Nice spaces with bad reputations and political correctness of the mathematical language

Oleg Viro

May 20, 2011

is a set of efforts to implement language standards aimed to protect against talking about things that are bad, unpleasant, or insulting.

is a set of efforts to implement language standards aimed to protect against talking about things that are bad, unpleasant, or insulting.

Mathematics has no right to be ugly.

is a set of efforts to implement language standards aimed to protect against talking about things that are bad, unpleasant, or insulting.

Mathematics has no right to be ugly.

Mathematicians like to exercise their tastes.

is a set of efforts to implement language standards aimed to protect against talking about things that are bad, unpleasant, or insulting.

Mathematics has no right to be ugly.

Mathematicians like to exercise their tastes.

Political correctness in Mathematics is a sad unavoidable reality

is a set of efforts to implement language standards aimed to protect against talking about things that are bad, unpleasant, or insulting.

Mathematics has no right to be ugly.

Mathematicians like to exercise their tastes.

Political correctness in Mathematics is a sad unavoidable reality,

it distorts the ways we do mathematics.

Differential Spaces

- Differentiable Manifolds
- What is wrong
- Political correctness
- in Mathematics
- Publications
- Differential Structures
- Differential Spaces
- Differentiable maps
- Generating, refining, relaxing
- Subspaces
- Embeddings
- Example
- Constructing new differential spaces
- Examples of quotient spaces
- Tangent vectors and dimensions
- Metric spaces

Finite Topological

Spaces

Differential Spaces

Differentiable Manifolds

The modern definition of differentiable manifold was given in the book by O. Veblen and J.H.C. Whitehead The foundations of differential geometry. Cambridge tracts in mathematics and mathematical physics.

Differentiable Manifolds

The modern definition of differentiable manifold was given in the book by O. Veblen and J.H.C. Whitehead The foundations of differential geometry. Cambridge tracts in mathematics and mathermatical physics. Published in 1932 by Cambridge University Press.

Differentiable Manifolds

The modern definition of differentiable manifold was given in the book by O. Veblen and J.H.C. Whitehead The foundations of differential geometry. Cambridge tracts in mathematics and mathermatical physics. Published in 1932 by Cambridge University Press. Inspired by H.Weyl's book on Riemann surfaces Die Idee der Riemannschen Fläche published in 1913.

The traditional definition of smooth structures is quite long

The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures

The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures studied in algebraic geometry and topology.

The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures studied in algebraic geometry and topology.

Smooth structures are traditionally defined only on manifolds.

The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures studied in algebraic geometry and topology.

Smooth structures are traditionally defined only on manifolds. This deprives us of flexibility that we enjoy in general topology

The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures studied in algebraic geometry and topology.

Smooth structures are traditionally defined only on manifolds. This deprives us of flexibility that we enjoy in general topology, where any set-theoretic construction has a topological counter-part:

The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures studied in algebraic geometry and topology.

Smooth structures are traditionally defined only on manifolds. This deprives us of flexibility that we enjoy in general topology, where any set-theoretic construction has a topological counter-part: a subset \mapsto a subspace,

The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures studied in algebraic geometry and topology.

Smooth structures are traditionally defined only on manifolds. This deprives us of flexibility that we enjoy in general topology, where any set-theoretic construction has a topological counter-part: a subset \mapsto a subspace,

a quotient set \mapsto a quotient space, etc.

The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures studied in algebraic geometry and topology.

Smooth structures are traditionally defined only on manifolds. This deprives us of flexibility that we enjoy in general topology, where any set-theoretic construction has a topological counter-part: a subset \mapsto a subspace,

a quotient set \mapsto a quotient space, etc.

The image of a differential manifold under a differentiable map may be not a manifold,

The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures studied in algebraic geometry and topology.

Smooth structures are traditionally defined only on manifolds. This deprives us of flexibility that we enjoy in general topology, where any set-theoretic construction has a topological counter-part: a subset \mapsto a subspace,

a quotient set \mapsto a quotient space, etc.

The image of a differential manifold under a differentiable map may be not a manifold, and hence not eligible to bear any trace of a differential structure.

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this good?

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this good?

Is this *acceptable*?

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this good?

Is this acceptable?

Even if you hate pathology

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good?* Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good*? Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Would you like to have an *ability to speak* about

the natural smooth structure on $\mathbb{C}P^2/\operatorname{conj}$?

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good*? Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Would you like to have an *ability to speak* about

the natural smooth structure on $\mathbb{C}P^2/\operatorname{conj}$?

smooth structure on a Cantor set?

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good*? Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Would you like to have an *ability to speak* about

the natural smooth structure on $\mathbb{C}P^2/\operatorname{conj}$? smooth structure on a Cantor set? on a fractal set?

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good*? Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Would you like to have an *ability to speak* about

the natural smooth structure on $\mathbb{C}P^2/\operatorname{conj}$?

smooth structure on a Cantor set?

on a fractal set?

The notion of *differential space* was developed in the sixties

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good*? Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Would you like to have an *ability to speak* about

the natural smooth structure on $\mathbb{C}P^2/\operatorname{conj}$? smooth structure on a Cantor set?

on a fractal set?

The notion of *differential space* was developed in the sixties, but has not found a way to the mainstream Mathematics.

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good*? Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Would you like to have an *ability to speak* about

the natural smooth structure on $\mathbb{C}P^2/\operatorname{conj}$? smooth structure on a Cantor set?

on a fractal set?

The notion of *differential space* was developed in the sixties, but has not found a way to the mainstream Mathematics.

Why?

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good?* Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Would you like to have an *ability to speak* about

the natural smooth structure on $\mathbb{C}P^2/\operatorname{conj}$? smooth structure on a Cantor set?

on a fractal set?

The notion of *differential space* was developed in the sixties, but has not found a way to the mainstream Mathematics.

Why? Was it not a right time for this?

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good?* Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Would you like to have an *ability to speak* about

the natural smooth structure on $\mathbb{C}P^2/\operatorname{conj}$? smooth structure on a Cantor set?

on a fractal set?

The notion of *differential space* was developed in the sixties, but has not found a way to the mainstream Mathematics.

Why? Was it not a right time for this?

Late sixties.

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good*? Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Would you like to have an *ability to speak* about

the natural smooth structure on $\mathbb{C}P^2/\operatorname{conj}$? smooth structure on a Cantor set?

on a fractal set?

Late sixties.

The notion of *differential space* was developed in the sixties, but has not found a way to the mainstream Mathematics.

Why? Was it not a right time for this? Were there not right people?

Terminology related to differentiable manifolds

does not let us speak on bad spaces.

Is this *good*? Is this *acceptable*?

Even if you hate pathology,

do you know beforehand what is pathologically bad in Mathematics?

Would you like to have an *ability to speak* about

the natural smooth structure on $\mathbb{C}P^2/\operatorname{conj}$? smooth structure on a Cantor set?

on a fractal set?

The notion of *differential space* was developed in the sixties, but has not found a way to the mainstream Mathematics.

Why? Was it not a right time for this?Late sixties.Were there not right people?R. Sikorski, M. A. Mostow, Kuo-Tsai Chen.

Publications

Publications

1. Roman Sikorski, Abstract covariant derivative, 18 (1967) 251-272.

Publications

- 1. Roman Sikorski, Abstract covariant derivative, 18 (1967) 251-272.
- Mostow M. A., *The differentiable space structures of Milnor classifying spaces, simplicial complexes, and geometric realizations*, J. Diff. Geom., 14, 1979, 255-293.

Publications

- 1. Roman Sikorski, Abstract covariant derivative, 18 (1967) 251-272.
- Mostow M. A., *The differentiable space structures of Milnor classifying spaces, simplicial complexes, and geometric realizations*, J. Diff. Geom., 14, 1979, 255-293.
- 3. Juan A. Navarro Gonzales, Juan B. Sanch de Salas, C^{∞} -Differential Spaces, Springer, 2003.

Let X be a set and r be a natural number or ∞ .

Let X be a set and r be a natural number or ∞ . A differential structure of class C^r on X

Let X be a set and r be a natural number or ∞ . A differential structure of class C^r on X

not differentiable, but differential, for nobody is going to differentiate it!

Let X be a set and r be a natural number or ∞ . A *differential structure* of class C^r on Xis an algebra $\mathcal{C}^r(X)$ of functions $X \to \mathbb{R}$ such that:

Let X be a set and r be a natural number or ∞ . A *differential structure* of class C^r on Xis an algebra $\mathcal{C}^r(X)$ of functions $X \to \mathbb{R}$ such that:

Let X be a set and r be a natural number or ∞ . A *differential structure* of class C^r on Xis an algebra $\mathcal{C}^r(X)$ of functions $X \to \mathbb{R}$ such that:

1. Composition of functions belonging to $C^r(X)$ with C^r -differentiable function belongs to $C^r(X)$.

Let X be a set and r be a natural number or ∞ . A *differential structure* of class C^r on X is an algebra $\mathcal{C}^r(X)$ of functions $X \to \mathbb{R}$ such that: 1 *Composition of functions belonging to* $\mathcal{C}^r(X)$ *with* C^r -differentiable

1. Composition of functions belonging to $C^r(X)$ with C^r -differentiable function belongs to $C^r(X)$.

In other words, $(g \circ f : X \to \mathbb{R}) \in \mathcal{C}^r(X)$

Let X be a set and r be a natural number or ∞ . A *differential structure* of class C^r on X is an algebra $\mathcal{C}^r(X)$ of functions $X \to \mathbb{R}$ such that:

1. Composition of functions belonging to $\mathcal{C}^r(X)$ with C^r -differentiable function belongs to $\mathcal{C}^r(X)$.

In other words, $(g \circ f : X \to \mathbb{R}) \in \mathcal{C}^r(X)$ if $f : X \to U$ is defined by $f_1, \ldots, f_n \in \mathcal{C}^r(X)$, $U \subset \mathbb{R}^n$ is an open set,

Let X be a set and r be a natural number or ∞ . A *differential structure* of class C^r on X is an algebra $\mathcal{C}^r(X)$ of functions $X \to \mathbb{R}$ such that:

1. Composition of functions belonging to $\mathcal{C}^r(X)$ with C^r -differentiable function belongs to $\mathcal{C}^r(X)$.

In other words, $(g \circ f : X \to \mathbb{R}) \in \mathcal{C}^r(X)$ if $f : X \to U$ is defined by $f_1, \ldots, f_n \in \mathcal{C}^r(X)$, $U \subset \mathbb{R}^n$ is an open set, and $g : U \to \mathbb{R}$ is a C^r -map.

Let X be a set and r be a natural number or ∞ . A *differential structure* of class C^r on X is an algebra $\mathcal{C}^r(X)$ of functions $X \to \mathbb{R}$ such that:

1. Composition of functions belonging to $\mathcal{C}^r(X)$ with C^r -differentiable function belongs to $\mathcal{C}^r(X)$.

In other words, $(g \circ f : X \to \mathbb{R}) \in \mathcal{C}^r(X)$ if $f : X \to U$ is defined by $f_1, \ldots, f_n \in \mathcal{C}^r(X)$, $U \subset \mathbb{R}^n$ is an open set, and $g : U \to \mathbb{R}$ is a C^r -map.

2. $f \in \mathcal{C}^r(X)$ if near each point of X it coincides with a function belonging to $\mathcal{C}^r(X)$.

Let X be a set and r be a natural number or ∞ . A *differential structure* of class C^r on X

is an algebra $\mathcal{C}^r(X)$ of functions $X \to \mathbb{R}$ such that:

1. Composition of functions belonging to $C^r(X)$ with C^r -differentiable function belongs to $C^r(X)$.

In other words, $(g \circ f : X \to \mathbb{R}) \in \mathcal{C}^r(X)$ if $f : X \to U$ is defined by $f_1, \ldots, f_n \in \mathcal{C}^r(X)$, $U \subset \mathbb{R}^n$ is an open set, and $g : U \to \mathbb{R}$ is a C^r -map.

2. $f \in \mathcal{C}^r(X)$ if near each point of X it coincides with a function belonging to $\mathcal{C}^r(X)$.

In other words, $f \in C^r(X)$ if for each $a \in X$ there exist $g, h \in C^r(X)$ such that h(a) > 0 and f(x) = g(x) for each x with h(x) > 0.

A pair (a set X, a differential structure of class C^r on X) is called a *differential space of class* C^r

A pair (a set X, a differential structure of class C^r on X) is called a *differential space of class* C^r , or just a C^r -space.

A pair (a set X, a differential structure of class C^r on X) is called a *differential space of class* C^r , or just a C^r -space.

Examples

A pair (a set X, a differential structure of class C^r on X) is called a *differential space of class* C^r , or just a C^r -space.

Examples

1. Any smooth manifold X with algebra of C^r -differentiable functions.

A pair (a set X, a differential structure of class C^r on X) is called a *differential space of class* C^r , or just a C^r -space.

Examples

- 1. Any smooth manifold X with algebra of C^r -differentiable functions.
- 2. Discrete space. Any X and all functions $X \to \mathbb{R}$.

A pair (a set X, a differential structure of class C^r on X) is called a *differential space of class* C^r , or just a C^r -space.

Examples

- 1. Any smooth manifold X with algebra of C^r -differentiable functions.
- 2. Discrete space. Any X and all functions $X \to \mathbb{R}$.
- 3. *Indiscrete space.* Any X and all constant functions $X \to \mathbb{R}$.

A pair (a set X, a differential structure of class C^r on X) is called a *differential space of class* C^r , or just a C^r -space.

Examples

- 1. Any smooth manifold X with algebra of C^r -differentiable functions.
- 2. Discrete space. Any X and all functions $X \to \mathbb{R}$.
- 3. *Indiscrete space.* Any X and all constant functions $X \to \mathbb{R}$.

4. Topological space. A topological space X with all continuous functions $X \to \mathbb{R}$.

Let X and Y be C^r -spaces.

Let X and Y be C^r -spaces.

 $f: X \to Y$ is called a C^r -map if $f \circ \phi \in \mathcal{C}^r(X)$ for any $\phi \in \mathcal{C}^r(Y)$.

Let X and Y be C^r -spaces. $f: X \to Y$ is called a C^r -map if $f \circ \phi \in \mathcal{C}^r(X)$ for any $\phi \in \mathcal{C}^r(Y)$.

A $C^r\text{-map }f:X\to Y \text{ induces }f^*:\mathcal{C}^r(Y)\to \mathcal{C}^r(X)$.

Let X and Y be C^r -spaces.

 $f: X \to Y$ is called a C^r -map if $f \circ \phi \in \mathcal{C}^r(X)$ for any $\phi \in \mathcal{C}^r(Y)$.

A C^r -map $f: X \to Y$ induces $f^*: \mathcal{C}^r(Y) \to \mathcal{C}^r(X)$.

 C^r -spaces and C^r -maps constitute a category.

Let X and Y be C^r -spaces.

 $f: X \to Y$ is called a C^r -map if $f \circ \phi \in \mathcal{C}^r(X)$ for any $\phi \in \mathcal{C}^r(Y)$.

A C^r -map $f: X \to Y$ induces $f^*: \mathcal{C}^r(Y) \to \mathcal{C}^r(X)$.

 C^r -spaces and C^r -maps constitute a category.

Isomorphisms of this category are called C^r -diffeomorphims.

For any set \mathcal{F} of real valued functions on a set X, there exists a minimal C^r -structure on X containing \mathcal{F} .

For any set \mathcal{F} of real valued functions on a set X, there exists a minimal C^r -structure on X containing \mathcal{F} . It is said to be *generated* by \mathcal{F} .

For any set \mathcal{F} of real valued functions on a set X, there exists a minimal C^r -structure on X containing \mathcal{F} . It is said to be *generated* by \mathcal{F} .

For example, the coordinate projections $\mathbb{R}^n \to \mathbb{R}$ generate the standard differential structure on \mathbb{R}^n .

For any set \mathcal{F} of real valued functions on a set X, there exists a minimal C^r -structure on X containing \mathcal{F} . It is said to be *generated* by \mathcal{F} .

For example, the coordinate projections $\mathbb{R}^n \to \mathbb{R}$ generate the standard differential structure on \mathbb{R}^n .

The C^r -structure generated by a C^s -structure \mathcal{C} with s < r

coincides with \mathcal{C} .

For any set \mathcal{F} of real valued functions on a set X, there exists a minimal C^r -structure on X containing \mathcal{F} . It is said to be *generated* by \mathcal{F} .

For example, the coordinate projections $\mathbb{R}^n \to \mathbb{R}$ generate the standard differential structure on \mathbb{R}^n .

The C^r -structure generated by a C^s -structure \mathcal{C} with s < r

coincides with ${\mathcal C}$.

For example, a C^0 -structure

For any set \mathcal{F} of real valued functions on a set X, there exists a minimal C^r -structure on X containing \mathcal{F} . It is said to be *generated* by \mathcal{F} .

For example, the coordinate projections $\mathbb{R}^n \to \mathbb{R}$ generate the standard differential structure on \mathbb{R}^n .

The C^r -structure generated by a C^s -structure \mathcal{C} with s < r

coincides with ${\mathcal C}$.

For example, a C^0 -structure

which is nothing but a topological structure.

For any set \mathcal{F} of real valued functions on a set X, there exists a minimal C^r -structure on X containing \mathcal{F} . It is said to be *generated* by \mathcal{F} .

For example, the coordinate projections $\mathbb{R}^n \to \mathbb{R}$ generate the standard differential structure on \mathbb{R}^n .

The C^r -structure generated by a C^s -structure \mathcal{C} with s < r

coincides with ${\cal C}$.

For example, a C^0 -structure is a C^r -structure for any r.

For any set \mathcal{F} of real valued functions on a set X, there exists a minimal C^r -structure on X containing \mathcal{F} . It is said to be *generated* by \mathcal{F} .

For example, the coordinate projections $\mathbb{R}^n \to \mathbb{R}$ generate the standard differential structure on \mathbb{R}^n .

The C^r -structure generated by a C^s -structure \mathcal{C} with s < r

coincides with ${\cal C}$.

For example, a C^0 -structure is a C^r -structure for any r.

On the other hand, when decreasing r, we have to add new functions.

For any set \mathcal{F} of real valued functions on a set X, there exists a minimal C^r -structure on X containing \mathcal{F} . It is said to be *generated* by \mathcal{F} .

For example, the coordinate projections $\mathbb{R}^n \to \mathbb{R}$ generate the standard differential structure on \mathbb{R}^n .

The C^r -structure generated by a C^s -structure \mathcal{C} with s < r coincides with \mathcal{C} .

For example, a C^0 -structure is a C^r -structure for any r.

On the other hand, when decreasing r, we have to add new functions.

A C^r -structure \mathcal{A} generated as a C^r -structure by a C^s -structure \mathcal{B} with s > r is called a *relaxation* of \mathcal{B} .

For any set \mathcal{F} of real valued functions on a set X, there exists a minimal C^r -structure on X containing \mathcal{F} . It is said to be *generated* by \mathcal{F} .

For example, the coordinate projections $\mathbb{R}^n \to \mathbb{R}$ generate the standard differential structure on \mathbb{R}^n .

The C^r -structure generated by a C^s -structure \mathcal{C} with s < r coincides with \mathcal{C} .

For example, a C^0 -structure is a C^r -structure for any r.

On the other hand, when decreasing r, we have to add new functions.

A C^r -structure \mathcal{A} generated as a C^r -structure by a C^s -structure \mathcal{B} with s > r is called a *relaxation* of \mathcal{B} . Then \mathcal{B} is called a *refinement* of \mathcal{A} .

Let X be a differential space and $A \subset X$.

Let X be a differential space and $A \subset X$. Restrictions to A of functions differentiable on X

Let X be a differential space and $A \subset X$. Restrictions to A of functions differentiable on X

do not necessarily constitute a differential structure on A.

Let X be a differential space and $A \subset X$. Restrictions to A of functions differentiable on Xdo not necessarily constitute a differential structure on A.

For example, if $X = \mathbb{R}$ and $A = \mathbb{R}_{>0} = \{x \mid x > 0\}$, then

Let X be a differential space and $A \subset X$. Restrictions to A of functions differentiable on Xdo not necessarily constitute a differential structure on A.

For example, if $X = \mathbb{R}$ and $A = \mathbb{R}_{>0} = \{x \mid x > 0\}$, then

 $A \to \mathbb{R} : x \mapsto \frac{1}{x}$ is not a restriction of any function continuous on \mathbb{R} ,

Let X be a differential space and $A \subset X$. Restrictions to A of functions differentiable on Xdo not necessarily constitute a differential structure on A. For example, if $X = \mathbb{R}$ and $A = \mathbb{R}_{>0} = \{x \mid x > 0\}$, then $A \to \mathbb{R} : x \mapsto \frac{1}{x}$ is not a restriction of any function continuous on \mathbb{R} , but any $a \in A$ has a neighborhood restriction to which extends to a C^{∞} -function on \mathbb{R} .

Let *X* be a differential space and $A \subset X$. Restrictions to *A* of functions differentiable on *X* do not necessarily constitute a differential structure on *A*. For example, if $X = \mathbb{R}$ and $A = \mathbb{R}_{>0} = \{x \mid x > 0\}$, then $A \to \mathbb{R} : x \mapsto \frac{1}{x}$ is not a restriction of any function continuous on \mathbb{R} , but any $a \in A$ has a neighborhood restriction to which extends to a C^{∞} -function on \mathbb{R} . Restrictions to *A* of functions differentiable on *X*

generate a differential structure.

Let *X* be a differential space and $A \subset X$. Restrictions to *A* of functions differentiable on *X* do not necessarily constitute a differential structure on *A*. For example, if $X = \mathbb{R}$ and $A = \mathbb{R}_{>0} = \{x \mid x > 0\}$, then $A \to \mathbb{R} : x \mapsto \frac{1}{x}$ is not a restriction of any function continuous on \mathbb{R} , but any $a \in A$ has a neighborhood restriction to which extends to a C^{∞} -function on \mathbb{R} . Restrictions to *A* of functions differentiable on *X* generate a differential structure.

This structure is said to be *induced* on A by the structure of X

Let X be a differential space and $A \subset X$. Restrictions to A of functions differentiable on X do not necessarily constitute a differential structure on A. For example, if $X = \mathbb{R}$ and $A = \mathbb{R}_{>0} = \{x \mid x > 0\}$, then $A \to \mathbb{R} : x \mapsto \frac{1}{x}$ is not a restriction of any function continuous on \mathbb{R} , but any $a \in A$ has a neighborhood restriction to which extends to a C^{∞} -function on \mathbb{R} . Restrictions to A of functions differentiable on X generate a differential structure. This structure is said to be *induced* on A by the structure of X,

and A with this structure is called a *(differential)* subspace of X.

Let X be a differential space and $A \subset X$. Restrictions to A of functions differentiable on X do not necessarily constitute a differential structure on A. For example, if $X = \mathbb{R}$ and $A = \mathbb{R}_{>0} = \{x \mid x > 0\}$, then $A \to \mathbb{R} : x \mapsto \frac{1}{x}$ is not a restriction of any function continuous on \mathbb{R} , but any $a \in A$ has a neighborhood restriction to which extends to a C^{∞} -function on \mathbb{R} . Restrictions to A of functions differentiable on X generate a differential structure.

This structure is said to be *induced* on A by the structure of X,

and A with this structure is called a *(differential)* subspace of X.

Whitney Problem (1934):

Describe the differential structure induced on a closed $X \subset \mathbb{R}^n$.

Let *X* be a differential space and $A \subset X$. Restrictions to *A* of functions differentiable on *X* do not necessarily constitute a differential structure on *A*. For example, if $X = \mathbb{R}$ and $A = \mathbb{R}_{>0} = \{x \mid x > 0\}$, then $A \to \mathbb{R} : x \mapsto \frac{1}{x}$ is not a restriction of any function continuous on \mathbb{R} , but any $a \in A$ has a neighborhood restriction to which extends to a C^{∞} -function on \mathbb{R} . Restrictions to *A* of functions differentiable on *X*

generate a differential structure.

This structure is said to be *induced* on A by the structure of X,

and A with this structure is called a *(differential)* subspace of X.

Whitney Problem (1934):

Describe the differential structure induced on a closed $X \subset \mathbb{R}^n$. Solved by Whitney for n = 1, in general, by C.Fefferman (2006).

Let X and Y be differential spaces (of class C^r).

Let X and Y be differential spaces (of class C^r). A map $f: X \to Y$ is called a *differential embedding* if it defines a diffeomorphism $X \to f(X)$.

Let X and Y be differential spaces (of class C^r). A map $f: X \to Y$ is called a *differential embedding* if it defines a diffeomorphism $X \to f(X)$. (Here f(X) is considered as a differential subspace of Y).

Let X and Y be differential spaces (of class C^r). A map $f: X \to Y$ is called a *differential embedding* if it defines a diffeomorphism $X \to f(X)$. (Here f(X) is considered as a differential subspace of Y). For a differential space X, functions f_1, \ldots, f_n define a differential embedding $f: X \to \mathbb{R}^n : x \mapsto (f_1(x), \ldots, f_n(x))$

Let X and Y be differential spaces (of class C^r). A map $f: X \to Y$ is called a *differential embedding* if it defines a diffeomorphism $X \to f(X)$. (Here f(X) is considered as a differential subspace of Y). For a differential space X, functions f_1, \ldots, f_n define a differential embedding $f: X \to \mathbb{R}^n : x \mapsto (f_1(x), \ldots, f_n(x))$ iff f_1, \ldots, f_n generate $\mathcal{C}^r(X)$ and f is injective.

Consider the set \mathcal{C} of all differentiable functions $\mathbb{R} \to \mathbb{R}$

with the first derivative vanishing at 0.

Consider the set \mathcal{C} of all differentiable functions $\mathbb{R} \to \mathbb{R}$

with the first derivative vanishing at 0.

This is a differential structure.

Consider the set \mathcal{C} of all differentiable functions $\mathbb{R} \to \mathbb{R}$

with the first derivative vanishing at 0.

This is a differential structure. How does the space $(\mathbb{R}, \mathcal{C})$ look like?

Is it embeddable to \mathbb{R}^2 ?

Consider the set \mathcal{C} of all differentiable functions $\mathbb{R} \to \mathbb{R}$ with the first derivative vanishing at 0.

How does the space $(\mathbb{R}, \mathcal{C})$ look like?

This is a differential structure.

Is it embeddable to \mathbb{R}^2 ?

We need functions $u, v : \mathbb{R} \to \mathbb{R}$ with u'(0) = v'(0) = 0such that any differential function $f : \mathbb{R} \to \mathbb{R}$ with f'(0) = 0 was a composition $F \circ (u \times v)$ for some differentiable $F : \mathbb{R}^2 \to \mathbb{R}$.

Consider the set \mathcal{C} of all differentiable functions $\mathbb{R} \to \mathbb{R}$ with the first derivative vanishing at 0.

This is a differential structure. How does the space $(\mathbb{R}, \mathcal{C})$ look like?

Is it embeddable to \mathbb{R}^2 ?

We need functions $u, v : \mathbb{R} \to \mathbb{R}$ with u'(0) = v'(0) = 0such that any differential function $f : \mathbb{R} \to \mathbb{R}$ with f'(0) = 0 was a composition $F \circ (u \times v)$ for some differentiable $F : \mathbb{R}^2 \to \mathbb{R}$.

Take $u(x) = x^2$, $v(x) = x^3$.

Consider the set \mathcal{C} of all differentiable functions $\mathbb{R} \to \mathbb{R}$ with the first derivative vanishing at 0.

How does the space $(\mathbb{R}, \mathcal{C})$ look like?

Is it embeddable to \mathbb{R}^2 ?

We need functions $u, v : \mathbb{R} \to \mathbb{R}$ with u'(0) = v'(0) = 0such that any differential function $f : \mathbb{R} \to \mathbb{R}$ with f'(0) = 0 was a composition $F \circ (u \times v)$ for some differentiable $F : \mathbb{R}^2 \to \mathbb{R}$.

Take
$$u(x) = x^2$$
 , $v(x) = x^3$.

This is a differential structure.

A parametrization of semicubical parabola:

Consider the set \mathcal{C} of all differentiable functions $\mathbb{R} \to \mathbb{R}$ with the first derivative vanishing at 0.

This is a differential structure. How does the space $(\mathbb{R}, \mathcal{C})$ look like?

Is it embeddable to \mathbb{R}^2 ?

We need functions $u, v : \mathbb{R} \to \mathbb{R}$ with u'(0) = v'(0) = 0such that any differential function $f : \mathbb{R} \to \mathbb{R}$ with f'(0) = 0 was a composition $F \circ (u \times v)$ for some differentiable $F : \mathbb{R}^2 \to \mathbb{R}$.

Take
$$u(x) = x^2$$
 , $v(x) = x^3$.

A parametrization of semicubical parabola:

Multiplication. Let X and Y be C^r -spaces.

Multiplication. Let *X* and *Y* be C^r -spaces. The canonical way to define C^r -structure in $X \times Y$

Multiplication. Let X and Y be C^r -spaces. The canonical way to define C^r -structure in $X \times Y$ is to generate it by $\{f \circ pr_X \mid f \in \mathcal{C}^r(X)\} \cup \{g \circ pr_Y \mid g \in \mathcal{C}^r(Y)\}$.

Multiplication. Let X and Y be C^r -spaces. The canonical way to define C^r -structure in $X \times Y$ is to generate it by $\{f \circ pr_X \mid f \in \mathcal{C}^r(X)\} \cup \{g \circ pr_Y \mid g \in \mathcal{C}^r(Y)\}$.

Factorization. Let X be a C^r -space and \sim

be an equivalence relation in X.

Multiplication. Let X and Y be C^r -spaces. The canonical way to define C^r -structure in $X \times Y$ is to generate it by $\{f \circ pr_X \mid f \in C^r(X)\} \cup \{g \circ pr_Y \mid g \in C^r(Y)\}$. **Factorization.** Let X be a C^r -space and \sim

be an equivalence relation in X.

The C^r -structure in X/\sim canonically defined by $\mathcal{C}^r(X)$

Multiplication. Let *X* and *Y* be C^r -spaces. The canonical way to define C^r -structure in $X \times Y$ is to generate it by $\{f \circ pr_X \mid f \in C^r(X)\} \cup \{g \circ pr_Y \mid g \in C^r(Y)\}$. **Factorization.** Let *X* be a C^r -space and ~

be an equivalence relation in X.

The C^r -structure in X/\sim canonically defined by $\mathcal{C}^r(X)$ consists of $f: X/\sim \to \mathbb{R}$ such that $(f \circ pr: X \to \mathbb{R}) \in \mathcal{C}^r(X)$.

1. What differential space is obtained by identification of the end points of $\left[0,1\right]$?

1. What differential space is obtained by identification of the end points of [0,1]? Is it embeddable to \mathbb{R}^2 ?

1. What differential space is obtained by identification of the end points of [0, 1]? Is it embeddable to \mathbb{R}^2 ?

If so, how does the the image look like?

1. What differential space is obtained by identification of the end points of [0,1]? Is it embeddable to \mathbb{R}^2 ?

?

If so, how does the the image look like? Like this:

1. What differential space is obtained by identification of the end points of [0,1]? Is it embeddable to \mathbb{R}^2 ? If so, how does the the image look like? Like this: ? No, like this: !

1. What differential space is obtained by identification of the end points of [0, 1]? Is it embeddable to \mathbb{R}^2 ? If so, how does the the image look like? Like this: ? No, like this: ? Or that: ?

1. What differential space is obtained by identification of the end points of [0, 1]? Is it embeddable to \mathbb{R}^2 ? If so, how does the the image look like? Like this: ? No, like this: ! Or that: ! But not this: !

1. What differential space is obtained by identification of the end points of [0, 1]? Is it embeddable to \mathbb{R}^2 ? If so, how does the the image look like? Like this: ? No, like this: ! Or that: ! But not this: ! 2. What if we take [0, 1.5] and identify each $x \in [0, 0.5]$ with x + 1 ?

1. What differential space is obtained by identification of the end points of [0, 1]? Is it embeddable to \mathbb{R}^2 ? If so, how does the the image look like? Like this: ? No, like this: ! Or that: ! But not this: ! 2. What if we take [0, 1.5] and identify each $x \in [0, 0.5]$ with x + 1 ? Then we get really a space diffeomorphic to .

1. What differential space is obtained by identification of the end points of [0, 1]? Is it embeddable to \mathbb{R}^2 ? If so, how does the the image look like? Like this: ? No, like this: ! Or that: ! But not this: ! 2. What if we take [0, 1.5] and identify each $x \in [0, 0.5]$ with x + 1 ? Then we get really a space diffeomorphic to .

New factorization:

1. What differential space is obtained by identification of the end points of [0, 1]? Is it embeddable to \mathbb{R}^2 ? If so, how does the the image look like? Like this: ? No, like this: ! Or that: ! But not this: ! 2. What if we take [0, 1.5] and identify each $x \in [0, 0.5]$ with x + 1 ? Then we get really a space diffeomorphic to . New factorization:

Identifying end points of [0, 1], identify also tangent vectors!

1. What differential space is obtained by identification of the end points Is it embeddable to \mathbb{R}^2 ? of [0, 1]? If so, how does the the image look like? Like this: ? $\langle \rangle$ > ! Or that: $\langle \rangle$! But not this: (No, like this: 2. What if we take [0, 1.5] and identify each $x \in [0, 0.5]$ with x + 1 ? Then we get really a space diffeomorphic to New factorization: Identifying end points of [0, 1], identify also tangent vectors! That is consider functions $f: [0,1] \to \mathbb{R}$ with f(0) = f(1) and f'(0) = f'(1).

1. What differential space is obtained by identification of the end points Is it embeddable to \mathbb{R}^2 ? of [0, 1]? If so, how does the the image look like? Like this: ? $\langle \rangle$ > ! Or that: $\langle \rangle$! But not this: No, like this: (2. What if we take |0, 1.5| and identify each $x \in [0, 0.5]$ with x + 1 ? Then we get really a space diffeomorphic to New factorization: Identifying end points of [0, 1], identify also tangent vectors! That is consider functions $f:[0,1] \to \mathbb{R}$ with f(0) = f(1) and f'(0) = f'(1). The resulting space:

1. What differential space is obtained by identification of the end points Is it embeddable to \mathbb{R}^2 ? of [0, 1]? If so, how does the the image look like? Like this: ? No, like this: () I Or that: ($\langle \rangle$ But not this: (2. What if we take |0, 1.5| and identify each $x \in [0, 0.5]$ with x + 1 ? Then we get really a space diffeomorphic to New factorization: Identifying end points of [0, 1], identify also tangent vectors! That is consider functions $f: [0,1] \to \mathbb{R}$ with f(0) = f(1) and f'(0) = f'(1). . Smooth, but with jump of curvature. The resulting space:

It is easier to define cotangent vectors.

It is easier to define cotangent vectors. Let X be a differential space and $p \in X$.

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$.

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$.

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p.

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p. As usual.

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p. As usual.

Other traditional definition of tangent vectors (via an equivalence of smooth paths)

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p. As usual.

Other traditional definition of tangent vectors (via an equivalence of smooth paths) gives another result

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p. As usual.

Other traditional definition of tangent vectors (via an equivalence of smooth paths) gives another result and does not give a vector space.

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p. As usual.

 $\dim T_p^*(X)$ may differ from the topological dimension of X at p.

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p. As usual.

 $\dim T_p^*(X)$ may differ from the topological dimension of X at p. For example, $\dim T_0([0,1]/(0 \sim 1)) = 2$.

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p. As usual.

 $\dim T_p^*(X)$ may differ from the topological dimension of X at p. For example, $\dim T_0([0,1]/(0 \sim 1)) = 2$.

Theorem: If $C^r(X)$ is the set of all continuous functions on a topological space X, then $\dim T^*_p(X) = 0$.

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p. As usual.

 $\dim T_p^*(X) \text{ may differ from the topological dimension of } X \text{ at } p.$ For example, $\dim T_0([0,1]/(0\sim 1)) = 2.$

Theorem: If $C^r(X)$ is the set of all continuous functions on a topological space X, then $\dim T_p^*(X) = 0$. The quotient space $D^2/\partial D^2$ of disk D^2 is homeomorphic to sphere S^2 .

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p. As usual.

 $\dim T_p^*(X) \text{ may differ from the topological dimension of } X \text{ at } p.$ For example, $\dim T_0([0,1]/(0\sim 1)) = 2.$

Theorem: If $\mathcal{C}^r(X)$ is the set of all continuous functions on a topological space X, then $\dim T_p^*(X) = 0$.

The quotient space $D^2/\partial D^2$ of disk D^2 is homeomorphic to sphere S^2 . What is $\dim_{\partial D^2/\partial D^2}(D^2/\partial D^2)$?

It is easier to define cotangent vectors.

Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $\mathcal{C}^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

Tangent space $T_p(X)$ is the dual to $T_p^*(X)$. It can be defined as the space of differentiations of differentiable functions on X at p. As usual.

 $\dim T_p^*(X) \text{ may differ from the topological dimension of } X \text{ at } p.$ For example, $\dim T_0([0,1]/(0\sim 1)) = 2.$

Theorem: If $C^r(X)$ is the set of all continuous functions on a topological space X, then $\dim T_p^*(X) = 0$.

The quotient space $D^2/\partial D^2$ of disk D^2 is homeomorphic to sphere S^2 . What is $\dim_{\partial D^2/\partial D^2}(D^2/\partial D^2)$? Infinity!

Each metric space is a differential space.

Each metric space is a differential space. A metric gives rise to many functions:

Each metric space is a differential space.

A metric gives rise to many functions: distances from points.

Each metric space is a differential space.

A metric gives rise to many functions: distances from points.

However on a Riemannian manifold they are not differentiable.

Each metric space is a differential space.

A metric gives rise to many functions: distances from points.

However on a Riemannian manifold they are not differentiable.

In a sufficiently small neighborhood of a point,

distances from other points form local coordinate system.

Each metric space is a differential space.

A metric gives rise to many functions: distances from points. However on a Riemannian manifold they are not differentiable.

In a sufficiently small neighborhood of a point,

distances from other points form local coordinate system.

Let X be a metric space. A function $f : X \to \mathbb{R}$ is *differentiable* at $p \in X$ if for any neighborhood U of p there exist points $q_1, \ldots, q_n \in U$ and real numbers a_1, \ldots, a_n such that

$$\frac{|f(x) - f(p) - \sum a_i(\operatorname{dist}(q_i, x) - \operatorname{dist}(q_i, p))|}{\operatorname{dist}(x, p)} \to 0$$

as $x \to p$.

Each metric space is a differential space.

A metric gives rise to many functions: distances from points. However on a Riemannian manifold they are not differentiable.

In a sufficiently small neighborhood of a point,

distances from other points form local coordinate system.

Let X be a metric space. A function $f : X \to \mathbb{R}$ is *differentiable* at $p \in X$ if for any neighborhood U of p there exist points $q_1, \ldots, q_n \in U$ and real numbers a_1, \ldots, a_n such that

$$\frac{|f(x) - f(p) - \sum a_i(\operatorname{dist}(q_i, x) - \operatorname{dist}(q_i, p))|}{\operatorname{dist}(x, p)} \to 0$$

as $x \to p$.

Is this definition good?

Each metric space is a differential space.

A metric gives rise to many functions: distances from points. However on a Riemannian manifold they are not differentiable.

In a sufficiently small neighborhood of a point,

distances from other points form local coordinate system.

Let X be a metric space. A function $f : X \to \mathbb{R}$ is *differentiable* at $p \in X$ if for any neighborhood U of p there exist points $q_1, \ldots, q_n \in U$ and real numbers a_1, \ldots, a_n such that

$$\frac{|f(x) - f(p) - \sum a_i(\operatorname{dist}(q_i, x) - \operatorname{dist}(q_i, p))|}{\operatorname{dist}(x, p)} \to 0$$

as $x \to p$.

Is this definition good?

At least, it recovers the smooth structure of a Riemannian manifold.

Political correctness

Differential Spaces

Finite Topological

Spaces

- Hesitation of finite spaces
- Fundamental group
- Space of faces
- Homotopy
- Digital plane and Jordan Theorem
- Arbitrary finite space
- Baricentric
- subdivision
- Conclusion
- Table of Contents

Finite Topological Spaces

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Who is guilty?

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Who is guilty? Interest towards Analysis?

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Who is guilty? Interest towards Analysis? Hausdorff axiom?

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Who is guilty?

Interest towards Analysis? Hausdorff axiom? Topology textbooks?

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Who is guilty? Interest towards Analysis? Hausdorff axiom? Topology textbooks?

An average mathematician is well aware at best

about two kinds of finite topological spaces:

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Who is guilty?

Interest towards Analysis? Hausdorff axiom? Topology textbooks?

An average mathematician is well aware at best

about two kinds of finite topological spaces:

discrete and indiscrete.

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Who is guilty? Interest towards Analysis? Hausdorff axiom? Topology textbooks?

An average mathematician is well aware at best about two kinds of finite topological spaces: discrete and indiscrete.

Let us take a look at the rest of them.

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Who is guilty? Interest towards Analysis? Hausdorff axiom? Topology textbooks?

An average mathematician is well aware at best about two kinds of finite topological spaces: discrete and indiscrete.

Let us take a look at the rest of them. They are not that bad!

Topology seams to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Who is guilty? Interest towards Analysis? Hausdorff axiom? Topology textbooks?

An average mathematician is well aware at best about two kinds of finite topological spaces: discrete and indiscrete.

Let us take a look at the rest of them.

They are not that bad!

At early days of topology, they were the main objects of the

Combinatorial Topology

Fundamental group

What is the minimal number of points in a topological space with nontrivial fundamental group?

Fundamental group

What is the minimal number of points in a topological space with nontrivial fundamental group?

What is the group?

Fundamental group

What is the minimal number of points in a topological space with nontrivial fundamental group?

What is the group?

What is the next group?

Let P be a compact polyhedron.

Let P be a compact polyhedron

represented as the union of closed convex polyhedra

any two of which meet in a common face.

Let P be a compact polyhedron

represented as the union of closed convex polyhedra

any two of which meet in a common face.

P is partitioned to open faces of these convex polyhedrons.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P.

Especially if the partition was a triangulation.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P. Each point of Q represents a face of P.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P. Each point of Q represents a face of P.

Points representing vertices are closed.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P. Each point of Q represents a face of P. Doints representing vertices are closed. The closure of a point $x \in Q$ correspondent to a face F of Pconsists of points correspondent to faces of F.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P. Each point of Q represents a face of P. Points representing vertices are closed. The closure of a point $x \in Q$ correspondent to a face F of P consists of points correspondent to faces of F. Each point in a finite space has minimal neighborhood.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P. Each point of Q represents a face of P. Points representing vertices are closed. The closure of a point $x \in Q$ correspondent to a face F of P consists of points correspondent to faces of F. Each point in a finite space has minimal neighborhood, the intersection of all of its neighborhoods.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P. Each point of Q represents a face of P. Points representing vertices are closed. The closure of a point $x \in Q$ correspondent to a face F of P consists of points correspondent to faces of F. Each point in a finite space has minimal neighborhood. In Q the minimal neighborhood of a point corresponds to the star of corresponding face.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P. Each point of Q represents a face of P. Points representing vertices are closed. The closure of a point $x \in Q$ correspondent to a face F of P consists of points correspondent to faces of F. Each point in a finite space has minimal neighborhood. In Q the minimal neighborhood of a point corresponds to the star of corresponding face. The star $St(\sigma)$ of a face σ is the union of all faces Σ such that $\partial \Sigma \supset \sigma$.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P. Each point of Q represents a face of P. Points representing vertices are closed. The closure of a point $x \in Q$ correspondent to a face F of P consists of points correspondent to faces of F. Each point in a finite space has minimal neighborhood. In Q the minimal neighborhood of a point corresponds to the star of the corresponding face. Faces in P are partially ordered by adjacency: $\Sigma > \sigma$ iff $\operatorname{Cl}(\Sigma) \supset \sigma$.

Let P be a compact polyhedron represented as the union of closed convex polyhedra any two of which meet in a common face. P is partitioned to open faces of these convex polyhedrons. The quotient space Q is a finite topological space. Q knows everything on P. Each point of Q represents a face of P. Points representing vertices are closed. The closure of a point $x \in Q$ correspondent to a face F of P consists of points correspondent to faces of F. Each point in a finite space has minimal neighborhood. In Q the minimal neighborhood of a point corresponds to the star of the corresponding face. Faces in P are partially ordered by adjacency: $\Sigma > \sigma$ iff $\operatorname{Cl}(\Sigma) \supset \sigma$. This partial order defines and is defined by the topology of Q.

Let P be a triangulated polyhedron

Let P be a triangulated polyhedron,

Q the space of its simplices

Let P be a triangulated polyhedron,

Q the space of its simplices (the quotient space of P)

Let P be a triangulated polyhedron,

Q the space of its simplices (the quotient space of P),

 $pr: P \rightarrow Q$ the natural projection.

Let P be a triangulated polyhedron,

Q the space of its simplices (the quotient space of P),

 $pr: P \rightarrow Q$ the natural projection.

For topological spaces X and Y denote by $\pi(X,Y)$

the set of homotopy classes of maps $X \to Y$.

Let P be a triangulated polyhedron,

Q the space of its simplices (the quotient space of P),

 $pr: P \rightarrow Q$ the natural projection.

For topological spaces X and Y denote by $\pi(X, Y)$

the set of homotopy classes of maps $X \to Y$.

Theorem. For any topological space X, composition with pr defines a bijection $\pi(X, P) \to \pi(X, Q)$.

Let P be a triangulated polyhedron,

Q the space of its simplices (the quotient space of P),

 $pr: P \rightarrow Q$ the natural projection.

For topological spaces X and Y denote by $\pi(X,Y)$

the set of homotopy classes of maps $X \to Y$.

Theorem. For any topological space X, composition with pr defines a bijection $\pi(X, P) \to \pi(X, Q)$.

Corollary. All homotopy and singular homology groups of P and Q are isomorphic.

Let P be a triangulated polyhedron,

Q the space of its simplices (the quotient space of P),

 $pr: P \rightarrow Q$ the natural projection.

For topological spaces X and Y denote by $\pi(X, Y)$

the set of homotopy classes of maps $X \to Y$.

Theorem. For any topological space X, composition with pr defines a bijection $\pi(X, P) \to \pi(X, Q)$.

Corollary. All homotopy and singular homology groups of P and Q are isomorphic.

Corollary. Any compact polyhedron is weak homotopy equivalent to a finite topological space.

Digital plane and Jordan Theorem

Digital plane and Jordan Theorem

Digital line \mathcal{D} is the quotient space of \mathbb{R} by partition to points of \mathbb{Z} and open intervals (n, n + 1).

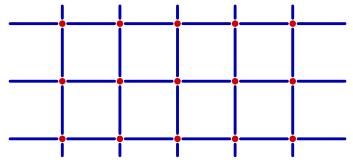
Digital plane and Jordan Theorem

Digital line \mathcal{D} is the quotient space of \mathbb{R} by partition to points of \mathbb{Z} and open intervals (n, n + 1).

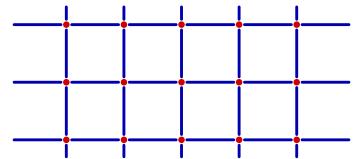
Digital line \mathcal{D} is the quotient space of \mathbb{R} by partition to points of \mathbb{Z} and open intervals (n, n + 1).

Digital line \mathcal{D} is the quotient space of \mathbb{R} by partition to points of \mathbb{Z} and open intervals (n, n + 1). **Digital plane** is \mathcal{D}^2 . It is the quotient space of \mathbb{R}^2 by the partition formed by integer points, open unit intervals connecting them, and open unit squares.

Digital line \mathcal{D} is the quotient space of \mathbb{R} by partition to points of \mathbb{Z} and open intervals (n, n + 1). **Digital plane** is \mathcal{D}^2 . It is the quotient space of \mathbb{R}^2 by the partition formed by integer points, open unit intervals connecting them, and open unit squares.

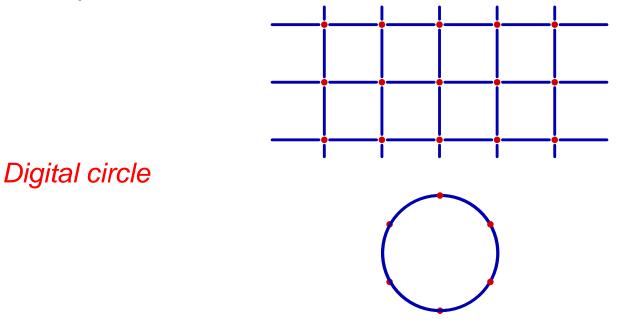


Digital line \mathcal{D} is the quotient space of \mathbb{R} by partition to points of \mathbb{Z} and open intervals (n, n + 1). *Digital plane* is \mathcal{D}^2 . It is the quotient space of \mathbb{R}^2 by the partition formed by integer points, open unit intervals connecting them, and open unit squares.

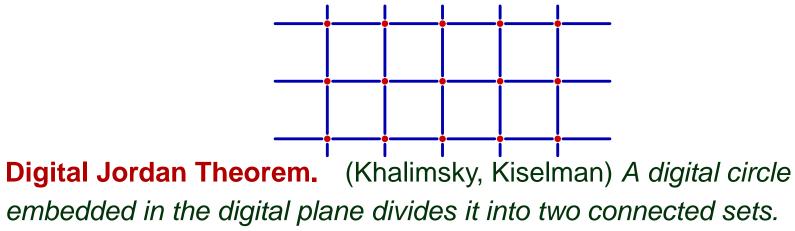


Digital circle of length d is the quotient space of the circle $S^1 \subset \mathbb{C}$ by the partition formed by complex roots of unity of degree d and open arcs connecting the roots next to each other.

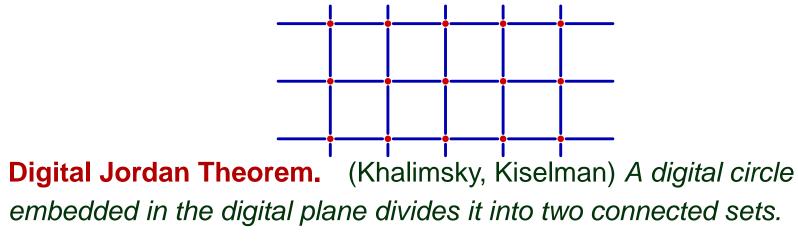
Digital line \mathcal{D} is the quotient space of \mathbb{R} by partition to points of \mathbb{Z} and open intervals (n, n + 1). *Digital plane* is \mathcal{D}^2 . It is the quotient space of \mathbb{R}^2 by the partition formed by integer points, open unit intervals connecting them, and open unit squares.



Digital line \mathcal{D} is the quotient space of \mathbb{R} by partition to points of \mathbb{Z} and open intervals (n, n + 1). *Digital plane* is \mathcal{D}^2 . It is the quotient space of \mathbb{R}^2 by the partition formed by integer points, open unit intervals connecting them, and open unit squares.



Digital line \mathcal{D} is the quotient space of \mathbb{R} by partition to points of \mathbb{Z} and open intervals (n, n + 1). **Digital plane** is \mathcal{D}^2 . It is the quotient space of \mathbb{R}^2 by the partition formed by integer points, open unit intervals connecting them, and open unit squares.



Here spaces are not finite, but *locally finite*.

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods.

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods. The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 :

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods. The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 : for any pair of points x, yat least one of them has a neighborhood not containing the other one.

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods. The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 . In any T_0 -space the relation $x \in \operatorname{Cl} y$ is a partial order.

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods. The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 . In any T_0 -space the relation $x \in \operatorname{Cl} y$ is a partial order.

Remark. Without T_0 axiom this is only a preorder, that is transitive and reflexive, but not antisymmetric.

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods. The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 . In any T_0 -space the relation $x \in Cl y$ is a partial order.

Remark. Without T_0 axiom this is only a preorder, that is transitive and reflexive, but not antisymmetric

(if x and y are T_0 -equivalent, then both $x \in \operatorname{Cl} y$ and $y \in \operatorname{Cl} x$).

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods. The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 . In any T_0 -space the relation $x \in \operatorname{Cl} y$ is a partial order.

Any partial order defines a *poset topology* generated by sets $\{x \mid a \prec x\}$.

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods. The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 . In any T_0 -space the relation $x \in \operatorname{Cl} y$ is a partial order.

Any partial order defines a *poset topology* generated by sets $\{x \mid a \prec x\}$.

A topology is a poset topology iff the Kolmogorov axiom holds true and each point has the smallest neighborhood.

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods. The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 . In any T_0 -space the relation $x \in \operatorname{Cl} y$ is a partial order.

Any partial order defines a *poset topology* generated by sets $\{x \mid a \prec x\}$.

A topology is a poset topology iff the Kolmogorov axiom holds true and each point has the smallest neighborhood.

In particular, topology in a finite space is a poset topology

iff this is a T_0 -space.

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods. The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 . In any T_0 -space the relation $x \in \operatorname{Cl} y$ is a partial order.

Any partial order defines a *poset topology* generated by sets $\{x \mid a \prec x\}$.

A topology is a poset topology iff the Kolmogorov axiom holds true and each point has the smallest neighborhood.

In particular, topology in a finite space is a poset topology

iff this is a T_0 -space.

An arbitrary finite topological space

is composed of clusters of T_0 -equivalent points.

In any topological space there is T_0 -equivalence relation: $x \sim y$ if x and y have the same neighborhoods. The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 . In any T_0 -space the relation $x \in \operatorname{Cl} y$ is a partial order.

Any partial order defines a *poset topology* generated by sets $\{x \mid a \prec x\}$.

A topology is a poset topology iff the Kolmogorov axiom holds true and each point has the smallest neighborhood.

In particular, topology in a finite space is a poset topology

iff this is a T_0 -space.

An arbitrary finite topological space

is composed of clusters of T_0 -equivalent points.

The clusters are partially ordered and the order determines the topology.

How far is a poset topology from the face space of a polyhedron?

How far is a poset topology from the face space of a polyhedron? Not really far, just one step construction.

How far is a poset topology from the face space of a polyhedron? Not really far, just one step construction. Let (X, \prec) be a poset.

How far is a poset topology from the face space of a polyhedron? Not really far, just one step construction. Let (X, \prec) be a poset. Let $X' = \{a_1 \prec a_2 \prec \cdots \prec a_n \mid a_i \in X\}$.

How far is a poset topology from the face space of a polyhedron? Not really far, just one step construction. Let (X, \prec) be a poset. Let $X' = \{a_1 \prec a_2 \prec \cdots \prec a_n \mid a_i \in X\}$, the set of all non-empty finite subsets of X in each of which \prec defines a linear order.

How far is a poset topology from the face space of a polyhedron? Not really far, just one step construction. Let (X, \prec) be a poset. Let $X' = \{a_1 \prec a_2 \prec \cdots \prec a_n \mid a_i \in X\}$, the set of all non-empty finite subsets of X in each of which \prec defines a linear order. X' is partially ordered by inclusion.

How far is a poset topology from the face space of a polyhedron? Not really far, just one step construction. Let (X, \prec) be a poset. Let $X' = \{a_1 \prec a_2 \prec \cdots \prec a_n \mid a_i \in X\}$, the set of all non-empty finite subsets of X in each of which \prec defines a linear order. X' is partially ordered by inclusion. Poset (X', \subset) is called the *baricentric subdivision of* (X, \prec) .

How far is a poset topology from the face space of a polyhedron? Not really far, just one step construction. Let (X, \prec) be a poset. Let $X' = \{a_1 \prec a_2 \prec \cdots \prec a_n \mid a_i \in X\}$, the set of all non-empty finite subsets of X in each of which \prec defines a linear order. X' is partially ordered by inclusion. Poset (X', \subset) is called the *baricentric subdivision of* (X, \prec) . The baricentric subdivision of any finite poset is the space of simplices of a compact triangulated polyhedron.

How far is a poset topology from the face space of a polyhedron? Not really far, just one step construction. Let (X, \prec) be a poset. Let $X' = \{a_1 \prec a_2 \prec \cdots \prec a_n \mid a_i \in X\}$, the set of all non-empty finite subsets of X in each of which \prec defines a linear order. X' is partially ordered by inclusion. Poset (X', \subset) is called the *baricentric subdivision of* (X, \prec) . The baricentric subdivision of any finite poset is the space of simplices of a compact triangulated polyhedron. This construction is used in combinatorics

to define homology groups of a poset.

How far is a poset topology from the face space of a polyhedron? Not really far, just one step construction. Let (X, \prec) be a poset. Let $X' = \{a_1 \prec a_2 \prec \cdots \prec a_n \mid a_i \in X\}$, the set of all non-empty finite subsets of X in each of which \prec defines a linear order. X' is partially ordered by inclusion. Poset (X', \subset) is called the *baricentric subdivision of* (X, \prec) . The baricentric subdivision of any finite poset is the space of simplices of a compact triangulated polyhedron. This construction is used in combinatorics to define homology groups of a poset.

Theorem. Any finite topological space

is weak homotopy equivalent to a compact polyhedron.

What to do with the matters of taste?

What to do with the matters of taste?

Keep balance: beware of stupid empty theories

What to do with the matters of taste?

Keep balance: beware of stupid empty theories, and prejudices.

What to do with the matters of taste?

Keep balance: beware of stupid empty theories, and prejudices.

What axioms are good for the background objects?

What to do with the matters of taste?

Keep balance: beware of stupid empty theories, and prejudices.

What axioms are good for the background objects?

Valuable qualities:

What to do with the matters of taste?

Keep balance: beware of stupid empty theories, and prejudices.

What axioms are good for the background objects?

Valuable qualities:

motivation and non-triviality

What to do with the matters of taste?

Keep balance: beware of stupid empty theories, and prejudices.

What axioms are good for the background objects?

Valuable qualities: motivation and non-triviality, simplicity

What to do with the matters of taste?

Keep balance: beware of stupid empty theories, and prejudices.

What axioms are good for the background objects?

Valuable qualities: motivation and non-triviality, simplicity, hierarchic notions

What to do with the matters of taste?

Keep balance: beware of stupid empty theories, and prejudices.

What axioms are good for the background objects?

Valuable qualities: motivation and non-triviality, simplicity, hierarchic notions, use of the right lobe

What to do with the matters of taste?

Keep balance: beware of stupid empty theories, and prejudices.

What axioms are good for the background objects?

Valuable qualities: motivation and non-triviality, simplicity, hierarchic notions, use of the right lobe, common mathematical legacy.

Table of Contents

Differential Spaces

Differentiable Manifolds What is wrong Political correctness in Mathematics **Publications Differential Structures Differential Spaces** Differentiable maps Generating, refining, relaxing Subspaces Embeddings Example Constructing new differential spaces Examples of quotient spaces Tangent vectors and dimensions

Metric spaces

Finite Topological Spaces

Hesitation of finite spaces Fundamental group Space of faces Homotopy Digital plane and Jordan Theorem Arbitrary finite space Baricentric subdivision Conclusion Table of Contents