R} , that means that this topological space is locally homeomorphic to \mathbb{R} , but the same does not extend to the whole space, that is, there is no homeomorphism from S^{1+} to \mathbb{R} .

Note: Notice that we cannot talk about differentiability of S^{1+} in the above immediately, as differentiability requires some sort of vector space structure.

Example: Consider $S_3^1 := \{(x, y, z) \in \mathbb{R}^3 \mid x^2 + y^2 + z^2 = 1\}$

Doing the same analysis on this set as before using the Implicit function theorem, we obtain that after removing the appropriate critical points, and giving a topology to whatever remains, we obtain patches obtain open sets in whatever remains that are homeomorphic to open subsets of \mathbb{R}^2 , hence the topological subspace obtained after removing the critical points is locally homeomorphic to \mathbb{R}^2 .

Definition 4 (Tangent to a smooth curve at a point):

Let I be an open interval in \mathbb{R} , and $\gamma : I \rightarrow \mathbb{R}^n$ be a smooth curve given by $\gamma(t) = (x_1(t), x_2(t), \dots, x_n(t))$, then for a point $t \in I$, the tangent of the curve at t is defined as

$$\gamma'(t) = (x_1'(t), x_2'(t), \dots, x_n'(t))$$

Definition 5 (Regular Curve):

A smooth curve $\gamma : I \rightarrow \mathbb{R}^n$ is said to be a regular curve if $\gamma'(t) \neq 0 \forall t \in I$.

Definition 6 (Diffeomorphism):

Let A and B be two manifolds, and a function $f : A \rightarrow B$ is said to be a diffeomorphism if f is bijective, differentiable, and the inverse $f^{-1} : B \rightarrow A$ is differentiable as well.

Note: In this course, by smooth, we mean a C^∞ function.

Definition 7 (Reparametrization of a Curve):

Let J, I be open intervals of \mathbb{R} , let $\gamma : I \rightarrow \mathbb{R}^n$ be a curve, and let $\phi : J \rightarrow I$ be a diffeomorphism. Then $\beta = \gamma \circ \phi : J \rightarrow \mathbb{R}^n$ is a curve on J called as reparametrization of γ .

Observe: If β is a reparametrization of γ , and the setup is as above, then $\beta(s) = \gamma \circ \phi(s)$ for each $s \in J$. Then

$$\beta'(s) = \gamma'(\phi(s)) \cdot \phi'(s)$$

Now, ϕ is a diffeomorphism and $(\phi \circ \phi^{-1})' = 1$ and by chain rule, we have $(\phi^{-1})' = \frac{1}{\phi'}$. And since $(\phi^{-1})'$ exists throughout I , ϕ' cannot be 0 on J , hence $\gamma'(s) \neq 0$.

Hence if γ is regular, then so is β , hence regularity is preserved under a diffeomorphism.

Definition 8 (Arc Length of a Curve):

Let $\gamma : I \rightarrow \mathbb{R}^n$ be a regular parametrized curve. For fixed $t_1, t_2 \in I$, the arc length between t_1 and t_2 is given by

$$\begin{aligned} L_\gamma(t_1, t_2) &= \int_{t_1}^{t_2} \|\gamma'(t)\| dt \\ &= \int_{t_1}^{t_2} \sqrt{(x'_1(t))^2 + (x'_2(t))^2 + \cdots + (x'_n(t))^2} dt \end{aligned}$$

References

- [1] M. P. Do Carmo. *Differential Geometry of Curves and Surfaces*. 2nd ed. Dover Publications, 2016.
- [2] J. M. Lee. *Introduction to Smooth Manifolds*. 2nd ed. Springer, 2013.
- [3] L. W. Tu. *An Introduction to Manifolds*. 2nd ed. Springer, 2011.