数理解析研究所講究録 1374 巻 2004 年 188-200

EVERSION OF A FOLD MAP OF S^2 TO $\mathbf{R}^2$ WITH ONE SINGULAR SET

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1. Introduction

In the following, all manifolds and maps are differentiable of class C^∞.

Let M be an n-dimensional closed manifold, N an n-dimensional manifold and $f : M \to N$ a map of M into N. We denote by $S(f)$ the set of the points in M where the rank of the differential of f is strictly less than n. We call $S(f)$ the *singular set* of f and $f(S(f))$ the *singular value set* of f. We say that a map $f : M \to N$ is a *fold map* if there exist local coordinate systems $(x_1, x_2, \ldots, x_n)$ around $q \in M$ and $(y_1, y_2, \ldots, y_n)$ around $f(q) \in N$ such that f has one of the following forms:

$$(y_1 \circ f, y_2 \circ f, \ldots, y_{n-1} \circ f, y_n \circ f) = \begin{cases} (x_1, x_2, \ldots, x_{n-1}, x_n), & q\text{: regular point,} \\ (x_1, x_2, \ldots, x_{n-1}, x_n^2), & q\text{: fold point.} \end{cases}$$

Note that for a fold map $f : M \to N$, $S(f)$ is an $(n-1)$-dimensional submanifold of M. If the restricted map $f|S(f) : S(f) \looparrowright N$ is an immersion with normal crossings, we call f a *stable fold map*.

Let V be an $(n-1)$-dimensional submanifold of M and $f : M \to N$ a fold map such that $S(f) = V$. We denote by $\mathcal{F}(M, N; V)$ the set of such fold maps. Note that $\mathcal{F}(M, N; V)$ is the subspace of $C^\infty(M, N)$ having the Whitney C^∞-topology. Let T be a tubular neighborhood of V in M such that there exists a fiber involution of it, $h : T \to T$, whose fixed points set is V and the composition $(f|T) \circ h$ coincides with $f|T$. Note that for any $f \in \mathcal{F}(M, N; V)$, we may assume that T does not depend on f but depends on M and V. For $\widetilde{M} = \mathrm{cl}(M \setminus T)$, the closure of $M \setminus T$, $f|\widetilde{M} : \widetilde{M} \to N$ is an immersion.

In [1, 2], Eliashberg studied the existence of a fold map $f : M \to N$. In the appendix of [2], he proved that the number of the connected components of $\mathcal{F}(S^2, \mathbf{R}^2; S^1_0)$ is strictly four, where S^2 is an oriented 2-dimensional sphere, $\mathbf{R}^2$ is the oriented plane and S^1_0 is the equator of S^2. We denote by $\mathcal{S}_1, \mathcal{S}_2, \mathcal{E}_1$ and $\mathcal{E}_2$ the connected components of $\mathcal{F}(S^2, \mathbf{R}^2; S^1_0)$. We call a fold map f in $\mathcal{S}_i$ a *standard* fold map and in $\mathcal{E}_i$ an *exotic* fold map $(i = 1, 2)$. In the same paper, he showed the representative elements of each connected components of $\mathcal{F}(S^2, \mathbf{R}^2; S^1_0)$. Let $e : S^2 \to \mathbf{R}^2$ be the representative element of $\mathcal{E}_1$ such that Eliashberg gave this map in [2] ([1]). This fold map is constructed by using two immersed disks called *Milnor's examples*. We can construct

The author has been supported by JSPS Research Fellowships for Young Scientists.

another exotic fold map $\widetilde{e} \in \mathcal{E}_1$ by using these two Milnor's examples. Then, there exists a homotopy $E : S^2 \times [-1, 1] \to \mathbf{R}^2$ such that $e_{-1} = e$, $e_1 = \widetilde{e}$ and $e_t \in \mathcal{E}_1$, where e_t is defined by $e_t(x) = E(x, t)$ $(x \in S^2, t \in [-1, 1])$. We call such a homotopy a *fold eversion* between e and $\widetilde{e}$.

In [2], Eliashberg only stated the existence of a fold eversion. As the theorem of sphere eversion [7], it is difficult to give a fold eversion at first glance. In this report, we construct a fold eversion between e and $\widetilde{e}$ concretely as Morin and Petit constructed a sphere eversion concretely (see [6]).

The report is organized as follows.

In Section 2, we characterize each connected component of $\mathcal{F}(S^2, \mathbf{R}^2; S^1_0)$ and construct fold maps e and $\widetilde{e}$. We observe local behaviors of a homotopy of fold maps.

In Section 3, we give a fold eversion between e and $\widetilde{e}$ concretely.

The author would like to express his sincere gratitude to Prof. Goo Ishikawa, Prof. Syuichi Izumiya, Prof. Toru Ohmoto and Prof. Osamu Saeki for invaluable comments and encouragement.

2. Preliminaries

In this section, we state each connected component of $\mathcal{F}(S^2, \mathbf{R}^2; S^1_0)$ precisely. We also see local behaviors of a homotopy of fold maps.

Let S^2 be an oriented 2-dimensional sphere, $\mathbf{R}^2$ the oriented plane and S^1_0 the equator of S^2. Let T be a tubular neighborhood of S^1_0 in S^2 and we fix a trivialization $T \cong S^1_0 \times [-1, 1]$ such that $S^1_0 = S^1_0 \times \{0\}$. We have a fiber involution $h : S^1_0 \times [-1, 1] \to S^1_0 \times [-1, 1]$ such that $h(x, t) = (x, -t)$. Then we may assume that for any $f \in \mathcal{F}(S^2, \mathbf{R}^2; S^1_0)$, we have

$$(f|S^1_0 \times [-1, 1])(x, t) = (f|S^1_0 \times [-1, 1])(x, -t) \tag{2.1}$$

and

$$f|S^1_0 \times \{t\} \text{ is sufficiently close to } f|S^1_0 \times \{1\}. \tag{2.2}$$

Here, $\mathbf{R}^2$ has the Euclidean metric. We denote by D^2_N and D^2_S each connected component of $\mathrm{cl}(S^2 \setminus T)$.

Definition 2.1. Let $f : S^2 \to \mathbf{R}^2$ be a fold map in $\mathcal{F}(S^2, \mathbf{R}^2; S^1_0)$. We say that $f|D^2_N$ and $f|D^2_S$ are the *same extensions* of $f|\partial T$ if there exists an orientation reversing diffeomorphism $k : D^2_N \to D^2_S$ such that $k|\partial D^2_N = h$ and $f|D^2_S \circ k = f|D^2_N$. Otherwise, we say that $f|D^2_N$ and $f|D^2_S$ are the *different extensions* of $f|\partial T$.

Then, Eliashberg's theorem is stated as follows.

Theorem 2.2 (Eliashberg [2]). *Each connected component of $\mathcal{F}(S^2, \mathbf{R}^2; S^1_0) = \mathcal{S}_1 \cup \mathcal{S}_2 \cup \mathcal{E}_1 \cup \mathcal{E}_2$ consists of all fold maps satisfying the following properties.*

(1) *The connected component $\mathcal{S}_1$ (resp. $\mathcal{S}_2$) consists of all fold maps $f : S^2 \to \mathbf{R}^2$ in $\mathcal{F}(S^2, \mathbf{R}^2; S^1_0)$ such that $f|D^2_N$ and $f|D^2_S$ are the same extensions of $f|\partial T$. We set the*

orientation of S^2 so that $f|D_N^2$ is the orientation preserving (resp. reversing) immersion and $f|D_S^2$ is the orientation reversing (resp. preserving) immersion.

(2) *The connected component $\mathcal{E}_1$ (resp. $\mathcal{E}_2$) consists of all fold maps $f : S^2 \to \mathbf{R}^2$ in $\mathcal{F}(S^2, \mathbf{R}^2; S_0^1)$ such that $f|D_N^2$ and $f|D_S^2$ are the different extensions of $f|\partial T$. We set the orientation of S^2 so that $f|D_N^2$ is the orientation preserving (resp. reversing) immersion and $f|D_S^2$ is the orientation reversing (resp. preserving) immersion.*

Let $\pi : \mathbf{R}^3 \to \mathbf{R}^2$ be the canonical projection defined by $\pi(x_1, x_2, x_3) = (x_1, x_2)$ and $i : S^2 \to \mathbf{R}^3$ the inclusion defined by $i(S^2) = \{(x_1, x_2, x_3) \in \mathbf{R}^3 \mid x_1^2 + x_2^2 + x_3^2 = 1\}$ and $i(S_0^1) = \{(x_1, x_2, x_3) \in i(S^2) \mid x_3 = 0\}$. If we choose a suitable orientation on S^2, $s = \pi \circ i$ is a stable fold map in $\mathcal{S}_1$. The images of $s(D_N^2)$ and $s(D_S^2)$ are depicted as in FIGURE 1.

FIGURE 1

In [2] ([1]), Eliashberg gave a representative element, $e : S^2 \to \mathbf{R}^2$, of $\mathcal{E}_1$. Let D^2 be an oriented 2-dimensional disk. Let m_1 and $m_2 : D^2 \looparrowright \mathbf{R}^2$ be two orientation preserving immersions called *Milnor's examples* (see FIGURE 2). Note that m_1 and m_2 are the different extensions of $m_1|\partial D^2 = m_2|\partial D^2$.

FIGURE 2

Let $g_N : D_N^2 \to D^2$ be an orientation preserving diffeomorphism and $g_S : D_S^2 \to D^2$ an orientation reversing diffeomorphism such that $g_S \circ h|\partial D_N^2 = g_N|\partial D_N^2$ holds. Then, we have the desired fold map $e \in \mathcal{E}_1$ such that $e|D_N^2 = m_1 \circ g_N$, $e|D_S^2 = m_2 \circ g_S$ and $e|T$ satisfies the conditions (2.1) and (2.2). The image of $e(D_N^2)$ is depicted as in FIGURE 3 (a) and $e(D_S^2)$ is depicted as in FIGURE 3 (b).

FIGURE 3

If we exchange these two Milnor's examples on D_N^2 and D_S^2, we have another exotic fold map $\tilde{e} \in \mathcal{E}_1$ such that $\tilde{e}|D_N^2 = m_2 \circ g_N$, $\tilde{e}|D_S^2 = m_1 \circ g_S$ and $\tilde{e}|T$ satisfies the conditions (2.1) and (2,2). The image of $\tilde{e}(D_N^2)$ is depicted as in FIGURE 4 (a) and $\tilde{e}(D_S^2)$ is depicted as in FIGURE 4 (b).

FIGURE 4

Note that e and $\tilde{e}$ are stable fold maps. In FIGURES 3 and 4, gray strips are the image of rectangles properly embedded in D_N^2 and D_S^2, respectively. We draw these gray strips so that they help the readers to understand how to extend $e|\partial T$ (resp. $\tilde{e}|\partial T$) to $e|D_N^2$ and $e|D_S^2$ (resp. $\tilde{e}|D_N^2$ and $\tilde{e}|D_S^2$). They also help the readers to understand $e|D_N^2$ and $e|D_S^2$ (resp. $\tilde{e}|D_N^2$ and $\tilde{e}|D_S^2$) are the different extensions of $e|\partial T$ (resp. $\tilde{e}|\partial T$).

Let f and g be fold maps in $\mathcal{F}(S^2, \mathbf{R}^2; S_0^1)$ such that f is a stable fold map. Let $y_g \in g(S(g))$ be a singular value of g. Suppose that there exists a singular value $y_f \in f(S(f))$ such that a map germ $g : (S^2, g^{-1}(y_g) \cap S(g)) \to (\mathbf{R}^2, y_g)$ is $\mathcal{A}$-equivalent to a map germ $f : (S^2, f^{-1}(y_f) \cap S(f)) \to (\mathbf{R}^2, y_f)$. Then, we call y_g a *stable fold singular value* of g.

Let f and $g : S^2 \to \mathbf{R}^2$ be two stable fold maps such that they are in the same connected component of $\mathcal{F}(S^2, \mathbf{R}^2; S_0^1)$. By the relative version of the parameterized multi-transversality theorem, there exists a homotopy $F : S^2 \times [-1,1] \to \mathbf{R}^2$ such that F satisfies the following properties.

(1) For any $t \in [-1,1]$, $f_t : S^2 \to \mathbf{R}^2$ is a fold map such that $f_{-1} = f$, $f_1 = g$ and f_t and f are in the same connected component of $\mathcal{F}(S^2, \mathbf{R}^2; S_0^1)$. Here, f_t is defined by $f_t(x) = F(x,t)$.

(2) There is a finite set of parameter values $-1 < t_1 < t_2 < \cdots < t_l < 1$ (possibly empty) in the open interval $(-1,1)$ such that the following conditions hold.

(2-1) For any $t \in [-1,1] \setminus \{t_1, \dots, t_l\}$, $f_t : M \to \mathbf{R}^2$ is a stable fold map.

(2-2) For each t_i $(i = 1, \dots, l)$, f_{t_i} has the unique singular value $y_i \in f_{t_i}(S(f_{t_i}))$ which is not stable fold singular value of f_{t_i} $(i = 1, \dots, l)$. The map germ

$$F : (S^2 \times (t_i - \varepsilon, t_i + \varepsilon), (f_{t_i}^{-1}(y_i) \cap S_0^1) \times \{t_i\}) \to (\mathbf{R}^2, y_i)$$

is $\mathcal{A}$-equivalent to one of the 1-parameter unfoldings in TABLE 1, where ε is a sufficiently small positive real number.

We call such an F a *generic fold homotopy* between f and g. We say that each t_i a *codimension* 1 *bifurcation value* of F and each f_{t_i} a *codimension* 1 *fold map* in $\mathcal{F}(S^2, \mathbf{R}^2; S_0^1)$ $(i = 1, \dots, l)$. We say that f is the *initial stable fold map* of F and g is the *terminal stable fold map* of F. We denote by Γ_1 the set of all codimension 1 fold maps in $\mathcal{F}(S^2, \mathbf{R}^2; S_0^1)$. By using local normal forms in TABLE 1, Γ_1 is classified into five strata, $J_*^\star$ and T_* ($\star = +, -$ and $* = 1, 2$). Note that each stratum may not necessarily be connected.

Remark 2.3. The relative multi-transversality theorem is stated and proved in [4] and the parameterized relative multi-transversality theorem is stated in [8]. The $\mathcal{A}$-equivalence classification of map germs $g : (\mathbf{R}^2, S) \to (\mathbf{R}^2, 0)$ and their 1-parameter unfoldings has been studied by Gibson and Hobbs [3]. Here, S consists of finitely many isolated points of $g^{-1}(0)$.

type	normal form $G(x,y,t)$
J^+	$(x_1, y_1^2 + t), (x_2, x_2^2 + y_2^2)$
J_1^-	$(x_1, -y_1^2 + t), (x_2, x_2^2 + y_2^2)$
J_2^-	$(x_1, y_1^2 + t), (x_2, x_2^2 - y_2^2)$
T_1	$(x_1 + y_1^2, x_1 - y_1^2 + t), (x_2, y_2^2), (-y_3^2, x_3)$
T_2	$(x_1 + y_1^2, x_1 - y_1^2 + t), (x_2, y_2^2), (y_3^2, x_3)$

TABLE 1. 1-parameter unfoldings

Let $G : (\mathbf{R}^2 \times \mathbf{R}, S \times \{0\}) \to (\mathbf{R}^2, 0)$ be a 1-parameter unfolding in TABLE 1. We define $g_t : \mathbf{R}^2 \to \mathbf{R}^2$ by $g_t(x) = G(x,t)$ and suppose that $S \subset S(g_0)$. Using the local normal forms in TABLE 1, we see that the deformations of set germs $g_t(\mathbf{R}^2)$ around $0 \in \mathbf{R}^2$ are as depicted in FIGURE 5.

FIGURE 5

Let $F : S^2 \times [-1, 1] \to \mathbf{R}^2$ be a generic fold homotopy such that $0 \in [-1, 1]$ is the unique codimension 1 bifurcation value of F. Then we say that F crosses Γ_1 positively at f_0 if one of the following holds.

(1) When $f_0 \in J^+$, J_1^- and J_2^-, the number of normal crossing points of $f_1(S(f_1))$ is greater than that of $f_{-1}(S(f_{-1}))$.

(2) When $f_0 \in T_1$ and T_2, the number of preimage over a point in the new-born triangle of $f_1(S(f_1))$ is greater than that over a point in the vanishing triangle of $f_{-1}(S(f_{-1}))$.

If a generic fold homotopy F does not satisfy the above property, then we say that F crosses Γ_1 negatively at f_0.

3. Fold eversion between e and $\widetilde{e}$

In this section, we concretely construct a fold eversion $E : S^2 \times [-1, 1] \to \mathbf{R}^2$ between e and $\widetilde{e}$ such that E is a generic fold homotopy.

To describe a variant of such a fold eversion E, we describe a finite series of images of stable fold map, $e_t(D_N^2)$ and $e_t(D_S^2)$, through which the reader can imagine the smooth fold eversion. Note that for any $t \in [-1, 1]$, $e_t|T$ satisfies the conditions (2.1) and (2.2) and e_t is defined by $e_t(x) = E(x, t)$.

The initial stable fold map of E is $e = e_{-1}$ and see FIGURE 6.

FIGURE 6

The stable fold map e_{s_1}, FIGURE 7, is obtained from e by crossing J^+ positively four times.

FIGURE 7

The stable fold map e_{s_2}, FIGURE 8, is obtained from e_{s_1} by crossing J^+, J_1^- and T_1 positively twice, T_2 positively four times and J_2^- negatively twice.

FIGURE 8

The stable fold map e_{s_3}, FIGURE 9, is obtained from e_{s_2} by crossing J^+ and T_1 positively twice and J_2^- negatively once.

FIGURE 9

The stable fold map e_{s_4}, FIGURE 10, is obtained from e_{s_3} by crossing T_2 positively twice.

FIGURE 10

The stable fold map e_{s_5}, FIGURE 11, is obtained from e_{s_4} by crossing J^+ positively twice, T_2 positively four times and J_2^- negatively twice.

FIGURE 11

The stable fold map e_{s_6}, FIGURE 12, is obtained from e_{s_5} with the rotation of $\pi/2$. We see that $e_{s_5}(D_N^2) = e_{s_6}(D_S^2)$ and $e_{s_5}(D_S^2) = e_{s_6}(D_N^2)$ hold if we ignore the orientations on D_N^2 and D_S^2.

FIGURE 12

We obtain the terminal stable fold map, $e_1 = \widetilde{e}$, of E (FIGURE 13) from e_{s_6} by reversing the generic fold homotopy between e and e_{s_5} constructed in FIGURES 6–11

FIGURE 13

Then, we have the desired fold eversion $E : S^2 \times [-1,1] \to \mathbf{R}^2$ between e and $\tilde{e}$. In FIGURES 6–13, we omit the orientations on $e_t(D^2_N), e_t(D^2_S)$ and $\mathbf{R}^2$. Gray strips are the image of rectangles properly embedded in D^2_N and D^2_S, respectively. We draw the gray strips so that they help the readers to understand how to extend $e_t|\partial T$ to $e_t|D^2_N$ and $e_t|D^2_S$ $(t = \{-1, s_1, s_2, \dots, s_6, 1\})$.

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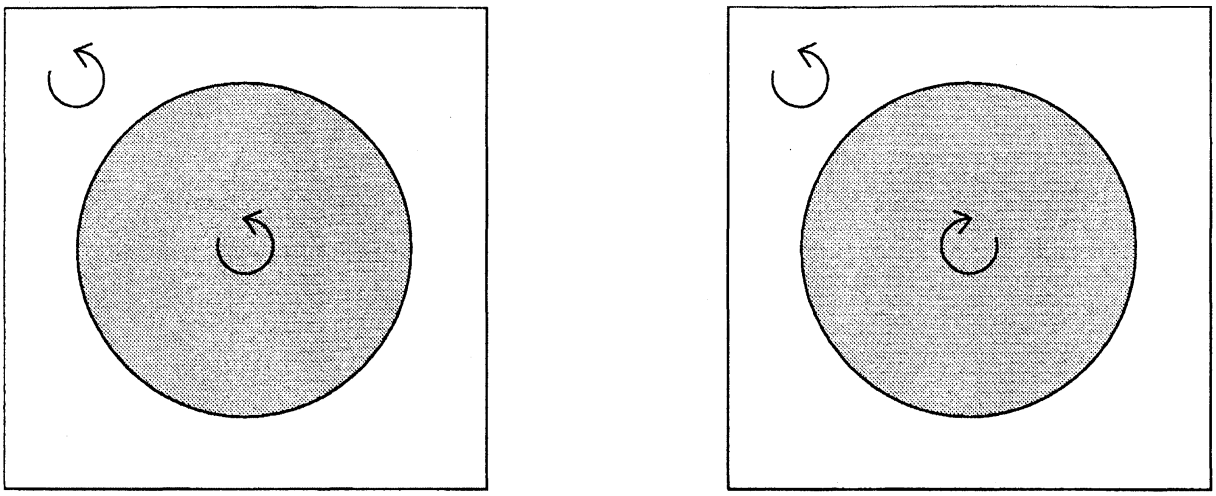
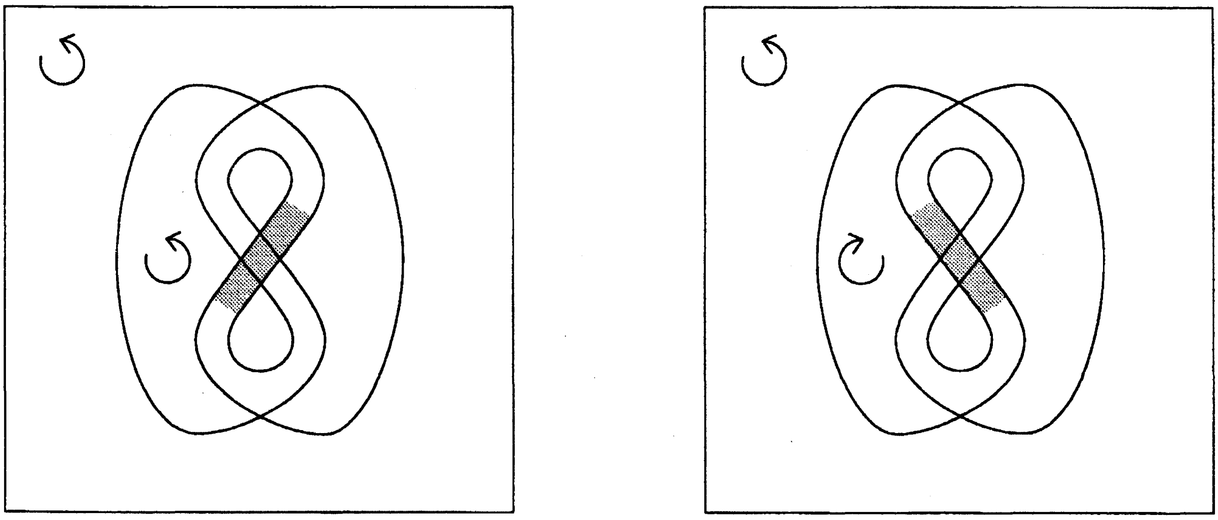


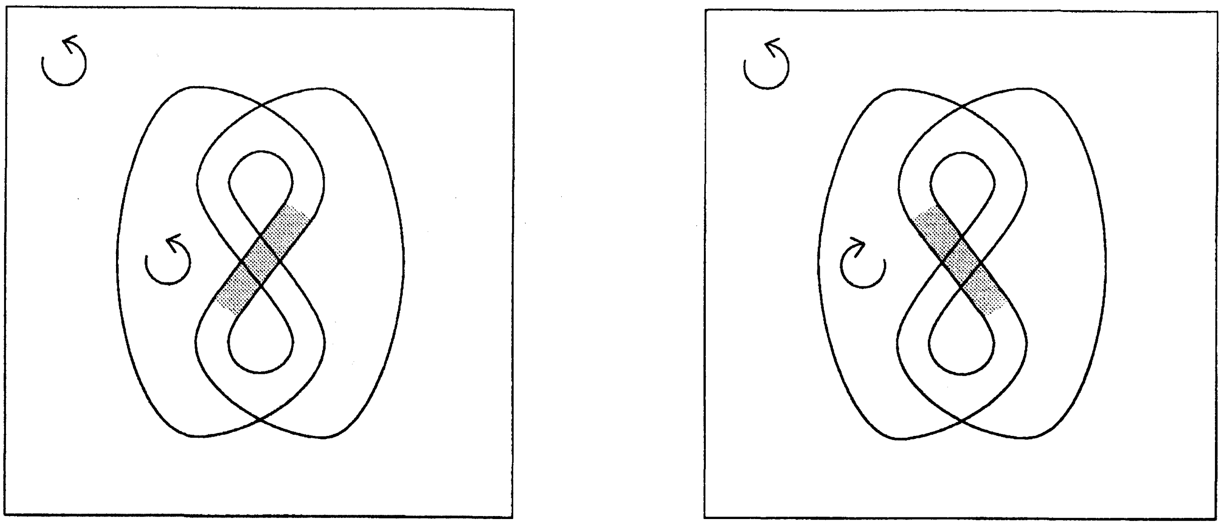
$s(D^2_N)$ $s(D^2_S)$

FIGURE 1. The stable fold map s



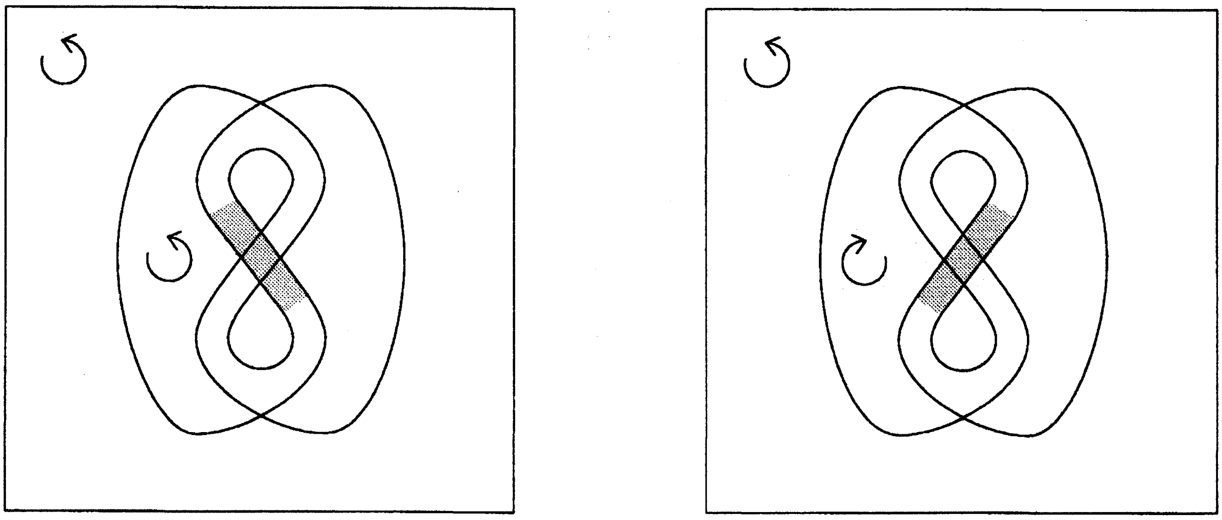
$m_1(D^2)$ $m_2(D^2)$

FIGURE 2. Milnor's examples m_1 and m_2



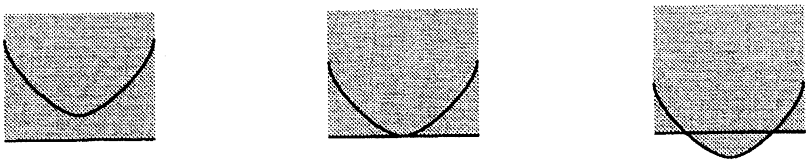
(a) $e(D^2_N)$ (b) $e(D^2_S)$

FIGURE 3. The stable fold map e



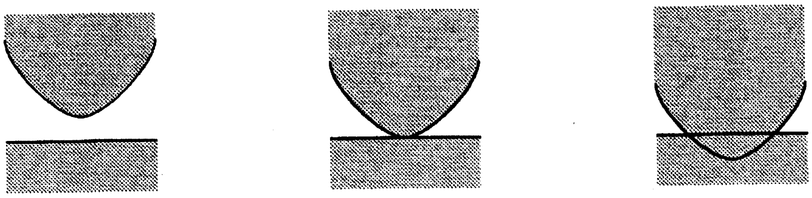
(a) $\widetilde{e}(D^2_N)$ (b) $\widetilde{e}(D^2_S)$

FIGURE 4. The stable fold map $\widetilde{e}$



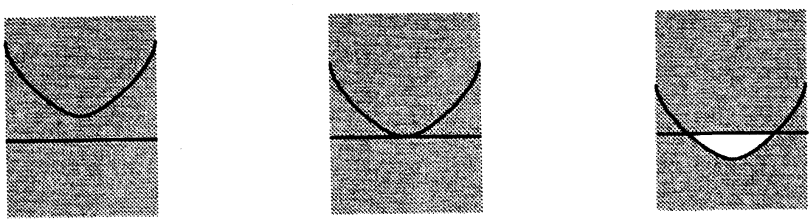
g_{-1} g_0 g_1

(1) if 0 corresponds to J^+



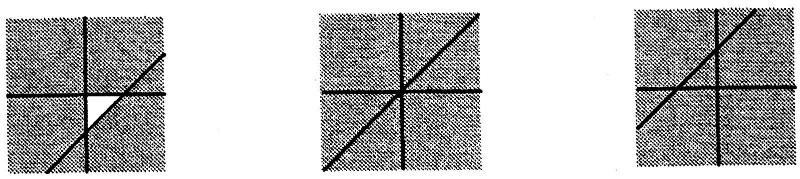
g_{-1} g_0 g_1

(2) if 0 corresponds to J_1^-



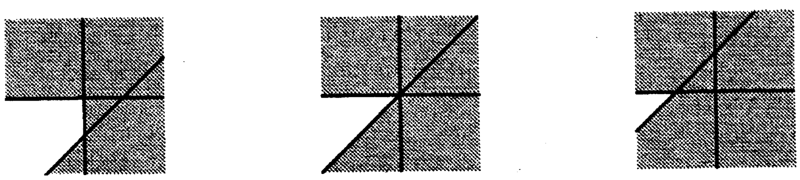
g_{-1} g_0 g_1

(3) if 0 corresponds to J_2^-



g_{-1} g_0 g_1

(4) if 0 corresponds to T_1



g_{-1} g_0 g_1

(5) if 0 corresponds to T_2

FIGURE 5

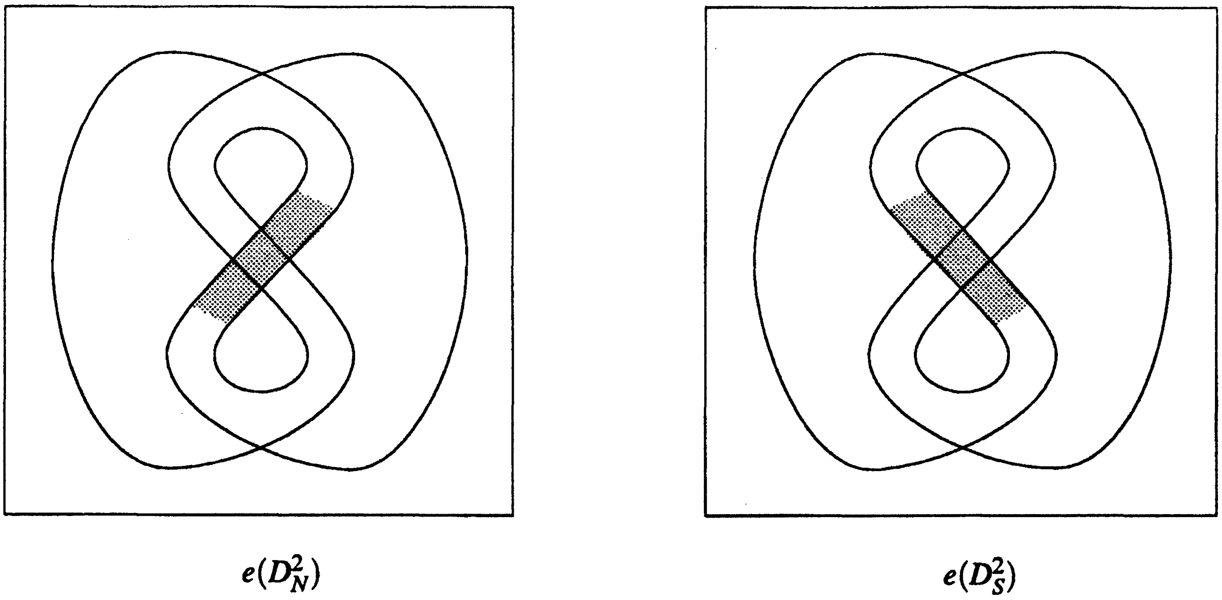


FIGURE 6. The stable fold map e

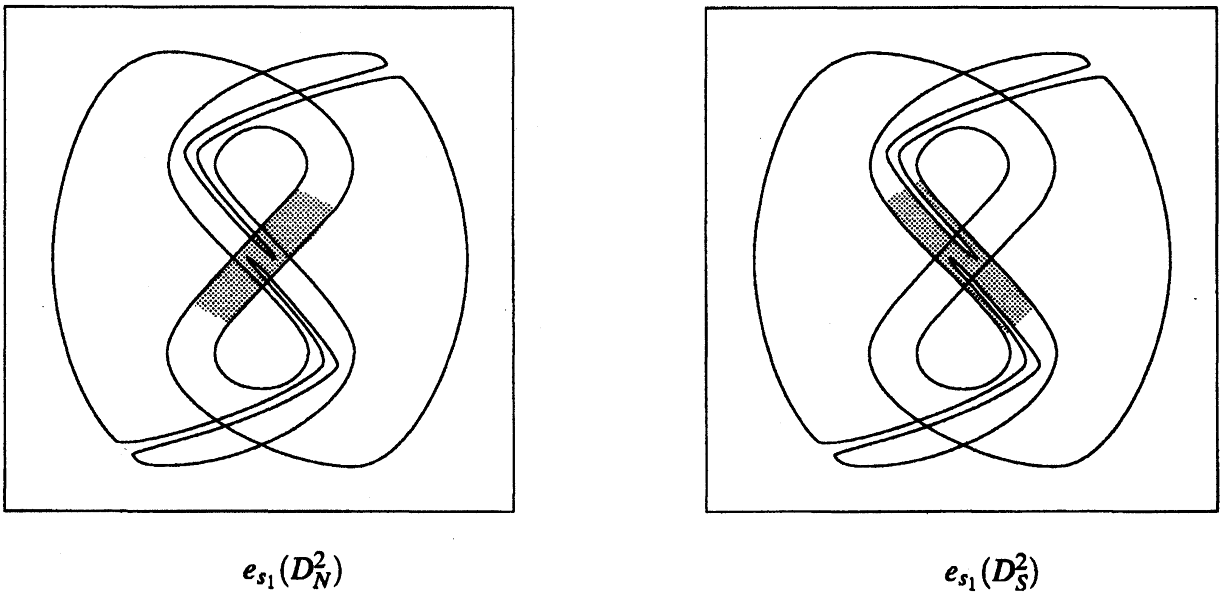
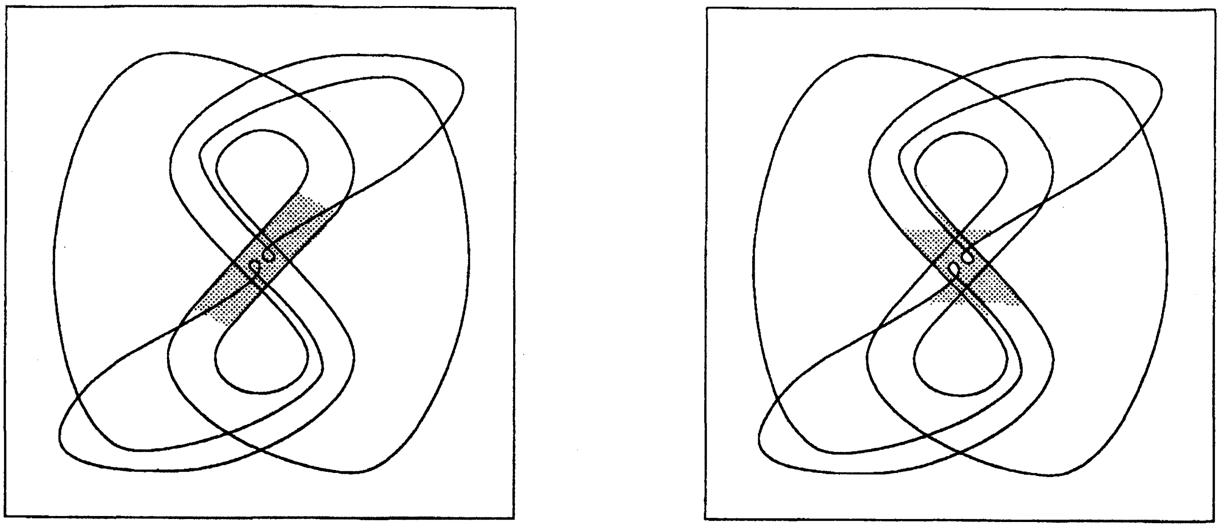
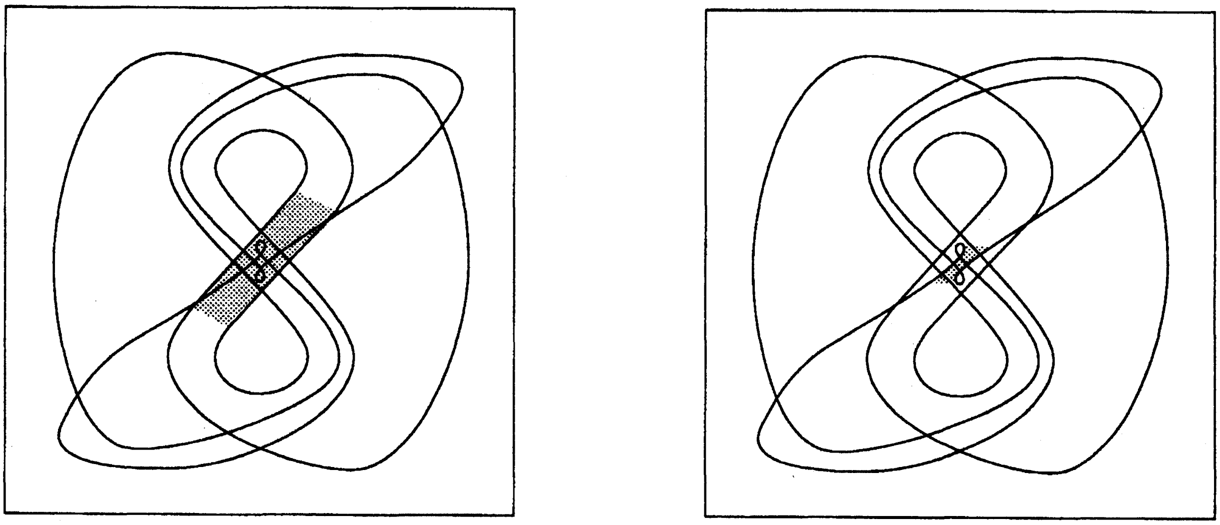


FIGURE 7. The stable fold map e_{s_1}



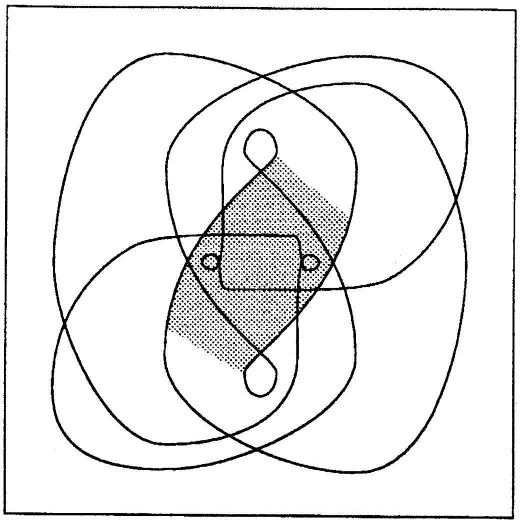
$e_{s_2}(D^2_N)$ $e_{s_2}(D^2_S)$

FIGURE 8. The stable fold map e_{s_2}

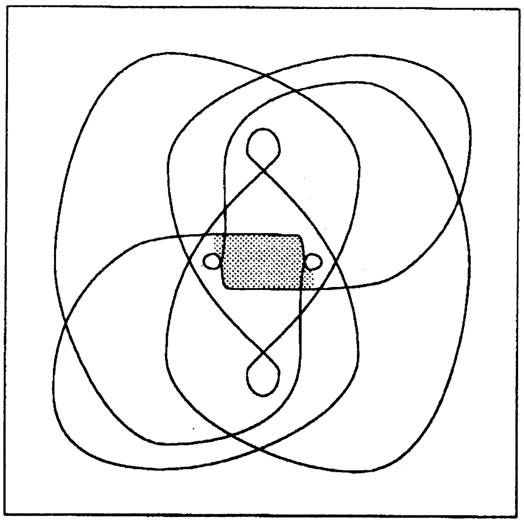


$e_{s_3}(D^2_N)$ $e_{s_3}(D^2_S)$

FIGURE 9. The stable fold map e_{s_3}

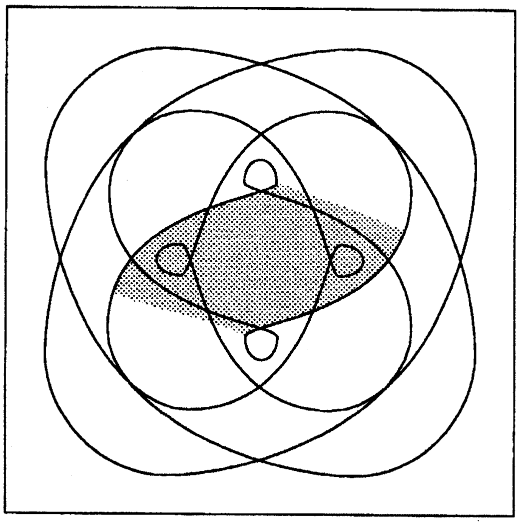


$e_{s_4}(D^2_N)$

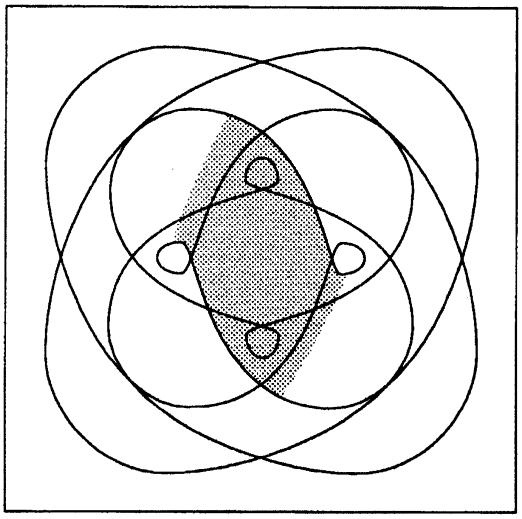


$e_{s_4}(D^2_S)$

FIGURE 10. The stable fold map e_{s_4}

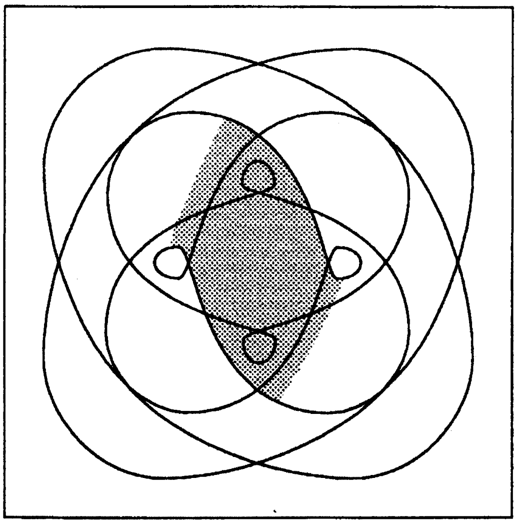


$e_{s_5}(D^2_N)$

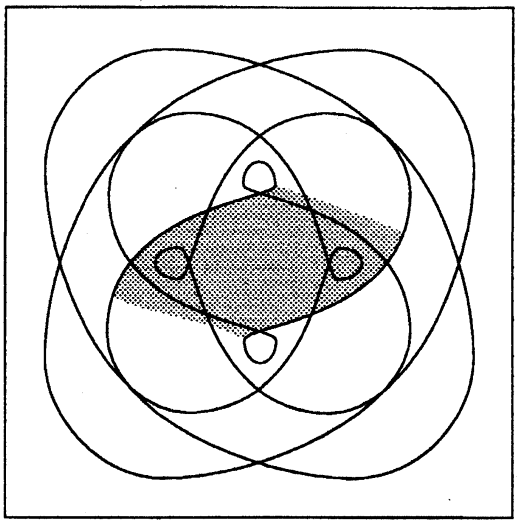


$e_{s_5}(D^2_S)$

FIGURE 11. The stable fold map e_{s_5}

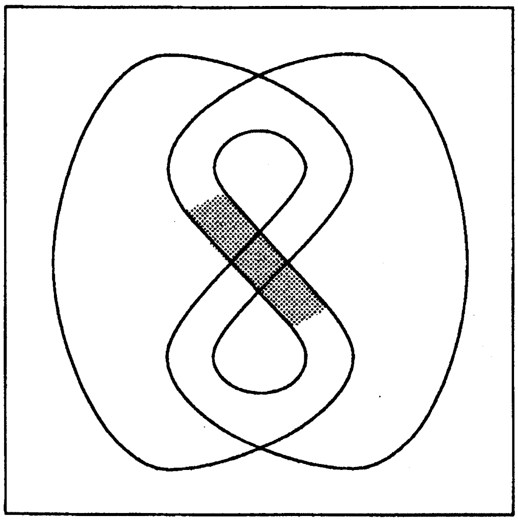


$e_{s_6}(D_N^2)$

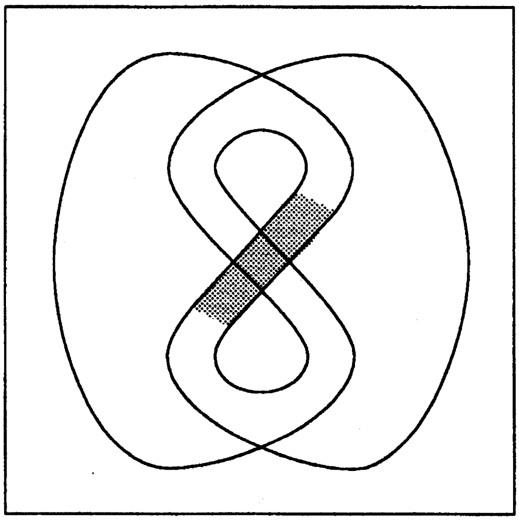


$e_{s_6}(D_S^2)$

FIGURE 12. The stable fold map e_{s_6}



$\widetilde{e}(D_N^2)$



$\widetilde{e}(D_S^2)$

FIGURE 13. The stable fold map $\widetilde{e}$