## The Geometry of $2 \times 2$ Matrices

William M. Goldman<br>Department of Mathematics, University of Maryland, College Park, MD 20742

Spring 2009 MD-DC-VA Sectional Meeting Mathematical Association of America University of Mary Washington<br>Fredericksburg, Virginia 18 April 2009

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Algebraicizing geometry

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Tiling the hyperbolic plane by ideal triangles with dual tree


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Algebraicizing geometry through symmetry


Library of Congress

Felix Klein's Erlangen Program: A geometry is the study of objects invariant under some group of symmetries. (1872)

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■ Can an abstract space locally support a geometry?
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■ Can an abstract space locally support a geometry?
■ A torus is a rectangle with sides identified by translations.
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■ Can an abstract space locally support a geometry?
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■ Every point has a Euclidean coordinate neighborhood.

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A sphere is not Euclidean

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■ No local Euclidean geometry structure on the sphere.

## A sphere is not Euclidean

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A sphere is not Euclidean

■ No local Euclidean geometry structure on the sphere.
■ No metrically accurate atlas of the world!

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A sphere is not Euclidean

■ No local Euclidean geometry structure on the sphere.
■ No metrically accurate atlas of the world!
■ For example a cube has the topology of a sphere, but its geometry fails to be Euclidean at its 8 vertices.

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The geometry on the space of geometries

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■ Geometric objects and transformations represented by scalars, vectors and matrices, all arising from symmetry.

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■ Geometric objects and transformations represented by scalars, vectors and matrices, all arising from symmetry.
■ Example: Triangles in the plane are classified (up to congruence) by the lengths of their sides:

$$
\begin{aligned}
& 0<a, b, c \\
& a<b+c \\
& b<c+a \\
& c<a+b
\end{aligned}
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The geometry on the space of geometries

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The geometry on the space of geometries

■ In general the space of equivalence classes of a geometry has an interesting geometry of its own.

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\section*{Euclidean structures on torus}

■ Every Euclidean structure on a torus arises as the quotient of the plane by a lattice of translations, for example
\[
(x, y) \longmapsto(x+m, y+n)
\]
where \(m, n \in \mathbb{Z}\).
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■ The translations identify the fundamental parallelogram.

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■ Identify \(\mathbb{R}^{2}\) with \(\mathbb{C}\). Up to equivalence the lattice is generated by complex numbers 1 and \(\tau=x+i y\), where \(y>0\).

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Moduli space
■ The space of structures \(\longleftrightarrow\) with equivalence classes of \(\tau \in H^{2}\) by \(\mathrm{SL}(2, \mathbb{Z})\) - natural hyperbolic geometry.
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Moduli space
■ The space of structures $\longleftrightarrow$ with equivalence classes of $\tau \in H^{2}$ by $\operatorname{SL}(2, \mathbb{Z})$ - natural hyperbolic geometry.
■ Changing basis $\longleftrightarrow$ action of the group $\operatorname{SL}(2, \mathbb{Z})$ of integral $2 \times 2$ matrices by

$$
\tau \longmapsto \frac{a \tau+b}{c \tau+d} \text { where } a, b, c, d \in \mathbb{Z} .
$$



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## Euclidean geometry

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■ Euclidean geometry concerns properties of space invariant under rigid motions.
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■ For example: distance, parallelism, angle, area and volume.

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■ Points in Euclidean space are represented by vectors; Euclidean distance is defined by:

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d(\vec{a}, \vec{b}):=\|\vec{a}-\vec{b}\|,
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## Euclidean geometry

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d(\vec{a}, \vec{b}):=\|\vec{a}-\vec{b}\|,
$$

the size of the translation taking $\vec{b}$ to $\vec{a}$ :

$$
p \longmapsto p+(\vec{b}-\vec{a})
$$

## The Geometry of $2 \times 2$ Matrices <br> Spherical geometry

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\section*{Spherical geometry}

■ Points on the sphere \(S^{2}\) are unit vectors in \(\mathbb{R}^{3}\).
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## Spherical geometry

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Metric circles on the sphere of radius $R$.

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Metric circles on the sphere of radius $R$.


■ Spherical circle of radius $r$ has circumference

$$
C(R)=2 \pi R \sin (r / R)
$$

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## Geodesics (straight lines) on the sphere

## The Geometry of $2 \times 2$ <br> Matrices <br> William M. <br> Goldman <br> Geodesics (straight lines) on the sphere <br> - A great circle on $S^{2}$ is the intersection with a plane thru the origin.

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Geodesics (straight lines) on the sphere
- A great circle on \(S^{2}\) is the intersection with a plane thru the origin.
■ These are circles of maximum diameter
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\section*{Tilings by triangles}

■ Example: Take a triangle \(\triangle\) and try to tile the plane by reflecting \(\triangle\) repeatedly in its sides.

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\section*{Tilings by triangles}

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■ If the angles \(\alpha, \beta, \gamma\) in \(\triangle\) are \(\pi / n\), where \(n>0\) is an integer, then the triangles tile the plane.

Tilings by triangles

■ Example: Take a triangle \(\triangle\) and try to tile the plane by reflecting \(\triangle\) repeatedly in its sides.
■ If the angles \(\alpha, \beta, \gamma\) in \(\triangle\) are \(\pi / n\), where \(n>0\) is an integer, then the triangles tile the plane.
■ If the angles are \(\pi / p, \pi / q, \pi / r\) then the three reflections \(R_{1}, R_{2}, R_{3}\) generate a group with presentation with defining relations
\[
\begin{aligned}
\left(R_{1}\right)^{2} & =\left(R_{2}\right)^{2}=\left(R_{3}\right)^{2}= \\
\left(R_{1} R_{2}\right)^{p} & =\left(R_{2} R_{3}\right)^{q}=\left(R_{3} R_{1}\right)^{r}=1
\end{aligned}
\]
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\section*{What can go wrong}


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A tiling of the Euclidean plane by equilateral ( \(\pi / 3-\) ) triangles

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## Trichotomy

■ If $\alpha+\beta+\gamma=\pi$, then a Euclidean triangle exists with these angles.

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## Trichotomy

■ If $\alpha+\beta+\gamma=\pi$, then a Euclidean triangle exists with these angles.

■ Such a triangle is unique up to similarity.

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\section*{Trichotomy}

■ If \(\alpha+\beta+\gamma=\pi\), then a Euclidean triangle exists with these angles.
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■ If \(\pi / \alpha\), etc. are integers \(>1\), reflected images of \(\triangle\) tile \(\mathbb{R}^{2}\).
```

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## Trichotomy

■ If $\alpha+\beta+\gamma=\pi$, then a Euclidean triangle exists with these angles.

- Such a triangle is unique up to similarity.
- If $\pi / \alpha$, etc. are integers $>1$, reflected images of $\triangle$ tile $\mathbb{R}^{2}$.

■ If $\alpha+\beta+\gamma>\pi$, then a spherical triangle exists with these angles.

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\section*{Trichotomy}

■ If \(\alpha+\beta+\gamma=\pi\), then a Euclidean triangle exists with these angles.
- Such a triangle is unique up to similarity.
- If \(\pi / \alpha\), etc. are integers \(>1\), reflected images of \(\triangle\) tile \(\mathbb{R}^{2}\).

■ If \(\alpha+\beta+\gamma>\pi\), then a spherical triangle exists with these angles. These triangles tile \(S^{2}\).

\section*{Trichotomy}

■ If \(\alpha+\beta+\gamma=\pi\), then a Euclidean triangle exists with these angles.
- Such a triangle is unique up to similarity.
\(\square\) If \(\pi / \alpha\), etc. are integers \(>1\), reflected images of \(\triangle\) tile \(\mathbb{R}^{2}\).
■ If \(\alpha+\beta+\gamma>\pi\), then a spherical triangle exists with these angles.
These triangles tile \(S^{2}\).
The number of triangles equals
\[
\frac{4 \pi}{\alpha+\beta+\gamma-\pi},
\]
the numerator equals area \(\left(S^{2}\right)\). and the denominator equals area \((\triangle)\).
```

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Angle-Angle-Angle implies Congruence

■ If \(\alpha+\beta+\gamma<\pi\), then a hyperbolic triangle exists with these angles.
```

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Angle-Angle-Angle implies Congruence
■ If $\alpha+\beta+\gamma<\pi$, then a hyperbolic triangle exists with these angles. These triangles tile $H^{2}$.

```
```

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■ If \(\alpha+\beta+\gamma<\pi\), then a hyperbolic triangle exists with these angles. These triangles tile \(H^{2}\).
■ In both spherical and hyperbolic geometry, the angles ( \(\alpha, \beta, \gamma\) ) determine \(\triangle\) up to congruence.

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\section*{Stereographic Projection}


Stereographic projection maps \(z=x+i y \in \mathbb{C}\) to
\[
\Sigma(z):=\frac{1}{1+|z|^{2}}\left[\begin{array}{c}
2 z \\
-1+|z|^{2}
\end{array}\right]
\]
```

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Stereographic models for inversive geometry

■ Stereographic projection maps circles to circles

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Stereographic models for inversive geometry

■ Stereographic projection maps circles to circles
■ - and preserves angles.
```

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Stereographic models for inversive geometry

■ Stereographic projection maps circles to circles

-     - and preserves angles.

■ Great circles are those which are symmetric about the origin (maximum radius).

```
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Stereographic models for inversive geometry

■ Stereographic projection maps circles to circles
■ - and preserves angles.
■ Great circles are those which are symmetric about the origin (maximum radius).
■ Euclidean straight lines those which pass through \(\infty\) (the North Pole).
```

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\section*{All-right triangles on the sphere}
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\section*{All-right triangles on the sphere}
```

■ The coordinate planes intersect $S^{2}$ in three orthogonal great circles.

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All-right triangles on the sphere
- The coordinate planes intersect \(S^{2}\) in three orthogonal great circles.
- Eight octants define triangles with three right angles.
```

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■ The coordinate planes intersect \(S^{2}\) in three orthogonal

\section*{All-right triangles on the sphere}
great circles.
■ Eight octants define triangles with three right angles.
■ Here is a stereogrphic projection of this tiling:

\section*{All-right triangles on the sphere}

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- The coordinate planes intersect \(S^{2}\) in three orthogonal great circles.
■ Eight octants define triangles with three right angles.
■ Here is a stereogrphic projection of this tiling:

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Tiling the sphere by triangles with two right angles


Here is a tiling of \(S^{2}\) by 24 triangles with angles \(\pi / 2, \pi / 2\) and \(\pi / 6\).

The tetrahedral tiling of the sphere by triangle


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Conclusion
Inscribe a tetrahedron in a sphere and then join the centers of its faces to the vertices to obtain a tiling of the sphere by 24 triangles. Each triangle has angles \(\pi / 2, \pi / 3, \pi / 3\).

The tetrahedral tiling of the sphere by triangle


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Inscribe a tetrahedron in a sphere and then join the centers of its faces to the vertices to obtain a tiling of the sphere by 24 triangles. Each triangle has angles \(\pi / 2, \pi / 3, \pi / 3\).

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Stereographic projection of the tetrahedral tiling


Tiling the sphere by 24 triangles with angles \(\pi / 2, \pi / 3\) and \(\pi / 3\).

\section*{The Octahedral Tiling}


Stereographic projection of the tiling of a sphere by 48 triangles of angles \(\pi / 2, \pi / 3, \pi / 4\) corresponding to a regular octahedron inscribed in the sphere.

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\section*{The Icosahedral Tiling}


Tiling the sphere by 120 triangles of angles \(\pi / 2, \pi / 3, \pi / 5\) corresponding to an icosahedron.
(Poincaré:) Hyperbolic geometry arises on a disc bounded by a circle \(C_{\infty}\). Geodesics are circular arcs orthogonal to \(C_{\infty}\).
```

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(Poincaré:) Hyperbolic geometry arises on a disc bounded by a circle \(C_{\infty}\). Geodesics are circular arcs orthogonal to \(C_{\infty}\).

■ Geodesic rays may be asymptotic if they remain a bounded distance; they are represented by mutually tangent arcs.
(Poincaré:) Hyperbolic geometry arises on a disc bounded by a circle \(C_{\infty}\). Geodesics are circular arcs orthogonal to \(C_{\infty}\).

■ Geodesic rays may be asymptotic if they remain a bounded distance; they are represented by mutually tangent arcs.
■ Otherwise they are ultraparallel, they diverge, and have a common orthogonal.

(Poincaré:) Hyperbolic geometry arises on a disc bounded by a circle \(C_{\infty}\). Geodesics are circular arcs orthogonal to \(C_{\infty}\).

■ Geodesic rays may be asymptotic if they remain a bounded distance; they are represented by mutually tangent arcs.
■ Otherwise they are ultraparallel, they diverge, and have a common orthogonal.


■ Given \(\alpha, \beta, \gamma \geq 0\) such that \(\alpha+\beta+\gamma<\pi\), a unique triangle exists with these angles.


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Tiling \(H^{2}\) by triangles with angles \(\pi / 2, \pi / 4, \pi / 8\).


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Tiling the hyperbolic plane by \(\pi / 6\)-equilateral triangles


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Tiling the hyperbolic plane by triangles with asymptotic sides


Finite area although sides have infinite length.

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\[
\left[\begin{array}{ll}
a & b \\
c & d
\end{array}\right], a d-b c=1
\]

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■ The group \(\operatorname{SL}(2, \mathbb{C})\) of \(2 \times 2\) complex matrices of determinant one:
\[
\left[\begin{array}{ll}
a & b \\
c & d
\end{array}\right], a d-b c=1
\]

■ acts by linear fractional transformations
\[
z \stackrel{\phi}{\longmapsto} \frac{a z+b}{c z+d}
\]
on \(\mathbb{C} \cup\{\infty\}\).

\section*{Subgroup corresponding to Euclidean geometry}

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## Subgroup corresponding to Euclidean geometry

■ Euclidean plane: complement of one point $(\infty)$ in $S^{2}$.

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\section*{Subgroup corresponding to Euclidean geometry}

■ Euclidean plane: complement of one point \((\infty)\) in \(S^{2}\).
■ If \(c=0\), then \(\phi(\infty)=\infty\).

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■ Euclidean plane: complement of one point \((\infty)\) in \(S^{2}\).
- If \(c=0\), then \(\phi(\infty)=\infty\).
- For some \(A \neq 0, B \in \mathbb{C}\),
\[
\phi(z)=A z+B
\]

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■ Euclidean plane: complement of one point \((\infty)\) in \(S^{2}\).
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■ \(\phi\) is a Euclidean similarity transformation:

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\section*{Subgroup corresponding to Euclidean geometry}

■ Euclidean plane: complement of one point \((\infty)\) in \(S^{2}\).
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■ \(\phi\) is a Euclidean similarity transformation:
- A composition of translations, rotations and dilations.

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\section*{Subgroup corresponding to Euclidean geometry}

■ Euclidean plane: complement of one point \((\infty)\) in \(S^{2}\).
- If \(c=0\), then \(\phi(\infty)=\infty\).
- For some \(A \neq 0, B \in \mathbb{C}\),
\[
\phi(z)=A z+B
\]

■ \(\phi\) is a Euclidean similarity transformation:
- A composition of translations, rotations and dilations.
- Represented by \(\left[\begin{array}{cc}A & B \\ 0 & 1\end{array}\right]\).

\section*{The Geometry of \(2 \times 2\)} Matrices

\section*{Subgroup corresponding to spherical geometry}

■ Reflection in the origin in \(\mathbb{R}^{3}\) corresponds to the antipodal map of \(S^{2}\) :
\[
\left[\begin{array}{l}
x \\
y \\
z
\end{array}\right] \longmapsto\left[\begin{array}{l}
-x \\
-y \\
-z
\end{array}\right]
\]

\section*{Subgroup corresponding to spherical geometry}

■ Reflection in the origin in \(\mathbb{R}^{3}\) corresponds to the antipodal map of \(S^{2}\) :
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y \\
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-x \\
-y \\
-z
\end{array}\right]
\]

■ Under stereographic projection, corresponds to:
\[
z \stackrel{\sigma}{\longmapsto}-1 / \bar{z}
\]
where \(z=x+i y\) and \(\bar{z}=x-i y\).

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\section*{Subgroup corresponding to spherical geometry}
- Reflection in the origin in \(\mathbb{R}^{3}\) corresponds to the antipodal map of \(S^{2}\) :
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\]

■ Under stereographic projection, corresponds to:
\[
z \stackrel{\sigma}{\longmapsto}-1 / \bar{z}
\]
where \(z=x+i y\) and \(\bar{z}=x-i y\).
■ \(\phi\) is a spherical isometry \(\Longleftrightarrow \phi \circ \sigma=\sigma \circ \phi\)

\section*{Subgroup corresponding to hyperbolic geometry}
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■ A "hyperbolic geometry" arises by taking a circle $C_{\infty}$ (called the absolute) and a component of its complement (call it $H^{2}$ ).

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■ A "hyperbolic geometry" arises by taking a circle $C_{\infty}$ (called the absolute) and a component of its complement (call it $H^{2}$ ).
■ For example the real line $\mathbb{R}$.

Subgroup corresponding to hyperbolic geometry

■ A "hyperbolic geometry" arises by taking a circle $C_{\infty}$ (called the absolute) and a component of its complement (call it $H^{2}$ ).
■ For example the real line $\mathbb{R}$.
■ Inversion in $\mathbb{R}$ is just complex conjugation:

$$
z \stackrel{\iota_{\mathbb{R}}}{\longmapsto} \bar{z}=x-i y
$$

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$\square \phi$ is an isometry of $H^{2} \Longleftrightarrow \phi \circ \iota_{\mathbb{R}}=\iota_{\mathbb{R}} \circ \phi$,

Subgroup corresponding to hyperbolic geometry

■ A "hyperbolic geometry" arises by taking a circle $C_{\infty}$ (called the absolute) and a component of its complement (call it $H^{2}$ ).
■ For example the real line $\mathbb{R}$.
■ Inversion in $\mathbb{R}$ is just complex conjugation:

$$
z \stackrel{\iota_{\mathbb{R}}}{\longmapsto} \bar{z}=x-i y
$$

■ $\phi$ is an isometry of $H^{2} \Longleftrightarrow \phi \circ \iota_{\mathbb{R}}=\iota_{\mathbb{R}} \circ \phi$, that is, the matrix $\phi$ is real: $a, b, c, d \in \mathbb{R}$.

## The Geometry of $2 \times 2$ <br> Circles as matrices <br> Matrices <br> William M. <br> Goldman <br> $\square$ Every circle is fixed under a unique inversion.

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\section*{Circles as matrices \\ Circles as matrices}

■ Every circle is fixed under a unique inversion.
■ The inversion in the circle of radius \(R\) centered at 0 is:
\[
z \mapsto R^{2} / \bar{z}
\]
```

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## Circles as matrices

■ Every circle is fixed under a unique inversion.
■ The inversion in the circle of radius $R$ centered at 0 is:

$$
z \mapsto R^{2} / \bar{z}
$$

$$
\text { corresponding to }\left[\begin{array}{cc}
0 & i R \\
i / R & 0
\end{array}\right]
$$

## The Geometry

■ Every circle is fixed under a unique inversion.
■ The inversion in the circle of radius $R$ centered at 0 is:

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$$

corresponding to $\left[\begin{array}{cc}0 & i R \\ i / R & 0\end{array}\right]$.
■ A straight line is a (degenerate) circle passing through $\infty$.

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■ Every circle is fixed under a unique inversion.
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■ A straight line is a (degenerate) circle passing through $\infty$.
■ Its inversion is just Euclidean reflection.

Euclidean geometry

Circles as matrices
■ Every circle is fixed under a unique inversion.
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$$
z \mapsto R^{2} / \bar{z}
$$

corresponding to $\left[\begin{array}{cc}0 & i R \\ i / R & 0\end{array}\right]$.
■ A straight line is a (degenerate) circle passing through $\infty$.
■ Its inversion is just Euclidean reflection.

- Inversion in $e^{i \theta} \mathbb{R}$ is:

$$
z \mapsto e^{2 i \theta} \bar{z}
$$

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Circles as matrices
■ Every circle is fixed under a unique inversion.
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■ A straight line is a (degenerate) circle passing through $\infty$.
■ Its inversion is just Euclidean reflection.

- Inversion in $e^{i \theta} \mathbb{R}$ is:

$$
z \mapsto e^{2 i \theta} \bar{z}
$$

corresponding to $\left[\begin{array}{cc}e^{i \theta} & 0 \\ 0 & e^{-i \theta}\end{array}\right]$.

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## The trace

- A single matrix

$$
X=\left[\begin{array}{ll}
a & b \\
c & d
\end{array}\right] \in \operatorname{SL}(2, \mathbb{C})
$$

is determined up to equivalence by its trace:

$$
\operatorname{tr}(X):=a+d
$$

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## The trace

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a & b \\
c & d
\end{array}\right] \in \operatorname{SL}(2, \mathbb{C})
$$

is determined up to equivalence by its trace:

$$
\operatorname{tr}(X):=a+d
$$

■ Every complex number $a \in \mathbb{C}$ is the trace of some $A \in \operatorname{SL}(2, \mathbb{C})$, for example:

$$
A=\left[\left.\begin{array}{cc}
a & -1 \\
1 & 0
\end{array} \right\rvert\,\right.
$$

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## Products of reflections

geometry
■ Two distinct circles $C_{1}, C_{2}$ may intersect in two points, be tangent, or be disjoint.

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## Products of reflections

■ Two distinct circles $C_{1}, C_{2}$ may intersect in two points, be tangent, or be disjoint.
$\square$ Let $R_{i}$ be inversion in $C_{i}$, represented as matrices in $\mathrm{SL}(2, \mathbb{C})$.

```
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\section*{Products of reflections}

■ Two distinct circles \(C_{1}, C_{2}\) may intersect in two points, be tangent, or be disjoint.
\(\square\) Let \(R_{i}\) be inversion in \(C_{i}\), represented as matrices in \(\mathrm{SL}(2, \mathbb{C})\).
- \(C_{1}, C_{2}\) are tangent \(\Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2\).

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\section*{Products of reflections}

■ Two distinct circles \(C_{1}, C_{2}\) may intersect in two points, be tangent, or be disjoint.
\(\square\) Let \(R_{i}\) be inversion in \(C_{i}\), represented as matrices in \(\mathrm{SL}(2, \mathbb{C})\).
- \(C_{1}, C_{2}\) are tangent \(\Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2\).
- \(C_{1}, C_{2}\) intersect in angle \(\theta \Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2 \cos (\theta)\).

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\section*{Products of reflections}

■ Two distinct circles \(C_{1}, C_{2}\) may intersect in two points, be tangent, or be disjoint.
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- \(C_{1}, C_{2}\) are tangent \(\Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2\).
- \(C_{1}, C_{2}\) intersect in angle \(\theta \Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2 \cos (\theta)\).
- \(C_{1}, C_{2}\) are disjoint \(\theta \Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)>2\) or \(<-2\).

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\section*{Products of reflections}

■ Two distinct circles \(C_{1}, C_{2}\) may intersect in two points, be tangent, or be disjoint.
\(\square\) Let \(R_{i}\) be inversion in \(C_{i}\), represented as matrices in \(\mathrm{SL}(2, \mathbb{C})\).
- \(C_{1}, C_{2}\) are tangent \(\Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2\).
- \(C_{1}, C_{2}\) intersect in angle \(\theta \Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2 \cos (\theta)\).
- \(C_{1}, C_{2}\) are disjoint \(\theta \Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)>2\) or \(<-2\).

■ In the latter case, \(C_{1}\) and \(C_{2}\) are orthogonal to a unique circle \(C_{\infty}\).

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■ Two distinct circles \(C_{1}, C_{2}\) may intersect in two points, be tangent, or be disjoint.
- Let \(R_{i}\) be inversion in \(C_{i}\), represented as matrices in \(S L(2, \mathbb{C})\).
- \(C_{1}, C_{2}\) are tangent \(\Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2\).
- \(C_{1}, C_{2}\) intersect in angle \(\theta \Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2 \cos (\theta)\).
- \(C_{1}, C_{2}\) are disjoint \(\theta \Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)>2\) or \(<-2\).

■ In the latter case, \(C_{1}\) and \(C_{2}\) are orthogonal to a unique circle \(C_{\infty}\).
■ Let \(H^{2}\) be a disc bounded by \(C_{\infty}\).

\section*{Products of reflections}

■ Two distinct circles \(C_{1}, C_{2}\) may intersect in two points, be tangent, or be disjoint.
- Let \(R_{i}\) be inversion in \(C_{i}\), represented as matrices in \(S L(2, \mathbb{C})\).
- \(C_{1}, C_{2}\) are tangent \(\Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2\).
- \(C_{1}, C_{2}\) intersect in angle \(\theta \Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2 \cos (\theta)\).
- \(C_{1}, C_{2}\) are disjoint \(\theta \Longleftrightarrow \operatorname{tr}\left(R_{1} R_{2}\right)>2\) or \(<-2\).

■ In the latter case, \(C_{1}\) and \(C_{2}\) are orthogonal to a unique circle \(C_{\infty}\).
- Let \(H^{2}\) be a disc bounded by \(C_{\infty}\).
\(C_{1}, C_{2}\) determine Poincaré geodesics at distance \(d\) :
\[
\operatorname{tr}\left(R_{1} R_{2}\right)= \pm 2 \cosh (d)
\]

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\section*{Triangle representations}

■ If \(R_{1}, R_{2}, R_{3}\) satisfy \(\left(R_{i}\right)^{2}=I\), then
\[
\begin{aligned}
A & :=R_{1} R_{2} \\
B & :=R_{2} R_{3} \\
C & :=R_{3} R_{1}
\end{aligned}
\]
satisfy \(A B C=1\).

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satisfy \(A B C=1\).
- Thus the problem of finding circles intersecting at angles \(\alpha, \beta, \gamma\) reduces to finding matrices \(A, B, C\) satisfying \(A B C=I\) and
\[
\begin{aligned}
\operatorname{tr}(A) & =2 \cos (\alpha) \\
\operatorname{tr}(B) & =2 \cos (\beta) \\
\operatorname{tr}(C) & =2 \cos (\gamma) .
\end{aligned}
\]

\section*{The Lie product}

■ If \(A, B, C\) are found, then \(R_{1}, R_{2}, R_{3}\) can be reconstructed by formulas:
\[
\begin{aligned}
& R_{1}=C A-A C \\
& R_{2}=A B-B A \\
& R_{3}=B C-C B
\end{aligned}
\]
to ensure that \(A=R_{1} R_{2}\), etc.
■ The Lie product \(A B-B A\) is analogous to the cross product \(A \times B\) of vectors.
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The Vogt-Fricke-Klein Theorem (1889)

■ Central to all this theory is the fundamental result characterizing pairs of unimodular \(2 \times 2\) complex matrices:

\section*{The Vogt-Fricke-Klein Theorem (1889)}

■ Central to all this theory is the fundamental result characterizing pairs of unimodular \(2 \times 2\) complex matrices:
- Let \(A, B \in \operatorname{SL}(2, \mathbb{C})\), and define \(C=(A B)^{-1}\)
\[
\begin{aligned}
a & :=\operatorname{tr}(A) \\
b & :=\operatorname{tr}(B) \\
c & :=\operatorname{tr}(A B)=\operatorname{tr}(C)
\end{aligned}
\]

Then if \(a^{2}+b^{2}+c^{2}-a b c \neq 4\), then any other pair ( \(A^{\prime}, B^{\prime}\) ) with the same traces \((a, b, c)\) is conjugate to \((A, B)\).

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■ If \(a^{2}+b^{2}+c^{2}-a b c=4\), then \(\exists P\) such that

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\[
\begin{aligned}
P A P^{-1} & =\left[\begin{array}{cc}
\alpha & * \\
0 & 1 / \alpha
\end{array}\right] \\
P B P^{-1} & =\left[\begin{array}{cc}
\beta & * \\
0 & 1 / \beta
\end{array}\right] .
\end{aligned}
\]

■ so that
\[
\begin{aligned}
& a=\alpha+1 / \alpha \\
& b=\beta+1 / \beta \\
& c=(\alpha \beta)+1 /(\alpha \beta)
\end{aligned}
\]
parametrizing \(a^{2}+b^{2}+c^{2}-a b c=4\) by rational functions.

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Conversely, given \(a, b, c\) satisfying \(a^{2}+b^{2}+c^{2}-a b c \neq 4\). Choose \(\gamma\) so that
\[
c=\gamma+1 / \gamma
\]

Then \(\exists P\) such that
\[
\begin{aligned}
& P A P^{-1}=\left[\begin{array}{cc}
a & -1 \\
1 & 0
\end{array}\right] \\
& P B P^{-1}=\left[\begin{array}{cc}
0 & \gamma \\
-1 / \gamma & b
\end{array}\right] \\
& P C P^{-1}=\left[\begin{array}{cc}
\gamma & -a \gamma+b \\
0 & 1 / \gamma
\end{array}\right] .
\end{aligned}
\]
```

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## Building moduli spaces

■ Vogt's theorem $\Longrightarrow$ traces of $2 \times 2$ matrices give coordinates for spaces of geometries.

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\section*{Building moduli spaces}

■ Vogt's theorem \(\Longrightarrow\) traces of \(2 \times 2\) matrices give coordinates for spaces of geometries.
- \(\mathbb{C}^{3}\) parametrizes equivalence classes in \(\operatorname{SL}(2, \mathbb{C}) \times \operatorname{SL}(2, \mathbb{C})\).
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- Generalizes the Angle-Angle-Angle test for congruence in non-Euclidean geometry.
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- Triangles are the building blocks for surfaces.

■ Geometry of matrices defines geometric structure on the moduli space.
```

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## Other Geometries and Higher Dimensions

■ Just the beginning of a more intricate picture.

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■ For example:
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■ For example:

- Groups with $>2$ generators;

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## Other Geometries and Higher Dimensions

■ Just the beginning of a more intricate picture.
■ For example:

- Groups with > 2 generators;

■ Manifolds of dimension 3, 4, ...;

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\section*{Other Geometries and Higher Dimensions}

■ Just the beginning of a more intricate picture.
■ For example:
- Groups with > 2 generators;

■ Manifolds of dimension 3,4,...;
■ More complicated Lie groups ( \(\operatorname{SL}(n, \mathbb{C})\) when \(n>2)\).

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A (3,3,4)-triangle tiling in the real projective plane \(G=\operatorname{SL}(3, \mathbb{R})\).
```

