



last time

$$X = \{x_i\}_{i=1}^n \subseteq \mathbb{R}^d$$

$X_r =$ Rips complex

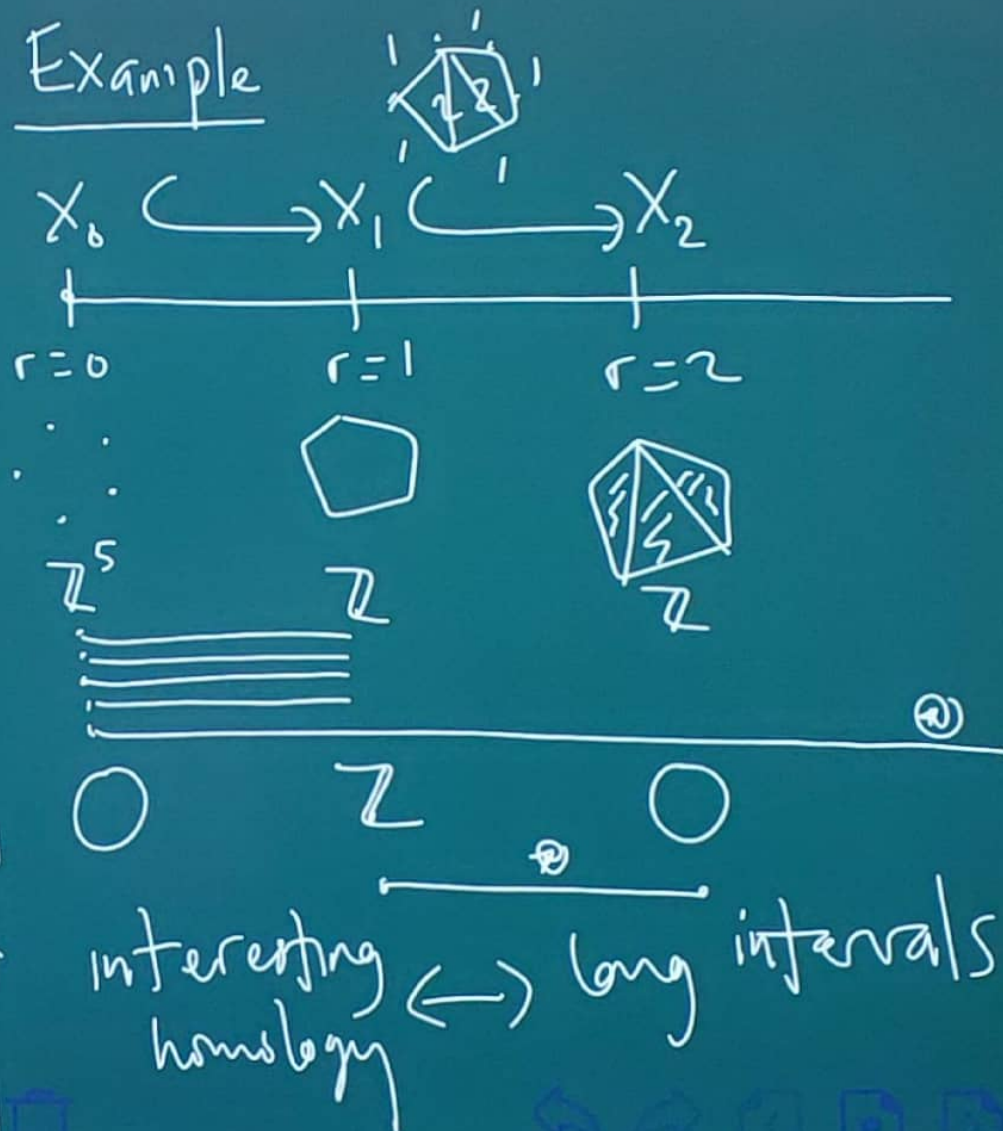
- edges (x_i, x_j) if $d(x_i, x_j) \leq r$

- fill in triangles, tetrahedra etc gives $X_{r_1} \subset X_{r_2} \subset \dots$

H_0

H_1

Example



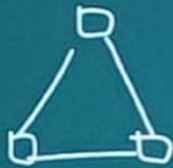


Example

$\vdots$

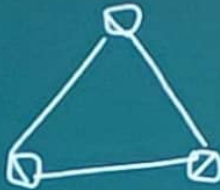
X_0

$\bigcirc$



X_1

$\mathbb{Z}^4$



X_2

$\mathbb{Z}$



X_{10}

$\bigcirc$

H_1

Technical notes

• R probably uses $\mathbb{Z}_2$ coefficients not $\mathbb{Z}$

$$\sum_{n, \sigma_1, \dots, \sigma_k} n_i \in \mathbb{Z}_2$$

$$\sum_{n, \sigma_1, \dots, \sigma_k} n_i \in \mathbb{Z}$$

C_k



$$X = \{x_i\}_{i=1}^n \subseteq \mathbb{R}^d$$

$X_r \approx \Delta^{n-1}$ for r large enough

Δ^{n-1} contains $2^{n-1} - 1$

subsimplices

— can't compute everything

n vertices

$\binom{n}{2}$ edges $\sim n^2$

$\binom{n}{3}$ faces $\sim n^3$

• significance?

— subsample probability measure

can compute H_0, H_1, H_2

Questions / problems

• errors? stability $\checkmark$

• noise? — clean up data e.g. (choose points with many nearest neighbours)





Homotopy

idea $f: X \rightarrow Y$
cts

want continuously varying families of maps

examples



Defn A homotopy is a map

$$F: X \times I \longrightarrow Y$$

cts

notation $f_t(x) = F(x, t)$

A homotopy between $f: X \rightarrow Y$
 $g: X \rightarrow Y$
is a map $F: X \times I \rightarrow Y$

$$\text{s.t. } f_0(x) = f(x)$$

$$f_1(x) = g(x)$$

$$I = [0, 1]$$

$$\begin{array}{c|c|c} 0 & 1 & \in \mathbb{R} \end{array}$$



Homotopy

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$$I = [0, 1]$$

$$\frac{1}{0} \quad \frac{1}{1} < \mathbb{R}$$

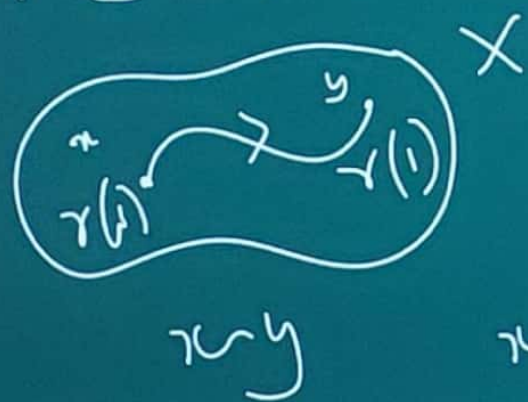


This is interesting
even for $X = \{pt\}$

$$\nexists \underbrace{\{pt\} \times I}_{\cong I} \longrightarrow Y$$

also called paths

$$\gamma: I \longrightarrow Y$$



Define an equivalence relation on X

$x \sim y$ if there is path $\gamma: I \longrightarrow X$
s.t. $\gamma(0) = x$ $\gamma(1) = y$

check • reflexive $x \sim x$

$$\gamma: I \longrightarrow x \quad \text{constant path} \quad \Rightarrow x \sim x \quad \checkmark$$

"0,1"

• symmetry $x \sim y \Rightarrow y \sim x$

$$x \sim y \Rightarrow \exists \gamma: I \longrightarrow X \text{ with } \gamma(0) = x, \gamma(1) = y$$

reverse path

$$\bar{\gamma}: I \longrightarrow X$$

$$\bar{\gamma}(t) = \gamma(1-t)$$

$$\Rightarrow y \sim x \quad \checkmark$$



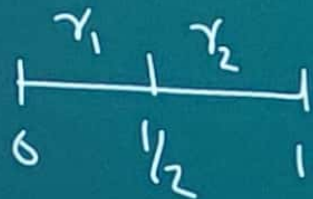
transitive $x \sim y, y \sim z \Rightarrow x \sim z$



notation $f \circ g$
function composition

then $\gamma_1 \cdot \gamma_2$ is a path
from x to z so
 $x \sim z$ ✓

define $\gamma_1 \cdot \gamma_2$
path composition



$$I \longrightarrow X$$

$$t \longmapsto \begin{cases} \gamma_1(2t) & 0 \leq t \leq \frac{1}{2} \\ \gamma_2(2t-1) & \frac{1}{2} \leq t \leq 1 \end{cases}$$

note this is cts as
 $\gamma_1(1) = \gamma_2(0)$

so this is an
equivalence relation $\square$

Defn equivalence
classes are called
the path components of X



Examples

$$\bullet \quad \bigcirc S^1 \quad \bigcirc S^1 \quad S^1 \times S^1$$

↑ 1-path component

↔ X is path connected

Observation $X \cong Y$
↑
homeo

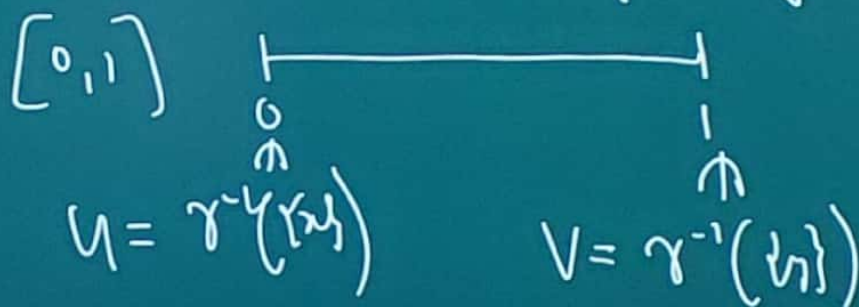
⇒ same # of path components



$$\bullet \quad S^0 = \{x, y\} \quad \text{Prop}^n \quad \text{Two path components}$$

Proof suppose $\gamma: I \rightarrow S^0$ s.t. $\gamma(0) = x$ and $\gamma(1) = y$, γ is so $f^{-1}(\text{open set})$ is open $\{x\}, \{y\}$ open in S^0

consider $\gamma^{-1}(\{x\}), \gamma^{-1}(\{y\})$





$$[0,1] = \begin{array}{c} \text{---} \\ | \quad \quad | \\ \cap \quad \quad \cap \\ \cup \quad \quad \cup \\ \text{open} \end{array}$$

$$U \cap V = \emptyset$$

$$\sup(U) = \text{least upper bound} = s$$

for all $t \in U$ $t \leq s$
and no other upper bound $< s$

Case 1 $s \in U$

there is $(a,b) \subseteq U$
 $s \in (a,b) \subseteq U$

so $\exists t \in U$ $t > s$ ~~upper bound~~

Case 2 $s \in V$

there is $s \in (a,b) \subseteq V$

so $\exists t < s$ which is
also an upper bound for U

least upper bound

so no map $I \rightarrow \{u,v\}$



Fact discrete set of n points has n path components

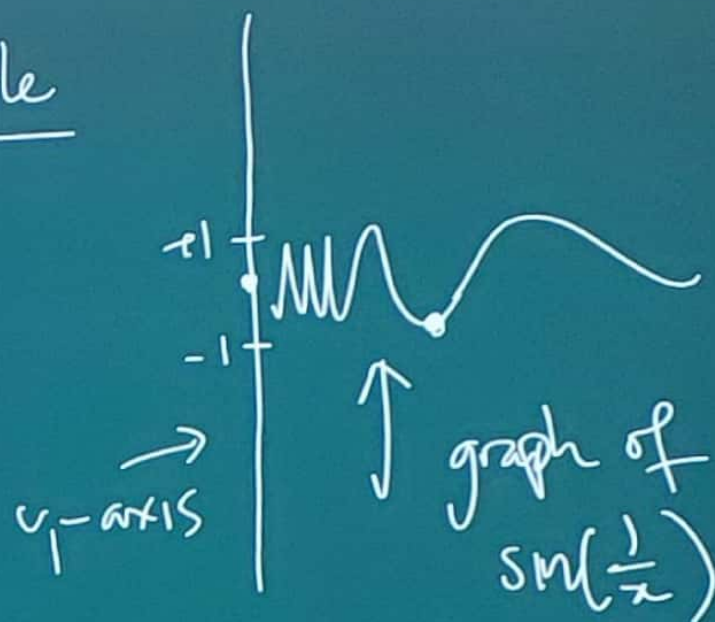
Warning connected $\neq$ path connected

Defn

X is connected if it is not the disjoint union of two open sets

Last $\Rightarrow [0, 1]$ connected

Example

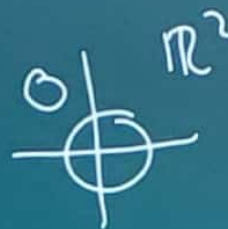


$X = \text{union of } y\text{-axis and graph of } \sin(1/x) \subseteq \mathbb{R}^2$

with induced topology
 X not Δ -complex



Application



Thm $\mathbb{R}^1 \not\cong \mathbb{R}^2$

Proof suppose $f: \mathbb{R}^1 \rightarrow \mathbb{R}^2$ is
a homeomorphism

$\mathbb{R} \xrightarrow{f} \mathbb{R}^2$

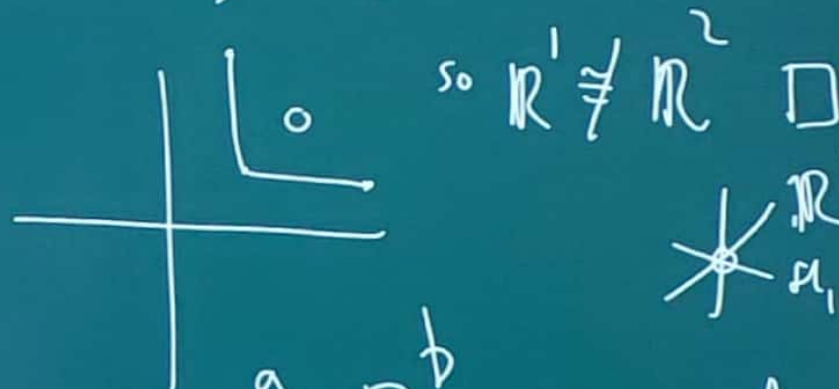


gives a homeomorphism

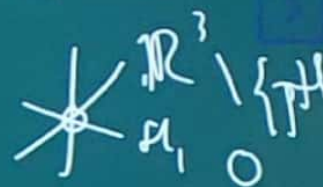
$f: \mathbb{R} \setminus \{0\} \rightarrow \mathbb{R}^2 \setminus \{f(0)\}$

$\mathbb{R} \setminus \{0\} \xrightarrow{(-1,0)} \xleftarrow{(0,1)}$
not path connected

$\mathbb{R}^2 \setminus \{0\}$ is path connected



so $\mathbb{R}^1 \not\cong \mathbb{R}^2 \quad \square$

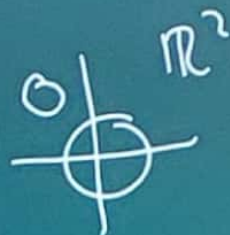


Thm $\mathbb{R}^a \cong \mathbb{R}^b \Rightarrow a=b$

Proof use homology $\square$



Application



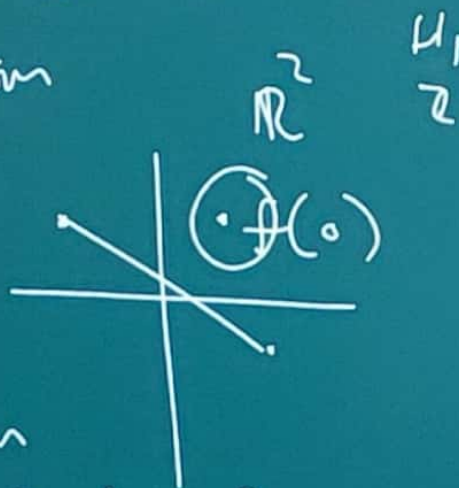
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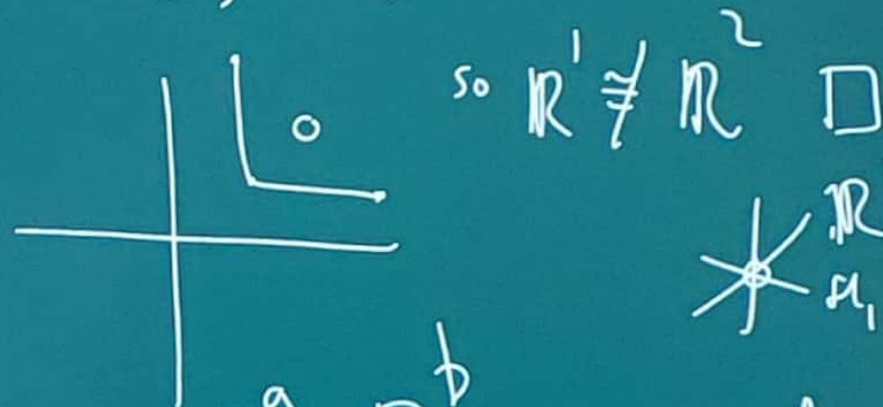
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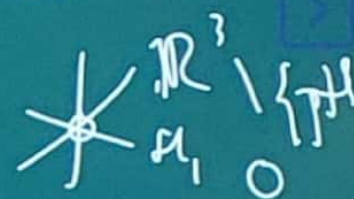


$\mathbb{R} \setminus \{0\} \xrightarrow{(-2,0)} \xleftarrow{(0,2)}$
not path connected

$\mathbb{R}^2 \setminus \{0\}$ is path connected



so $\mathbb{R}^1 \not\cong \mathbb{R}^2 \quad \square$



Thm $\mathbb{R}^a \cong \mathbb{R}^b \Rightarrow a=b$

Proof use homology $\square$