

Lecture 4

Volume Form

Def The volume form $\text{Vol}_g \in \Omega^n(M^n)$ induced by a Riemannian Metric on an orientable manifold is given in local coordinates $(x_1, \dots, x_n)$ by

$$\text{Vol}_g = \sqrt{\det(g_{ij})} dx_1 \wedge \dots \wedge dx_n$$

The (total) volume of (M^n, g) is $\text{Vol}(M, g) = \int_M \text{Vol}_g$.

Example $B_1 = \{x^2 + y^2 < 1\}$

$$\text{Area} = \text{Volume} \left(B_1, \frac{4}{(1-x^2-y^2)^2} (dx^2 + dy^2) \right)$$

Use Polar coordinates! $\iint \frac{4}{(1-x^2-y^2)^2} = \infty!$

Exercise

$$\text{Area} = \text{Volume} \left(B_1, \frac{4}{(1+x^2+y^2)^2} (dx^2 + dy^2) \right) = 2\pi$$

Distance the distance between p, q wrt Metric g is

$$\cancel{dist_g(p)} \quad d(p, q) = \inf \{ L_g(\gamma) \mid \gamma: [a, b] \rightarrow M \text{ piecewise smooth} \}$$

$$\begin{aligned} \gamma(a) &= p \\ \gamma(b) &= q \end{aligned}$$

Prop (M^n, g) is A Metric space.
(The Metric topology agrees with Manifold topology)

Proof $d(p, q) = d(q, p)$ is immediate
 $d(p, q) \geq 0$ is immediate

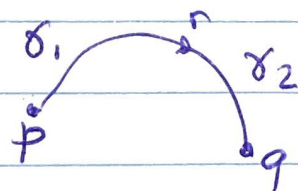
Triangle inequality : $\gamma_1: [a, b] \rightarrow M$ $\gamma_2: [a', b'] \rightarrow M$
with $\gamma_1(b) = \gamma_2(a')$

Define concatenation $\gamma_1 \# \gamma_2: [0, b+b'-a-a'] \rightarrow M$ by

$$\gamma_1 \# \gamma_2(t) = \begin{cases} \gamma_1(t+a) & \text{for } 0 \leq t \leq b-a \\ \gamma_2(t+a-b+a') & \text{for } b-a \leq t \leq b+b'-a-a' \end{cases}$$

Thus $\gamma_1 \# \gamma_2$ is A curve with length $L_g(\gamma_1) + L_g(\gamma_2)$.

Given $p, q, r \in M$, For Any ϵ we can choose γ_1, γ_2 such that



$$L_g(\gamma_1) < d(p, r) + \epsilon \text{ AND } L_g(\gamma_2) < d(r, q) + \epsilon$$

$$d(p, q) \leq L_g(\gamma_1 \# \gamma_2) = L_g(\gamma_1) + L_g(\gamma_2) < d(p, r) + d(r, q) + 2\epsilon$$

Let $\epsilon \rightarrow 0$.

We still Need to check $d(p, q) = 0$ only when $p = q$
(This can be done using chart)
to say that y is outside A Ball around x)

divergence of vector field

Def Suppose M is Riemannian manifold
with Riemannian volume Form μ . Suppose X is A vector
field. The divergence of X is A Function $\text{div} X$
defined by

$$d(\iota_X \mu) = (\text{div} X) \mu.$$

where the inner product $\iota_X \mu$ is $(n-1)$ -Form defined
by

$$(\iota_X \mu)(Y_1, \dots, Y_{n-1}) = \mu(X, Y_1, \dots, Y_{n-1})$$

By Stokes theorem:

$$\int_M (\text{div} X) \mu = \int_{\partial M} \iota_X \mu.$$

in particular if $\partial M = \emptyset$ then $\int_M (\text{div} X) \mu = 0.$

Product Manifolds

$$M = M_1 \times M_2 \quad TM = TM_1 \oplus TM_2$$

IF (M_i, g_i) are Riemannian Manifolds then

$M = M_1 \times M_2$ can be Endowed with product Metric $g_1 \oplus g_2$
i.e

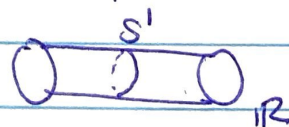
$$\forall p = (p_1, p_2) \in M \quad g_p(v, w) = (g_1)_{p_1}(v_1, w_1) + (g_2)_{p_2}(v_2, w_2) \quad \forall \begin{matrix} v = (v_1, v_2) \\ w = (w_1, w_2) \\ \in T_p M. \end{matrix}$$

Given a positive Function $f: M_1 \rightarrow \mathbb{R}$ one may endow M with A "warped product" metric

$$g^f = g_1 + f g_2$$

Example on $\mathbb{R} \times S^1 \ni (r, \theta)$ we have the product (cylinder)

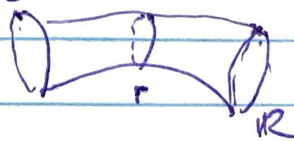
$$\text{Metric } dr^2 + d\theta^2$$



OR The warped product Metric

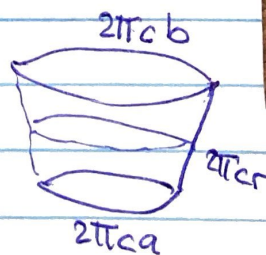
$$dr^2 + f(r)^2 d\theta^2$$

where the circle $S^1_{r_0} = \{(r_0, \theta) \mid \theta \in S^1\}$ has length $2\pi f(r_0)$



Setting $f(r) = cr$ for some $c > 0$

we have A cone Metric $dr^2 + c^2 r^2 d\theta^2$ on $[a, b] \times S^1$



Letting $a \rightarrow 0$ and $b \rightarrow \infty$ we get

$$g^c = dr^2 + c^2 r^2 d\theta^2 \text{ on } (0, \infty) \times S^1 \cong \mathbb{R}^2 \setminus \{0\}$$

Question For what values of $c > 0$ does g^c extend smoothly to $\mathbb{R}^2$?

Answer Around $0 \in \mathbb{R}^2$ we have the diffeomorphism

$$\phi(r, \theta) = (x = r \cos \theta, y = r \sin \theta) \text{ for } r > 0$$

$$\text{and so } \begin{pmatrix} dx \\ dy \end{pmatrix} = \begin{pmatrix} \cos \theta & -\sin \theta \\ \sin \theta & \cos \theta \end{pmatrix} \begin{pmatrix} dr \\ r d\theta \end{pmatrix}$$

rotation with angle θ

$$\leadsto \begin{pmatrix} dr \\ r d\theta \end{pmatrix} = \begin{pmatrix} \cos \theta & \sin \theta \\ -\sin \theta & \cos \theta \end{pmatrix} \begin{pmatrix} dx \\ dy \end{pmatrix}$$

angle $(-\theta)$ rotation.

$$\Rightarrow dr = \cos \theta dx + \sin \theta dy = \frac{x}{\sqrt{x^2 + y^2}} dx + \frac{y}{\sqrt{x^2 + y^2}} dy$$

$$d\theta = \frac{-y}{x^2 + y^2} dx + \frac{x}{x^2 + y^2} dy$$

$$\Rightarrow dr^2 = \frac{1}{x^2 + y^2} (x^2 dx^2 + 2xy dx dy + y^2 dy^2)$$

$$d\theta^2 = \frac{1}{(x^2 + y^2)^2} (y^2 dx^2 - 2xy dx dy + x^2 dy^2)$$

$$\hookrightarrow (\phi^{-1})^* g^c = \underset{\substack{\uparrow \\ \text{compute}}}{\frac{x^2 + c^2 y^2}{x^2 + y^2} dx^2 + \frac{2xy(1 - c^2)}{x^2 + y^2} dx dy + \frac{y^2 + c^2 x^2}{x^2 + y^2} dy^2}$$