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# The Geometry of $2 \times 2$ Matrices

### William M. Goldman

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 Fredericksburg, Virginia 18 April 2009

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#### Algebraicizing geometry through symmetry



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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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Locally has Euclidean geometry.

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- Locally has Euclidean geometry.
- Every point has a Euclidean coordinate neighborhood.

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### A sphere is not Euclidean

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A sphere is not Euclidean

■ No local Euclidean geometry structure on the sphere.

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A sphere is not Euclidean

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

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The geometry on the space of geometries

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:

$$0 < a, b, c$$
$$a < b + c$$
$$b < c + a$$
$$c < a + b$$

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

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| Algebraicizing<br>geometry                                    |  |
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#### Euclidean structures on torus

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Euclidean structures on torus

Every Euclidean structure on a torus arises as the quotient of the plane by a lattice of translations, for example

$$(x, y) \longmapsto (x + m, y + n)$$

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where  $m, n \in \mathbb{Z}$ .

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The translations identify the fundamental parallelogram.

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- The translations identify the fundamental parallelogram.
- Identify ℝ<sup>2</sup> with ℂ. Up to equivalence the lattice is generated by *complex numbers* 1 and τ = x + iy, where y > 0.

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Every Euclidean structure on a torus arises as the quotient of the plane by a lattice of translations, for example

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- The translations identify the fundamental parallelogram.
- Identify R<sup>2</sup> with C. Up to equivalence the lattice is generated by *complex numbers* 1 and τ = x + iy, where y > 0.



| The Geometry<br>of 2 × 2<br>Matrices | Moduli space                                  |
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| Euclidean<br>geometry                |   |
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The space of structures  $\longleftrightarrow$  with equivalence classes of  $\tau \in H^2$  by SL(2,  $\mathbb{Z}$ ) — natural hyperbolic geometry.

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 The space of structures → with equivalence classes of τ ∈ H<sup>2</sup> by SL(2, Z) → natural hyperbolic geometry.
Changing basis → action of the group SL(2, Z) of integral 2x2 matrices by

$$au \longmapsto rac{a au + b}{c au + d}$$
 where  $a, b, c, d \in \mathbb{Z}.$ 



| The Geometry<br>of 2 × 2<br>Matrices |  |
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### Euclidean geometry

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 Euclidean geometry concerns properties of space invariant under *rigid motions*.

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

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Euclidean geometry

- Euclidean geometry concerns properties of space invariant under *rigid motions*.
- For example: distance, parallelism, angle, area and volume.
- Points in Euclidean space are represented by vectors; Euclidean distance is defined by:

$$d(\vec{a},\vec{b}):=\|\vec{a}-\vec{b}\|,$$
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- Points in Euclidean space are represented by vectors; Euclidean distance is defined by:

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

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

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

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• Points on the sphere  $S^2$  are *unit vectors* in  $\mathbb{R}^3$ .

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### Spherical geometry

- Points on the sphere  $S^2$  are *unit vectors* in  $\mathbb{R}^3$ .
- Spherical distance between  $\vec{a}, \vec{b} \in S^2$  is the minimum length of a curve on  $S^2$  between joining them.

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• It is the angle  $\theta = \angle (\vec{a}, \vec{b})$ :

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- It is the angle  $\theta = \angle (\vec{a}, \vec{b})$ :

$$\cos(\theta) = \vec{a} \cdot \vec{b}$$

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- Points on the sphere  $S^2$  are *unit vectors* in  $\mathbb{R}^3$ .
- Spherical distance between  $\vec{a}, \vec{b} \in S^2$  is the minimum length of a curve on  $S^2$  between joining them.
- It is the angle  $\theta = \angle (\vec{a}, \vec{b})$ :

$$\cos(\theta) = \vec{a} \cdot \vec{b}$$

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• the size of the rotation taking  $\vec{b}$  to  $\vec{a}$ .

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Metric circles on the sphere of radius R.



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• Spherical circle of radius r has circumference  $C(R) = 2\pi R \sin(r/R)$ 

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Metric circles on the sphere of radius R.



• Spherical circle of radius r has circumference  $C(R) = 2\pi R \sin(r/R)$ 

• As  $R \longrightarrow \infty$ , the geometry approaches *Euclidean*:

 $C(r) \longrightarrow 2\pi r$ .

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### Geodesics (straight lines) on the sphere

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### Geodesics (straight lines) on the sphere

• A great circle on S<sup>2</sup> 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.

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These are circles of maximum diameter

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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
- The shortest curves between points (constant speed curves of zero acceleration) are arcs of great circles.

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Attempted "coordinate grid" on a sphere:

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### Geodesics (straight lines) on the sphere

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- Attempted "coordinate grid" on a sphere:



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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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Tilings by triangles

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If the angles α, β, γ in △ are π/n, where n > 0 is an integer, then the triangles tile the plane.

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### Tilings by triangles

- *Example:* Take a triangle  $\triangle$  and try to tile the plane by reflecting  $\triangle$  repeatedly in its sides.
- If the angles α, β, γ in △ are π/n, where n > 0 is an integer, then the triangles tile the plane.
- If the angles are π/p, π/q, π/r then the three reflections R<sub>1</sub>, R<sub>2</sub>, R<sub>3</sub> generate a group with presentation with defining relations

$$(R_1)^2 = (R_2)^2 = (R_3)^2 =$$
  
 $(R_1R_2)^p = (R_2R_3)^q = (R_3R_1)^r = I$ 

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| Triangle tilings<br>Stereographic<br>projection  |  |
| Triangle tilings<br>Stereographic<br>projection<br>Hyperbolic<br>Geometry  |  |
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| Triangle tilings                     |  |  |  |  |
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# Tiling $\mathbb{R}^2$ by triangles



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

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Such a triangle is unique up to *similarity*.

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- 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  $\mathbb{R}^2$ .

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

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

These triangles tile  $S^2$ .

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  - 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  $S^2$ .
  - The number of triangles equals

$$\frac{4\pi}{\alpha+\beta+\gamma-\pi},$$

the numerator equals  $\operatorname{area}(S^2)$ . and the denominator equals  $\operatorname{area}(\Delta)$ .

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### Angle-Angle implies Congruence

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If  $\alpha + \beta + \gamma < \pi$ , then a hyperbolic triangle exists with these angles.

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If α + β + γ < π, then a hyperbolic triangle exists with these angles.</li>
 These triangles tile H<sup>2</sup>.

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Angle-Angle implies Congruence

- If α + β + γ < π, then a hyperbolic triangle exists with these angles.</li>
  These triangles tile H<sup>2</sup>.
- In both spherical and hyperbolic geometry, the angles  $(\alpha, \beta, \gamma)$  determine  $\triangle$  up to *congruence*.

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# The Geometry of $2 \times 2$ Stereographic Projection Matrices $\Sigma(z)$ Stereographic 0 projection $\overline{z = x + iy}$ Stereographic projection maps $z = x + iy \in \mathbb{C}$ to $\Sigma(z) := rac{1}{1+|z|^2} \begin{vmatrix} 2z \\ -1+|z|^2 \end{vmatrix}$

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Stereographic projection maps circles to circles

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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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### All-right triangles on the sphere

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All-right triangles on the sphere

The coordinate planes intersect S<sup>2</sup> in three orthogonal great circles.

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All-right triangles on the sphere

- The coordinate planes intersect S<sup>2</sup> in three orthogonal great circles.
- Eight octants define triangles with *three* right angles.

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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  $\pi/6.$ 

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The tetrahedral tiling of the sphere by triangle



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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### The tetrahedral tiling of the sphere by triangle



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

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## 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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### The Icosahedral Tiling



Tiling the sphere by 120 triangles of angles  $\pi/2, \pi/3, \pi/5$  corresponding to an icosahedron.

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

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Geodesic rays may be *asymptotic* if they remain a bounded distance; they are represented by mutually tangent arcs.

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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.



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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  $\alpha, \beta, \gamma \ge 0$  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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■ The group SL(2, C) of 2 × 2 complex matrices of determinant one:

$$\begin{bmatrix} a & b \\ c & d \end{bmatrix}, ad - bc = 1$$

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■ The group SL(2, C) of 2 × 2 complex matrices of determinant one:

$$\begin{bmatrix} a & b \\ c & d \end{bmatrix}, ad - bc = 1$$

acts by linear fractional transformations

$$z \longmapsto \frac{\phi}{cz+d}$$

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on  $\mathbb{C} \cup \{\infty\}$ .

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### Subgroup corresponding to Euclidean geometry

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

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Euclidean plane: complement of one point (∞) in S<sup>2</sup>.
If c = 0, then φ(∞) = ∞.

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Euclidean plane: complement of one point (∞) in S<sup>2</sup>.
If c = 0, then φ(∞) = ∞.

• For some  $A \neq 0, B \in \mathbb{C}$ ,

$$\phi(z) = Az + B$$

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•  $\phi$  is a Euclidean similarity transformation:

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$$\phi(z) = Az + B$$

•  $\phi$  is a Euclidean similarity transformation:

A composition of translations, rotations and dilations.

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Euclidean plane: complement of one point (∞) in S<sup>2</sup>.
If c = 0, then φ(∞) = ∞.

For some 
$$A \neq 0, B \in \mathbb{C}$$
,

$$\phi(z) = Az + B$$

•  $\phi$  is a Euclidean similarity transformation:

A composition of translations, rotations and dilations. Represented by  $\begin{bmatrix} A & B \\ 0 & 1 \end{bmatrix}$ .

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Subgroup corresponding to spherical geometry

■ Reflection in the origin in ℝ<sup>3</sup> corresponds to the *antipodal map* of *S*<sup>2</sup>:

$$\begin{bmatrix} x \\ y \\ z \end{bmatrix} \longmapsto \begin{bmatrix} -x \\ -y \\ -z \end{bmatrix}$$

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$$\begin{bmatrix} x \\ y \\ z \end{bmatrix} \longmapsto \begin{bmatrix} -x \\ -y \\ -z \end{bmatrix}$$

Under stereographic projection, corresponds to:

$$z \stackrel{\sigma}{\longmapsto} -1/\bar{z}$$

where z = x + iy and  $\overline{z} = x - iy$ .

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where z = x + iy and  $\overline{z} = x - iy$ .

•  $\phi$  is a spherical isometry  $\iff \phi \circ \sigma = \sigma \circ \phi$ 

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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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For example the real line  $\mathbb{R}$ .

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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  $\mathbb{R}$ .
- Inversion in  $\mathbb{R}$  is just *complex conjugation*:

$$z \stackrel{\iota_{\mathbb{R}}}{\longmapsto} \overline{z} = x - iy$$

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

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

#### The Geometry of 2 × 2 Matrices

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Circles as matrices

Every circle is fixed under a unique *inversion*.

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- 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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corresponding to 
$$\begin{bmatrix} 0 & iR \\ i/R & 0 \end{bmatrix}$$
.

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  - The inversion in the circle of radius R centered at 0 is:

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corresponding to  $\begin{bmatrix} 0 & iR \\ i/R & 0 \end{bmatrix}$ . • A straight line is a (degenerate) circle passing through  $\infty$ .

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corresponding to 
$$\begin{bmatrix} 0 & iR\\ i/R & 0 \end{bmatrix}$$
.

A straight line is a (degenerate) circle passing through ∞.
Its inversion is just Euclidean reflection.

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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:

$$z\mapsto e^{2i heta}ar{z}$$

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

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

corresponding to 
$$\begin{bmatrix} 0 & iR \\ i/R & 0 \end{bmatrix}$$
.

- A straight line is a (degenerate) circle passing through  $\infty$ .
- Its inversion is just Euclidean reflection.
- Inversion in  $e^{i\theta}\mathbb{R}$  is:

corresponding to 
$$\begin{bmatrix} e^{i\theta} & 0\\ 0 & e^{-i\theta} \end{bmatrix}$$
.

=  $2i\theta =$ 

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### The trace

A single matrix

.

$$X = \begin{bmatrix} a & b \\ c & d \end{bmatrix} \in \mathsf{SL}(2,\mathbb{C})$$

is determined up to equivalence by its trace:

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

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### The trace

A single matrix

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$$X = \begin{bmatrix} a & b \\ c & d \end{bmatrix} \in \mathsf{SL}(2,\mathbb{C})$$

is determined up to equivalence by its trace:

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

■ Every complex number a ∈ C is the trace of some A ∈ SL(2, C), for example:

$$A = \begin{bmatrix} a & -1 \\ 1 & 0 \end{bmatrix}.$$

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Products of reflections

Two distinct circles C<sub>1</sub>, C<sub>2</sub> may intersect in two points, be tangent, or be disjoint.

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Two distinct circles C<sub>1</sub>, C<sub>2</sub> may intersect in two points, be tangent, or be disjoint.

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Let  $R_i$  be inversion in  $C_i$ , represented as matrices in  $SL(2, \mathbb{C})$ .

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■ Two distinct circles *C*<sub>1</sub>, *C*<sub>2</sub> may intersect in two points, be tangent, or be disjoint.

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- Let R<sub>i</sub> be inversion in C<sub>i</sub>, represented as matrices in SL(2, C).
  - $C_1, C_2$  are tangent  $\iff$  tr $(R_1R_2) = \pm 2$ .

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### Products of reflections

- Two distinct circles *C*<sub>1</sub>, *C*<sub>2</sub> may intersect in two points, be tangent, or be disjoint.
- Let R<sub>i</sub> be inversion in C<sub>i</sub>, represented as matrices in SL(2, C).
  - $C_1, C_2$  are tangent  $\iff$  tr $(R_1R_2) = \pm 2$ .
  - $C_1, C_2$  intersect in angle  $\theta \iff \operatorname{tr}(R_1R_2) = \pm 2\cos(\theta)$ .

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### Products of reflections

- Two distinct circles *C*<sub>1</sub>, *C*<sub>2</sub> may intersect in two points, be tangent, or be disjoint.
- Let  $R_i$  be inversion in  $C_i$ , represented as matrices in  $SL(2, \mathbb{C})$ .
  - $C_1, C_2$  are tangent  $\iff$  tr $(R_1R_2) = \pm 2$ .
  - $C_1, C_2$  intersect in angle  $\theta \iff \operatorname{tr}(R_1R_2) = \pm 2\cos(\theta)$ .

•  $C_1, C_2$  are disjoint  $\theta \iff \operatorname{tr}(R_1R_2) > 2$  or < -2.

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### Products of reflections

- Two distinct circles *C*<sub>1</sub>, *C*<sub>2</sub> may intersect in two points, be tangent, or be disjoint.
- Let R<sub>i</sub> be inversion in C<sub>i</sub>, represented as matrices in SL(2, C).
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  - $C_1, C_2$  intersect in angle  $\theta \iff \operatorname{tr}(R_1R_2) = \pm 2\cos(\theta)$ .
  - $C_1, C_2$  are disjoint  $\theta \iff \operatorname{tr}(R_1R_2) > 2$  or < -2.
- In the latter case,  $C_1$  and  $C_2$  are orthogonal to a unique circle  $C_{\infty}$ .

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• Let  $H^2$  be a disc bounded by  $C_{\infty}$ .

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### Products of reflections

- Two distinct circles *C*<sub>1</sub>, *C*<sub>2</sub> may intersect in two points, be tangent, or be disjoint.
- Let  $R_i$  be inversion in  $C_i$ , represented as matrices in  $SL(2, \mathbb{C})$ .
  - $C_1, C_2$  are tangent  $\iff$  tr $(R_1R_2) = \pm 2$ .
  - $C_1, C_2$  intersect in angle  $\theta \iff \operatorname{tr}(R_1R_2) = \pm 2\cos(\theta)$ .
  - $C_1, C_2$  are disjoint  $\theta \iff tr(R_1R_2) > 2$  or < -2.
- In the latter case,  $C_1$  and  $C_2$  are orthogonal to a unique circle  $C_{\infty}$ .
- Let H<sup>2</sup> be a disc bounded by C<sub>∞</sub>. C<sub>1</sub>, C<sub>2</sub> determine Poincaré geodesics at distance d:

$$\operatorname{tr}(R_1R_2) = \pm 2\cosh(d).$$

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Triangle representations

If R<sub>1</sub>, R<sub>2</sub>, R<sub>3</sub> satisfy (R<sub>i</sub>)<sup>2</sup> = I, then
 A := R<sub>1</sub>R<sub>2</sub>
 B := R<sub>2</sub>R<sub>3</sub>
 C := R<sub>3</sub>R<sub>1</sub>

satisfy ABC = I.

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 A := R<sub>1</sub>R<sub>2</sub>
 B := R<sub>2</sub>R<sub>3</sub>
 C := R<sub>3</sub>R<sub>1</sub>

satisfy ABC = I.

$$tr(A) = 2\cos(\alpha)$$
  

$$tr(B) = 2\cos(\beta)$$
  

$$tr(C) = 2\cos(\gamma).$$

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The Lie product

■ If *A*, *B*, *C* are found, then *R*<sub>1</sub>, *R*<sub>2</sub>, *R*<sub>3</sub> can be reconstructed by formulas:

$$R_1 = CA - AC$$
$$R_2 = AB - BA$$
$$R_3 = BC - CB$$

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to ensure that  $A = R_1 R_2$ , etc.

■ The *Lie product* AB – BA is analogous to the *cross* product A × 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 × 2 complex matrices:

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The Vogt-Fricke-Klein Theorem (1889)

Central to all this theory is the fundamental result characterizing pairs of unimodular 2 × 2 complex matrices:
 Let A, B ∈ SL(2, C), and define C = (AB)<sup>-1</sup>

$$a := tr(A)$$
  

$$b := tr(B)$$
  

$$c := tr(AB) = tr(C).$$

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

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If 
$$a^2 + b^2 + c^2 - abc = 4$$
, then  $\exists P$  such that

$$\begin{split} & \textit{PAP}^{-1} = \begin{bmatrix} \alpha & * \\ 0 & 1/\alpha \end{bmatrix} \\ & \textit{PBP}^{-1} = \begin{bmatrix} \beta & * \\ 0 & 1/\beta \end{bmatrix}. \end{split}$$

so that

$$a = \alpha + 1/\alpha$$
  

$$b = \beta + 1/\beta$$
  

$$c = (\alpha\beta) + 1/(\alpha\beta)$$

parametrizing  $a^2 + b^2 + c^2 - abc = 4$  by rational functions.

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Conversely, given a, b, c satisfying  $a^2 + b^2 + c^2 - abc \neq 4$ . Choose  $\gamma$  so that

$$c = \gamma + 1/\gamma.$$

Then  $\exists P$  such that

$$PAP^{-1} = \begin{bmatrix} a & -1 \\ 1 & 0 \end{bmatrix}$$
$$PBP^{-1} = \begin{bmatrix} 0 & \gamma \\ -1/\gamma & b \end{bmatrix}$$
$$PCP^{-1} = \begin{bmatrix} \gamma & -a\gamma + b \\ 0 & 1/\gamma \end{bmatrix}$$

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Building moduli spaces

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■ Vogt's theorem ⇒ traces of 2 × 2 matrices give coordinates for spaces of geometries.

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Building moduli spaces

- Vogt's theorem ⇒ traces of 2 × 2 matrices give coordinates for spaces of geometries.
  - $\mathbb{C}^3$  parametrizes equivalence classes in  $SL(2,\mathbb{C}) \times SL(2,\mathbb{C})$ .

#### The Geometry of 2 × 2 Matrices

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### Building moduli spaces

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 Generalizes the Angle-Angle Angle test for congruence in non-Euclidean geometry.

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- Generalizes the Angle-Angle Angle test for congruence in non-Euclidean geometry.
- Triangles are the building blocks for surfaces.

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  - $\mathbb{C}^3$  parametrizes equivalence classes in  $SL(2,\mathbb{C}) \times SL(2,\mathbb{C})$ .

- Generalizes the Angle-Angle-Angle test for congruence in non-Euclidean geometry.
- 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

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■ Just the beginning of a more intricate picture.

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

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  - 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, . . . ;
  - More complicated Lie groups  $(SL(n, \mathbb{C}) \text{ when } n > 2)$ .

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

