

Ex. 3. Claim: A_i commutes with ∇ .

Proof: Step 1 of the hint: We use the Koszul formula to expand the LHS. There are two contributions:

$$\begin{aligned} \mathcal{L}g(\nabla_x JY, Z) &= X(g(JY, Z)) + JY g(X, Z) - Z g(X, JY) \\ &\quad - g([JY, X], Z) - g([X, Z], JY) - g([JY, Z], X) \end{aligned}$$

$$\mathcal{L}g(J\nabla_x Y, Z) = \mathcal{L}g(\nabla_x Y, JZ)$$

g is J -invariant

$$\begin{aligned} &= X(g(Y, JZ)) + Y g(X, JZ) - JZ g(X, Y) \\ &\quad - g([Y, X], JZ) - g([X, JZ], Y) - g([Y, JZ], X) \end{aligned}$$

We expand the RHS using the formula for exterior derivative:

$$\begin{aligned} d\omega(X, Y, Z) &= X(\omega(Y, Z)) - Y\omega(X, Z) + Z\omega(X, Y) \\ &\quad - \omega([X, Y], Z) + \omega([X, Z], Y) - \omega([Y, Z], X) \end{aligned}$$

$$\begin{aligned} &= -Xg(Y, JZ) + Yg(X, JZ) - Zg(X, JY) \\ &\quad + g([X, Y], JZ) - g([X, Z], JY) + g([Y, Z], JX) \end{aligned}$$

def of $g(X, Y) = \omega(X, Y)$

$$\begin{aligned} -d\omega(X, JY, JZ) &= -Xg(JY, Z) + JYg(X, Z) - JZg(X, Y) \\ &\quad + g([X, JY], Z) - g([X, Z], Y) - g([JY, Z], JX) \end{aligned}$$

Now we watch up both sides and see what's left:

That should be precisely $-g(\omega(Y, Z), JX)$. (do in class).

Step 2 of the hint

If the $\pm i$ -eigenspaces of J are closed under $[-, \cdot]$, then a computation similar to the one in the lecture (for an almost product str.) shows $N \equiv 0$.

Once we pass from TM to $TM \otimes \mathbb{C}$, any $X \in T(TM)$ can be written $X = X_+ + X_-$ with X_{\pm} a section of the $\pm i$ -eigenspace of J (which we called $T^{1,0}$, $T^{0,1}$ in the lecture)

$$\begin{aligned} \text{Then: } N(Y_+, Z_+) &= [Y_+, Z_+] + J \underbrace{[JY_+, Z_+]}_{i[Y_+, Z_+]} + J \underbrace{[Y_+, JZ_+]}_{i[Y_+, Z_+]} \\ &\quad - \underbrace{[JY_+, JZ_+]}_{i^2[Y_+, Z_+]} \\ &= 2[Y_+, Z_+] + 2i \underbrace{J[Y_+, Z_+]}_{i\text{-eigenspace}} = 0. \end{aligned}$$

Similarly for $N(Y_-, Z_-) = 0$.

On the other hand,

$$\begin{aligned} N(Y_+, Z_-) &= [Y_+, Z_-] + J([JY_+, Z_-]) + J[Y_+, JZ_-] \\ &\quad - [JY_+, JZ_-] \\ &= [Y_+, Z_-] + J(i[Y_+, Z_-] - i[Y_+, Z_-]) \\ &\quad - [Y_+, Z_-] = 0. \end{aligned}$$

Similarly, $N(Y_-, Z_+) = 0$.

$\Rightarrow N \equiv 0$.

Step 3 of the list

ω_i symplectic $\Rightarrow d\omega_i = 0$.

lecture showed that the $\pm i$ -eigenspaces of A_i are closed under $\langle \cdot, \cdot \rangle$, so by step 2 $N \equiv 0$.

by step 1, $g((\nabla_x J)Y, Z) = 0 \quad \forall x, Y, Z$.

by non-degeneracy of g , $\nabla J \equiv 0$. □

Claim: ω_i is ∇ -compatible.

Proof: $L_x \omega(Y, Z) = -L_x g(JY, Z)$

$$\stackrel{\nabla \text{ is } g\text{-compatible}}{=} -g(\nabla_x JY, Z) - g(JY, \nabla_x Z)$$

$$\stackrel{\nabla J = 0}{=} -g(J\nabla_x Y, Z) - g(JY, \nabla_x Z)$$

$$\stackrel{\text{def of } \omega}{=} \omega(\nabla_x Y, Z) + \omega(Y, \nabla_x Z).$$

(here $\omega := \omega_i$ and $J := A_i$). □

Ex. 4. $\mathfrak{nil}_3 \times \mathbb{R}$ spanned by e_1, \dots, e_3 with $[e_1, e_2] = e_3$

let $\alpha_1, \dots, \alpha_4$ be the dual basis ($\alpha_i(e_j) = \delta_{ij}$) and extend them to left-inv. 1-forms on $\mathfrak{nil}_3 \times \mathbb{R}$

just mean $d_g \alpha = \alpha \quad \forall g \in \mathfrak{nil}_3 \times \mathbb{R}$
 $l_g =$ left-multiplication by g .

is the group of upper uni-triangular matrices $\left\{ \begin{pmatrix} 1 & x & z \\ & 1 & y \\ & & 1 \end{pmatrix} \mid \begin{matrix} x, y, z \\ \neq \\ \in \mathbb{R} \end{matrix} \right\}$

was not part of the exercise

formula for exterior derivative says

$$d\alpha_i(X, Y) = X(\alpha_i(Y)) - Y(\alpha_i(X)) - \alpha_i([X, Y])$$

~~made~~ mistake here last time where I forgot $L_X, L_Y \leadsto$ correct in class

let X_1, \dots, X_4 be the left-inv. vector fields associated to e_1, \dots, e_4 .

Evaluating $d\alpha$ on X_1, \dots, X_4 we get:

$$d\alpha_i(X_j, X_k) = X_j \alpha_i(X_k) - X_k \alpha_i(X_j) - \alpha_i([X_j, X_k])$$

now $\alpha_i(X_k)(g) = \alpha_i(d l_g(e_k)) = \overset{\text{dual to } e_i}{(l_g \alpha_i)}(e_k) = \delta_{ik}$

is constant, so $X_j \alpha_i(X_k) = 0$. Similarly $X_k \alpha_i(X_j) = 0$.

$$\Rightarrow d\alpha_i(X_j, X_k) = -\alpha_i([X_j, X_k]) = -\alpha_i([e_j, e_k]).$$

left-inv. form

vector dual to e_i

From the relations in $\mathfrak{nil}_3 \times \mathbb{R}$ we thus find

$$d\alpha_3 = -\alpha_1 \wedge \alpha_2 = \alpha_2 \wedge \alpha_1$$

$$\text{and } d\alpha_i = 0 \quad \forall i \neq 3.$$

α, β, γ are closed:

$$\begin{aligned} d\alpha &= d(\alpha_3 \wedge \alpha_2) + d(\alpha_1 \wedge \alpha_4) \\ &= d\alpha_3 \wedge \alpha_2 - \alpha_3 \wedge d\alpha_2 + d\alpha_1 \wedge \alpha_4 - \alpha_1 \wedge d\alpha_4 \\ &= \alpha_2 \wedge \alpha_2 \wedge \alpha_2 = 0. \end{aligned}$$

similarly for β and γ .

α, β, γ are non-degenerate

$$\alpha \wedge \alpha = - \iota \alpha_1 \wedge \alpha_2 \wedge \alpha_3 \wedge \alpha_4 \neq 0 \text{ nowhere zero.}$$

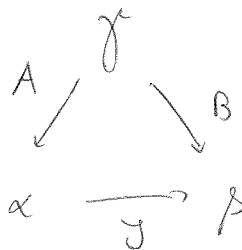
(at every point of $\mathbb{R}P^3 \times \mathbb{R}$ $\alpha_1, \dots, \alpha_4$ are covectors forming a basis for the cotangent space, so $\alpha_2 \wedge \dots \wedge \alpha_4$ is nowhere zero).

α, β, γ are left-invariant

hence pullback commute with \wedge .

α, β, γ define a hyperkähler structure for this we must

calculate the recursion operators:



E.g. find A s.t. $\gamma(A-, -) \stackrel{!}{=} \alpha$.

$$\begin{aligned} \rightarrow Ae_1 &= e_2 \\ Ae_2 &= e_1 \\ Ae_3 &= -e_4 \\ Ae_4 &= -e_3 \end{aligned} \quad \Rightarrow \quad A = \begin{pmatrix} 0 & 1 & & \\ 1 & 0 & & \\ & & 0 & -1 \\ & & -1 & 0 \end{pmatrix}$$

$$\gamma(B-, -) \stackrel{!}{=} \beta \quad \Rightarrow \quad \begin{aligned} Be_1 &= e_1 \\ Be_2 &= -e_2 \\ Be_3 &= e_3 \\ Be_4 &= -e_4 \end{aligned} \quad \Rightarrow \quad B = \begin{pmatrix} 1 & & & \\ & -1 & & \\ & & 1 & \\ & & & -1 \end{pmatrix}$$

$$\gamma \cdot \alpha(J-, -) \stackrel{!}{=} \beta \quad \Rightarrow \quad \begin{aligned} Je_1 &= e_2 \\ Je_2 &= -e_1 \\ Je_3 &= -e_4 \\ Je_4 &= e_3 \end{aligned} \quad \Rightarrow \quad J = \begin{pmatrix} 0 & 1 & & \\ 1 & 0 & & \\ & & 0 & 1 \\ & & -1 & 0 \end{pmatrix}$$

We see that $A^2 = B^2 = \text{id} = -J^2$.

\square