# MOMENT MAP GEOMETRY FOR THREE-FORMS 

Andrew Swann

IMF, University of Aarhus
IMADA / CP ${ }^{3}$-Origins, University of Southern Denmark
swann@imf.au.dk
May 2011 / Lund

# Moment map geometry for three-forms 

Andrew Swann

IMF, University of Aarhus
IMADA / CP ${ }^{3}$-Origins, University of Southern Denmark
swann@imf.au.dk
May 2011 / Lund

Joint work with Thomas Bruun Madsen
arXiv:1012.2048,1012.0402

## Outline

(1) Background

## Symplectic Geometry Strong Geometry <br> Covariant Moment Maps

## Outline

(1) Background

Symplectic Geometry
Strong Geometry
Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields Lie kernels
Existence
(2,3)-trivial Lie algebras

## Outline

(1) Background

Symplectic Geometry
Strong Geometry
Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields
Lie kernels
Existence
(2,3)-trivial Lie algebras
(3) $G_{2}$ HOLONOMY

Reduction
Four-dimensional geometry

## Outline

## (1) Background

## Symplectic Geometry

Strong Geometry
Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields
Lie kernels
Existence
(2,3)-trivial Lie algebras
(3) $G_{2}$ HOLONOMY

Reduction
Four-dimensional geometry

## Symplectic geometry and moment maps

$(M, \omega)$ is symplectic if $\omega \in \Omega^{2}(M)$ is closed $(d \omega=0)$ and non-degenerate.

## Symplectic geometry and moment maps

$(M, \omega)$ is symplectic if $\omega \in \Omega^{2}(M)$ is closed $(d \omega=0)$ and non-degenerate.

## BASIC CALCULATION

If $X$ preserves $\omega$,

## Symplectic geometry and moment maps

$(M, \omega)$ is symplectic if $\omega \in \Omega^{2}(M)$ is closed $(d \omega=0)$ and non-degenerate.

## BASIC CALCULATION

If $X$ preserves $\omega$, then

$$
\left.\left.\left.0=L_{X} \omega=X\right\lrcorner d \omega+d(X\lrcorner \omega\right)=d(X\lrcorner \omega\right)
$$

## Symplectic geometry and moment maps

$(M, \omega)$ is symplectic if $\omega \in \Omega^{2}(M)$ is closed $(d \omega=0)$ and non-degenerate.

## Basic calculation

If $X$ preserves $\omega$, then

$$
\left.\left.\left.0=L_{X} \omega=X\right\lrcorner d \omega+d(X\lrcorner \omega\right)=d(X\lrcorner \omega\right)
$$

So the one-form $X\lrcorner \omega$ is $d \mu_{X,}$

## Symplectic geometry and moment maps

$(M, \omega)$ is symplectic if $\omega \in \Omega^{2}(M)$ is closed $(d \omega=0)$ and non-degenerate.

## BASIC CALCULATION

If $X$ preserves $\omega$, then

$$
\left.\left.\left.0=L_{X} \omega=X\right\lrcorner d \omega+d(X\lrcorner \omega\right)=d(X\lrcorner \omega\right)
$$

So the one-form $X\lrcorner \omega$ is $d \mu_{X}$, for some local function $\mu_{X}$.

## Symplectic geometry and moment maps

$(M, \omega)$ is symplectic if $\omega \in \Omega^{2}(M)$ is closed $(d \omega=0)$ and non-degenerate.

## BASIC CALCULATION

If $X$ preserves $\omega$, then

$$
\left.\left.\left.0=L_{X} \omega=X\right\lrcorner d \omega+d(X\lrcorner \omega\right)=d(X\lrcorner \omega\right)
$$

So the one-form $X\lrcorner \omega$ is $d \mu_{X}$, for some local function $\mu_{X}$.

## DEFINITION

A moment map for an action of $G$ on $M$ that preserves $\omega$ is an equivariant map

$$
\mu: M \rightarrow \mathfrak{g}^{*}
$$

## Symplectic geometry and moment maps

$(M, \omega)$ is symplectic if $\omega \in \Omega^{2}(M)$ is closed $(d \omega=0)$ and non-degenerate.

## BASIC CALCULATION

If $X$ preserves $\omega$, then

$$
\left.\left.\left.0=L_{X} \omega=X\right\lrcorner d \omega+d(X\lrcorner \omega\right)=d(X\lrcorner \omega\right)
$$

So the one-form $X\lrcorner \omega$ is $d \mu_{X}$, for some local function $\mu_{X}$.

## DEFINITION

A moment map for an action of $G$ on $M$ that preserves $\omega$ is an equivariant map

$$
\mu: M \rightarrow \mathfrak{g}^{*}
$$

such that $d\langle\mu, \mathbf{X}\rangle=X\lrcorner \omega$, for each $X \in \mathfrak{g}$.

## Symplectic examples

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$ with

$$
\omega=\sum_{j=1}^{n} d x^{j} \wedge d y^{j}
$$

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$ with

$$
\omega=\sum_{j=1}^{n} d x^{j} \wedge d y^{j}
$$

Circle action $\mathbf{z} \mapsto e^{i \theta} \mathbf{z}$

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$ with

$$
\omega=\sum_{j=1}^{n} d x^{j} \wedge d y^{j}
$$

Circle action $\mathbf{z} \mapsto e^{i \theta} \mathbf{z}$ has $\mu(\mathbf{x}, \mathbf{y})=\frac{1}{2}\left(\|\mathbf{x}\|^{2}+\|\mathbf{y}\|^{2}\right)$.

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$ with

$$
\omega=\sum_{j=1}^{n} d x^{j} \wedge d y^{j}
$$

Circle action $\mathbf{z} \mapsto e^{i \theta} \mathbf{z}$ has $\mu(\mathbf{x}, \mathbf{y})=\frac{1}{2}\left(\|\mathbf{x}\|^{2}+\|\mathbf{y}\|^{2}\right)$.

## Cotangent bundle

$M=T^{*} N$

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$ with

$$
\omega=\sum_{j=1}^{n} d x^{j} \wedge d y^{j}
$$

Circle action $\mathbf{z} \mapsto e^{i \theta} \mathbf{z}$ has $\mu(\mathbf{x}, \mathbf{y})=\frac{1}{2}\left(\|\mathbf{x}\|^{2}+\|\mathbf{y}\|^{2}\right)$.

## Cotangent bundle

$M=T^{*} N$ is symplectic with

$$
\begin{aligned}
\omega & =d q^{1} \wedge d p_{1}+\cdots+d q^{n} \wedge d p_{n} \\
& =d \theta, \quad \theta(W)_{\alpha}=\alpha\left(\pi_{*} W\right)
\end{aligned}
$$

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$ with

$$
\omega=\sum_{j=1}^{n} d x^{j} \wedge d y^{j}
$$

Circle action $\mathbf{z} \mapsto e^{i \theta} \mathbf{z}$ has $\mu(\mathbf{x}, \mathbf{y})=\frac{1}{2}\left(\|\mathbf{x}\|^{2}+\|\mathbf{y}\|^{2}\right)$.

## Cotangent bundle

$M=T^{*} N$ is symplectic with

$$
\begin{aligned}
\omega & =d q^{1} \wedge d p_{1}+\cdots+d q^{n} \wedge d p_{n} \\
& =d \theta, \quad \theta(W)_{\alpha}=\alpha\left(\pi_{*} W\right)
\end{aligned}
$$

Any $G \subset \operatorname{Diff}(N)$ admits a moment map,

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$ with

$$
\omega=\sum_{j=1}^{n} d x^{j} \wedge d y^{j}
$$

Circle action $\mathbf{z} \mapsto e^{i \theta} \mathbf{z}$ has $\mu(\mathbf{x}, \mathbf{y})=\frac{1}{2}\left(\|\mathbf{x}\|^{2}+\|\mathbf{y}\|^{2}\right)$.

## Cotangent bundle

$M=T^{*} N$ is symplectic with

$$
\begin{aligned}
\omega & =d q^{1} \wedge d p_{1}+\cdots+d q^{n} \wedge d p_{n} \\
& =d \theta, \quad \theta(W)_{\alpha}=\alpha\left(\pi_{*} W\right)
\end{aligned}
$$

Any $G \subset \operatorname{Diff}(N)$ admits a moment map, $\mu_{X}=\theta(X)$.

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$ with

$$
\omega=\sum_{j=1}^{n} d x^{j} \wedge d y^{j}
$$

Circle action $\mathbf{z} \mapsto e^{i \theta} \mathbf{z}$ has $\mu(\mathbf{x}, \mathbf{y})=\frac{1}{2}\left(\|\mathbf{x}\|^{2}+\|\mathbf{y}\|^{2}\right)$.

## Cotangent bundle

$M=T^{*} N$ is symplectic with

$$
\begin{aligned}
\omega & =d q^{1} \wedge d p_{1}+\cdots+d q^{n} \wedge d p_{n} \\
& =d \theta, \quad \theta(W)_{\alpha}=\alpha\left(\pi_{*} W\right)
\end{aligned}
$$

Any $G \subset \operatorname{Diff}(N)$ admits a moment map, $\mu_{X}=\theta(X)$.

## Coadjoint orbits

$\mathcal{O}=G \cdot \theta_{0} \subset \mathfrak{g}^{*}$

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$ with

$$
\omega=\sum_{j=1}^{n} d x^{j} \wedge d y^{j}
$$

Circle action $\mathbf{z} \mapsto e^{i \theta} \mathbf{z}$ has $\mu(\mathbf{x}, \mathbf{y})=\frac{1}{2}\left(\|\mathbf{x}\|^{2}+\|\mathbf{y}\|^{2}\right)$.

## Cotangent bundle

$M=T^{*} N$ is symplectic with

$$
\begin{aligned}
\omega & =d q^{1} \wedge d p_{1}+\cdots+d q^{n} \wedge d p_{n} \\
& =d \theta, \quad \theta(W)_{\alpha}=\alpha\left(\pi_{*} W\right)
\end{aligned}
$$

Any $G \subset \operatorname{Diff}(N)$ admits a moment map, $\mu_{X}=\theta(X)$.

## CoAdjoint orbits

$\mathcal{O}=G \cdot \theta_{0} \subset \mathfrak{g}^{*}$ has Kirillov-Kostant-Souriau form

$$
\omega(X, Y)_{\theta}=\theta([X, Y]), \quad \theta \in \mathcal{O}, X, Y \in \mathfrak{g}
$$

## Symplectic examples

## Flat space

$M=\mathbb{R}^{2 n}=\mathbb{C}^{n}$ with

$$
\omega=\sum_{j=1}^{n} d x^{j} \wedge d y^{j}
$$

Circle action $\mathbf{z} \mapsto e^{i \theta} \mathbf{z}$ has $\mu(\mathbf{x}, \mathbf{y})=\frac{1}{2}\left(\|\mathbf{x}\|^{2}+\|\mathbf{y}\|^{2}\right)$.

## Cotangent bundle

$M=T^{*} N$ is symplectic with

$$
\begin{aligned}
\omega & =d q^{1} \wedge d p_{1}+\cdots+d q^{n} \wedge d p_{n} \\
& =d \theta, \quad \theta(W)_{\alpha}=\alpha\left(\pi_{*} W\right)
\end{aligned}
$$

Any $G \subset \operatorname{Diff}(N)$ admits a moment map, $\mu_{X}=\theta(X)$.

## COAdjOINT ORBITS

$\mathcal{O}=G \cdot \theta_{0} \subset \mathfrak{g}^{*}$ has Kirillov-Kostant-Souriau form

$$
\omega(X, Y)_{\theta}=\theta([X, Y]), \quad \theta \in \mathcal{O}, X, Y \in \mathfrak{g}
$$

The moment map $\mu: \mathcal{O} \rightarrow \mathfrak{g}^{*}$ is just inclusion.

## Uses of symplectic moment maps

## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.


## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.
- $T^{*} N / / G=T^{*}(N / G)$.


## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.
- $T^{*} N / / G=T^{*}(N / G)$.
- extensions to Kähler, hyperKähler, etc.


## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.
- $T^{*} N / / G=T^{*}(N / G)$.
- extensions to Kähler, hyperKähler, etc.
- gauge theory moduli spaces.


## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.
- $T^{*} N / / G=T^{*}(N / G)$.
- extensions to Kähler, hyperKähler, etc.
- gauge theory moduli spaces.
(2) Classification Theorems:


## UsES OF SYMPLECTIC MOMENT MAPS

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.
- $T^{*} N / / G=T^{*}(N / G)$.
- extensions to Kähler, hyperKähler, etc.
- gauge theory moduli spaces.
(2) Classification Theorems:
- homogeneous symplectic manifolds, homogeneous Kähler;


## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.
- $T^{*} N / / G=T^{*}(N / G)$.
- extensions to Kähler, hyperKähler, etc.
- gauge theory moduli spaces.
(2) Classification Theorems:
- homogeneous symplectic manifolds, homogeneous Kähler;
- cohomogeneity one hyperKähler, quaternionic Kähler;


## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.
- $T^{*} N / / G=T^{*}(N / G)$.
- extensions to Kähler, hyperKähler, etc.
- gauge theory moduli spaces.
(2) Classification Theorems:
- homogeneous symplectic manifolds, homogeneous Kähler;
- cohomogeneity one hyperKähler, quaternionic Kähler;
- contact manifolds, twistor spaces, 3-Sasaki manifolds with large symmetry.


## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.
- $T^{*} N / / G=T^{*}(N / G)$.
- extensions to Kähler, hyperKähler, etc.
- gauge theory moduli spaces.
(2) Classification Theorems:
- homogeneous symplectic manifolds, homogeneous Kähler;
- cohomogeneity one hyperKähler, quaternionic Kähler;
- contact manifolds, twistor spaces, 3-Sasaki manifolds with large symmetry.
(3) Constructions:


## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.
- $T^{*} N / / G=T^{*}(N / G)$.
- extensions to Kähler, hyperKähler, etc.
- gauge theory moduli spaces.
(2) Classification Theorems:
- homogeneous symplectic manifolds, homogeneous Kähler;
- cohomogeneity one hyperKähler, quaternionic Kähler;
- contact manifolds, twistor spaces, 3-Sasaki manifolds with large symmetry.
(3) Constructions:
- toric varieties: $G=T^{n}, \operatorname{dim} M=2 n, \mu: M \rightarrow \Delta \subset \mathbb{R}^{n}$ a convex polytope;


## Uses of symplectic moment maps

(1) Reduction: $N=\mu^{-1}(0) / G$ is symplectic, $\operatorname{dim} N=\operatorname{dim} M-2 \operatorname{dim} G$ if $G$ acts freely.

- $\mathbb{C P}(n)=\mathbb{R}^{2 n+2} / / S^{1}$.
- $T^{*} N / / G=T^{*}(N / G)$.
- extensions to Kähler, hyperKähler, etc.
- gauge theory moduli spaces.
(2) Classification Theorems:
- homogeneous symplectic manifolds, homogeneous Kähler;
- cohomogeneity one hyperKähler, quaternionic Kähler;
- contact manifolds, twistor spaces, 3-Sasaki manifolds with large symmetry.
(3) Constructions:
- toric varieties: $G=T^{n}, \operatorname{dim} M=2 n, \mu: M \rightarrow \Delta \subset \mathbb{R}^{n}$ a convex polytope;
- cuts, implosions.


## Key properties of symplectic moment maps

## Key properties of symplectic moment maps

$\mu: M \rightarrow \mathfrak{g}^{*}$

## Key properties of symplectic moment maps

$\mu: M \rightarrow \mathfrak{g}^{*}$

- Target space is a vector space independent of $M$.


## Key properties of symplectic moment maps

$\mu: M \rightarrow \mathfrak{g}^{*}$

- Target space is a vector space independent of $M$.
- $\mu$ exists if either


## Key properties of symplectic moment maps

$\mu: M \rightarrow \mathfrak{g}^{*}$

- Target space is a vector space independent of $M$.
- $\mu$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,


## KEy PROPERTIES OF SYMPLECTIC MOMENT MAPS

$\mu: M \rightarrow \mathfrak{g}^{*}$

- Target space is a vector space independent of $M$.
- $\mu$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact, with $b_{1}(M)=0$,


## Key properties of symplectic moment maps

$\mu: M \rightarrow \mathfrak{g}^{*}$

- Target space is a vector space independent of $M$.
- $\mu$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact, with $b_{1}(M)=0$,
(3) $\omega=d \theta$ with $\theta$ invariant under $G$, or


## Key properties of symplectic moment maps

$\mu: M \rightarrow \mathfrak{g}^{*}$

- Target space is a vector space independent of $M$.
- $\mu$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact, with $b_{1}(M)=0$,
(3) $\omega=d \theta$ with $\theta$ invariant under $G$, or
(4) $G$ is semi-simple.


## Outline

(1) BACKGROUND

Symplectic Geometry

## Strong Geometry

Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields
Lie kernels
Existence
(2,3)-trivial Lie algebras
(3) $G_{2}$ Holonomy

Reduction
Four-dimensional geometry

## Strong geometry

## Strong geometry

## DEFINITION

$(M, c)$ forms a strong geometry if $c \in \Omega^{3}(M)$ is closed, $d c=0$.

## Strong geometry

## DEFINITION

$(M, c)$ forms a strong geometry if $c \in \Omega^{3}(M)$ is closed, $d c=0$.
The geometry is 2-plectic (Baez, Hoffnung, and Rogers, 2010) if $c$ is non-degenerate, in the sense that $X\lrcorner c=0$ only for $X=0$.

## Strong geometry

## DEFINITION

$(M, c)$ forms a strong geometry if $c \in \Omega^{3}(M)$ is closed, $d c=0$.
The geometry is 2-plectic (Baez, Hoffnung, and Rogers, 2010) if $c$ is non-degenerate, in the sense that $X\lrcorner c=0$ only for $X=0$.

## ExTENDED PHASE SPACE

$M=\Lambda^{2} T^{*} N$,

## Strong geometry

## Definition

$(M, c)$ forms a strong geometry if $c \in \Omega^{3}(M)$ is closed, $d c=0$.
The geometry is 2-plectic (Baez, Hoffnung, and Rogers, 2010) if $c$ is non-degenerate, in the sense that $X\lrcorner c=0$ only for $X=0$.

## Extended phase space

$$
M=\Lambda^{2} T^{*} N
$$

$$
\begin{aligned}
c & =\sum_{i<j} d q^{i} \wedge d q^{j} \wedge d p_{i j} \\
& =d \beta, \quad \beta_{\alpha}(U, V)=\alpha\left(\pi_{*} U, \pi_{*} V\right)
\end{aligned}
$$

## Strong geometry

## Definition

$(M, c)$ forms a strong geometry if $c \in \Omega^{3}(M)$ is closed, $d c=0$.
The geometry is 2-plectic (Baez, Hoffnung, and Rogers, 2010) if $c$ is non-degenerate, in the sense that $X\lrcorner c=0$ only for $X=0$.

## Extended Phase space

$M=\Lambda^{2} T^{*} N$,

$$
\begin{aligned}
c & =\sum_{i<j} d q^{i} \wedge d q^{j} \wedge d p_{i j} \\
& =d \beta, \quad \beta_{\alpha}(U, V)=\alpha\left(\pi_{*} U, \pi_{*} V\right)
\end{aligned}
$$

is 2-plectic.

## EXAMPLES OF STRONG GEOMETRIES

## Strong geometries with torsion

## EXAMPLES OF STRONG GEOMETRIES

## STRONG GEOMETRIES WITH TORSION

( $M, g, c$ ), $g$ Riemannian defines

## EXAMPLES OF STRONG GEOMETRIES

## STRONG GEOMETRIES WITH TORSION

( $M, g, c$ ), $g$ Riemannian defines

$$
\nabla=\nabla^{\mathrm{LC}}+\frac{1}{2} c,
$$

## Examples of strong geometries

## Strong geometries with torsion

( $M, g, c$ ), $g$ Riemannian defines

$$
\nabla=\nabla^{\mathrm{LC}}+\frac{1}{2} c,
$$

a metric connection $\nabla g=0$

## Examples of strong geometries

## StRONG GEOMETRIES WITH TORSION

( $M, g, c$ ), $g$ Riemannian defines

$$
\nabla=\nabla^{\mathrm{LC}}+\frac{1}{2} c,
$$

a metric connection $\nabla g=0$ with the same geodesics as $\nabla^{\text {LC }}$.

## Examples of strong geometries

## StRONG GEOMETRIES WITH TORSION

( $M, g, c$ ), $g$ Riemannian defines

$$
\nabla=\nabla^{\mathrm{LC}}+\frac{1}{2} c,
$$

a metric connection $\nabla g=0$ with the same geodesics as $\nabla^{\text {LC }}$.

- $M=G / K$ isotropy irreducible, $c(X, Y, Z)=\langle X,[Y, Z]\rangle$.


## EXAMPLES OF STRONG GEOMETRIES

## Strong geometries with torsion

( $M, g, c$ ), $g$ Riemannian defines

$$
\nabla=\nabla^{\mathrm{LC}}+\frac{1}{2} c,
$$

a metric connection $\nabla g=0$ with the same geodesics as $\nabla^{\text {LC }}$.

- $M=G / K$ isotropy irreducible, $c(X, Y, Z)=\langle X,[Y, Z]\rangle$.
- Strong KT geometry: $\left(M, g, I, F_{I}\right)$ Hermitian, $c=-I d F_{I}$. Gauduchon (1984) every compact Hermitian $M^{4}$ is conformally SKT.


## EXAMPLES OF STRONG GEOMETRIES

## Strong geometries with torsion

( $M, g, c$ ), $g$ Riemannian defines

$$
\nabla=\nabla^{\mathrm{LC}}+\frac{1}{2} c,
$$

a metric connection $\nabla g=0$ with the same geodesics as $\nabla^{\text {LC }}$.

- $M=G / K$ isotropy irreducible, $c(X, Y, Z)=\langle X,[Y, Z]\rangle$.
- Strong KT geometry: $\left(M, g, I, F_{I}\right)$ Hermitian, $c=-I d F_{I}$. Gauduchon (1984) every compact Hermitian $M^{4}$ is conformally SKT.

Other examples of strong geometries include:

## EXAMPLES OF STRONG GEOMETRIES

## Strong geometries with torsion

( $M, g, c$ ), $g$ Riemannian defines

$$
\nabla=\nabla^{\mathrm{LC}}+\frac{1}{2} c,
$$

a metric connection $\nabla g=0$ with the same geodesics as $\nabla^{\text {LC }}$.

- $M=G / K$ isotropy irreducible, $c(X, Y, Z)=\langle X,[Y, Z]\rangle$.
- Strong KT geometry: $\left(M, g, I, F_{I}\right)$ Hermitian, $c=-I d F_{I}$. Gauduchon (1984) every compact Hermitian $M^{4}$ is conformally SKT.

Other examples of strong geometries include:

- Holonomy $G_{2}$ manifolds.


## EXAMPLES OF STRONG GEOMETRIES

## Strong geometries with torsion

( $M, g, c$ ), $g$ Riemannian defines

$$
\nabla=\nabla^{\mathrm{LC}}+\frac{1}{2} c,
$$

a metric connection $\nabla g=0$ with the same geodesics as $\nabla^{\text {LC }}$.

- $M=G / K$ isotropy irreducible, $c(X, Y, Z)=\langle X,[Y, Z]\rangle$.
- Strong KT geometry: $\left(M, g, I, F_{I}\right)$ Hermitian, $c=-I d F_{I}$. Gauduchon (1984) every compact Hermitian $M^{4}$ is conformally SKT.

Other examples of strong geometries include:

- Holonomy $G_{2}$ manifolds.
- Hermitian manifolds, $c=d F_{I}$.


## Outline

(1) Background

Symplectic Geometry
Strong Geometry
Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields
Lie kernels
Existence
(2,3)-trivial Lie algebras
(3) $G_{2}$ Holonomy

Reduction
Four-dimensional geometry

## Covariant moment maps

$(M, c)$ strong $(d c=0)$.

## Covariant moment maps

$(M, c)$ strong $(d c=0)$.
BASIC CALCULATION
If $X$ preserves $c$,

## Covariant moment maps

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

If $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right) .
$$

## Covariant moment maps

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

If $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right) .
$$

So the two-form $X\lrcorner c$ is $d \alpha_{X}$

## Covariant moment maps

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

If $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right)
$$

So the two-form $X\lrcorner c$ is $d \alpha_{X}$ for some local one-form $\alpha_{X}$.

## Covariant moment maps

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

If $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right)
$$

So the two-form $X\lrcorner c$ is $d \alpha_{X}$ for some local one-form $\alpha_{X}$.

## DEFINITION

A covariant moment map for an action of $G$ on $M$ that preserves $c$ is

## Covariant moment maps

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

If $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right)
$$

So the two-form $X\lrcorner c$ is $d \alpha_{X}$ for some local one-form $\alpha_{X}$.

## DEFINITION

A covariant moment map for an action of $G$ on $M$ that preserves $c$ is an equivariant map

$$
\alpha: M \rightarrow \Omega^{1}(M, \mathfrak{g})
$$

## Covariant moment maps

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

If $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right)
$$

So the two-form $X\lrcorner c$ is $d \alpha_{X}$ for some local one-form $\alpha_{X}$.

## DEFINITION

A covariant moment map for an action of $G$ on $M$ that preserves $c$ is an equivariant map

$$
\alpha: M \rightarrow \Omega^{1}(M, \mathfrak{g})
$$

such that $d\langle\alpha, X\rangle=X\lrcorner c$, for each $X \in \mathfrak{g}$.

## COVARIANT MOMENT MAPS: DISCUSSION

$\alpha: M \rightarrow \Omega^{1}(M, \mathfrak{g})$ with $\left.d\langle\alpha, X\rangle=X\right\lrcorner c$.

## Covariant moment maps: Discussion

$\alpha: M \rightarrow \Omega^{1}(M, \mathfrak{g})$ with $\left.d\langle\alpha, X\rangle=X\right\lrcorner c$.

- Definition introduced and studied by Cariñena, Crampin, and Ibort (1991) and by Gotay, Isenberg, Marsden, and Montgomery (1998).


## Covariant moment maps: Discussion

$\alpha: M \rightarrow \Omega^{1}(M, \mathfrak{g})$ with $\left.d\langle\alpha, X\rangle=X\right\lrcorner c$.

- Definition introduced and studied by Cariñena, Crampin, and Ibort (1991) and by Gotay, Isenberg, Marsden, and Montgomery (1998).
- Problems include:


## Covariant moment maps: Discussion

$\alpha: M \rightarrow \Omega^{1}(M, \mathfrak{g})$ with $\left.d\langle\alpha, \mathrm{X}\rangle=X\right\lrcorner c$.

- Definition introduced and studied by Cariñena, Crampin, and Ibort (1991) and by Gotay, Isenberg, Marsden, and Montgomery (1998).
- Problems include:
(1) Target space $\Omega^{1}(M, \mathfrak{g})$ depends both on $M$ and $\mathfrak{g}$.


## COVARIANT MOMENT MAPS: DISCUSSION

$\alpha: M \rightarrow \Omega^{1}(M, \mathfrak{g})$ with $\left.d\langle\alpha, X\rangle=X\right\lrcorner c$.

- Definition introduced and studied by Cariñena, Crampin, and Ibort (1991) and by Gotay, Isenberg, Marsden, and Montgomery (1998).
- Problems include:
(1) Target space $\Omega^{1}(M, \mathfrak{g})$ depends both on $M$ and $\mathfrak{g}$.
(2) Existence often requires some restrictive assumption such as $b_{2}(M)=0$.


## Outline

(1) BACKGROUND

Symplectic Geometry
Strong Geometry
Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields
Lie kernels
Existence
(2,3)-trivial Lie algebras
(3) $G_{2}$ HOLONOMY

Reduction
Four-dimensional geometry

## Commuting vector fields

$(M, c)$ strong $(d c=0)$.

## Commuting vector fields

$$
(M, c) \text { strong }(d c=0) .
$$

## BASIC CALCULATION

Suppose $X$ preserves $c$, then

## Commuting vector fields

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

Suppose $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right)
$$

## Commuting vector fields

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

Suppose $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right)
$$

Now suppose $Y$ preserves both $X$ and $c$ :

## Commuting vector fields

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

Suppose $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right)
$$

Now suppose $Y$ preserves both $X$ and $c$ :

$$
[X, Y]=0 \quad \text { and } \quad L_{Y} \mathcal{C}=0
$$

## Commuting vector fields

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

Suppose $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right)
$$

Now suppose $Y$ preserves both $X$ and $c$ :

$$
[X, Y]=0 \quad \text { and } \quad L_{Y} c=0
$$

Then

$$
\left.\left.\left.\left.\left.0=L_{Y}(X\lrcorner c\right)=Y\right\lrcorner d(X\lrcorner c\right)+d(Y\lrcorner X\right\lrcorner c\right)=d c(X, Y, \cdot) .
$$

## Commuting vector fields

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

Suppose $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right)
$$

Now suppose $Y$ preserves both $X$ and $c$ :

$$
[X, Y]=0 \quad \text { and } \quad L_{Y} c=0
$$

Then

$$
\left.\left.\left.\left.\left.0=L_{Y}(X\lrcorner c\right)=Y\right\lrcorner d(X\lrcorner c\right)+d(Y\lrcorner X\right\lrcorner c\right)=d c(X, Y, \cdot) .
$$

So the one-form $c(X, Y, \cdot)$ is $d v_{X, Y}$

## Commuting vector fields

$(M, c)$ strong $(d c=0)$.

## BASIC CALCULATION

Suppose $X$ preserves $c$, then

$$
\left.\left.\left.0=L_{X} c=X\right\lrcorner d c+d(X\lrcorner c\right)=d(X\lrcorner c\right)
$$

Now suppose $Y$ preserves both $X$ and $c$ :

$$
[X, Y]=0 \quad \text { and } \quad L_{Y} c=0
$$

Then

$$
\left.\left.\left.\left.\left.0=L_{Y}(X\lrcorner c\right)=Y\right\lrcorner d(X\lrcorner c\right)+d(Y\lrcorner X\right\lrcorner c\right)=d c(X, Y, \cdot) .
$$

So the one-form $c(X, Y, \cdot)$ is $d v_{X, Y}$ for some local function $v_{X, Y}$.

## Outline

(1) Background

Symplectic Geometry
Strong Geometry
Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields
Lie kernels
Existence
(2,3)-trivial Lie algebras


HOLONOMY
Reduction
Four-dimensional geometry

## LIE KERNELS

## DEFINITION <br> The Lie kernel $\mathcal{P}_{\mathfrak{g}}$ of Lie algebra $\mathfrak{g}$ is

## Lie kernels

## Definition

The Lie kernel $\mathcal{P}_{\mathfrak{g}}$ of Lie algebra $\mathfrak{g}$ is

$$
\mathcal{P}_{\mathfrak{g}}=\operatorname{ker}\left([\cdot, \cdot]: \Lambda^{2} \mathfrak{g} \rightarrow \mathfrak{g}\right)
$$

## Lie kernels

## Definition

The Lie kernel $\mathcal{P}_{\mathfrak{g}}$ of Lie algebra $\mathfrak{g}$ is

$$
\mathcal{P}_{\mathfrak{g}}=\operatorname{ker}\left([\cdot, \cdot]: \Lambda^{2} \mathfrak{g} \rightarrow \mathfrak{g}\right)
$$

A typical element of $p \in \mathcal{P}_{\mathfrak{g}}$ has the form

$$
\mathrm{p}=\mathrm{X}_{1} \wedge \mathrm{Y}_{1}+\cdots+\mathrm{X}_{r} \wedge \mathrm{Y}_{r}
$$

## Lie kernels

## DEFINITION

The Lie kernel $\mathcal{P}_{\mathfrak{g}}$ of Lie algebra $\mathfrak{g}$ is

$$
\mathcal{P}_{\mathfrak{g}}=\operatorname{ker}\left([\cdot, \cdot]: \Lambda^{2} \mathfrak{g} \rightarrow \mathfrak{g}\right)
$$

A typical element of $p \in \mathcal{P}_{\mathfrak{g}}$ has the form

$$
\mathrm{p}=\mathrm{X}_{1} \wedge \mathrm{Y}_{1}+\cdots+\mathrm{X}_{r} \wedge \mathrm{Y}_{r}
$$

with

$$
\sum_{i=1}^{r}\left[\mathrm{X}_{i}, \mathrm{Y}_{i}\right]=0
$$

## LIE KERNELS

## Definition

The Lie kernel $\mathcal{P}_{\mathfrak{g}}$ of Lie algebra $\mathfrak{g}$ is

$$
\mathcal{P}_{\mathfrak{g}}=\operatorname{ker}\left([\cdot, \cdot]: \Lambda^{2} \mathfrak{g} \rightarrow \mathfrak{g}\right)
$$

A typical element of $p \in \mathcal{P}_{\mathfrak{g}}$ has the form

$$
\mathrm{p}=\mathrm{X}_{1} \wedge \mathrm{Y}_{1}+\cdots+\mathrm{X}_{r} \wedge \mathrm{Y}_{r}
$$

with

$$
\sum_{i=1}^{r}\left[\mathrm{X}_{i}, \mathrm{Y}_{i}\right]=0 .
$$

Linearity in the basic calculation shows that

$$
\left.d(p\lrcorner c)=d\left(\sum_{i=1}^{r} c\left(X_{i}, Y_{i}, \cdot\right)\right)=-\left(\sum_{i=1}^{r}\left[X_{i}, Y_{i}\right]\right)\right\lrcorner c=0 .
$$

## Multi-moment maps

## Definition

A multi-moment map for $G$ acting on $M$ preserving $c$ is

## MUlti-moment maps

## DEFINITION

A multi-moment map for $G$ acting on $M$ preserving $c$ is an equivariant map

$$
v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}
$$

## MUlti-moment maps

## DEFINITION

A multi-moment map for $G$ acting on $M$ preserving $c$ is an equivariant map

$$
v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}
$$

such that $d\langle v, \mathrm{p}\rangle=p\lrcorner c$

## MUlti-moment maps

## DEFINITION

A multi-moment map for $G$ acting on $M$ preserving $c$ is an equivariant map

$$
v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}
$$

such that $d\langle v, \mathrm{p}\rangle=p\lrcorner c$ for all $\mathrm{p} \in \mathcal{P}_{\mathfrak{g}}$.

## MUlti-moment maps

## Definition

A multi-moment map for $G$ acting on $M$ preserving $c$ is an equivariant map

$$
v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}
$$

such that $d\langle v, \mathrm{p}\rangle=p\lrcorner c$ for all $\mathrm{p} \in \mathcal{P}_{\mathfrak{g}}$.
Note that:

## Multi-moment maps

## Definition

A multi-moment map for $G$ acting on $M$ preserving $c$ is an equivariant map

$$
v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}
$$

such that $d\langle v, \mathrm{p}\rangle=p\lrcorner c$ for all $\mathrm{p} \in \mathcal{P}_{\mathfrak{g}}$.
Note that:

- $\mathcal{P}_{\mathfrak{g}}^{*} \subset \Lambda^{2} \mathfrak{g}^{*}$ is a linear subspace depending on $\mathfrak{g}$, not on $M$.


## Multi-moment maps

## Definition

A multi-moment map for $G$ acting on $M$ preserving $c$ is an equivariant map

$$
v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}
$$

such that $d\langle v, \mathrm{p}\rangle=p\lrcorner c$ for all $\mathrm{p} \in \mathcal{P}_{\mathfrak{g}}$.
Note that:

- $\mathcal{P}_{\mathfrak{g}}^{*} \subset \Lambda^{2} \mathfrak{g}^{*}$ is a linear subspace depending on $\mathfrak{g}$, not on $M$.
- For $G$ Abelian, $\mathcal{P}_{\mathfrak{g}}=\Lambda^{2} \mathfrak{g}$.


## Multi-moment maps

## DEFINITION

A multi-moment map for $G$ acting on $M$ preserving $c$ is an equivariant map

$$
v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}
$$

such that $d\langle v, \mathrm{p}\rangle=p\lrcorner c$ for all $\mathrm{p} \in \mathcal{P}_{\mathfrak{g}}$.
Note that:

- $\mathcal{P}_{\mathfrak{g}}^{*} \subset \Lambda^{2} \mathfrak{g}^{*}$ is a linear subspace depending on $\mathfrak{g}$, not on $M$.
- For $G$ Abelian, $\mathcal{P}_{\mathfrak{g}}=\Lambda^{2} \mathfrak{g}$.
- For $G$ semi-simple, $\Lambda^{2} \mathfrak{g} \cong \mathfrak{g} \oplus \mathcal{P}_{\mathfrak{g}}$. In particular, for $G$ compact and simple, $\mathcal{P}_{\mathfrak{g}}$ is the isotropy representation of the isotropy irreducible space $S O(\operatorname{dim} \mathfrak{g}) / G$.


## Outline

(1) Background

Symplectic Geometry
Strong Geometry
Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields Lie kernels

## Existence

(2,3)-trivial Lie algebras
(3) $G_{2}$ HOLONOMY

Reduction
Four-dimensional geometry

## Existence of multi-moment maps

## EXISTENCE OF MULTI-MOMENT MAPS

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c.

## EXISTENCE OF MULTI-MOMENT MAPS

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either

## EXISTENCE OF MULTI-MOMENT MAPS

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,

## Existence of multi-MOMENT MAPs

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact with a $G$-invariant volume form and $b_{1}(M)=0$,

## EXISTENCE OF MULTI-MOMENT MAPS

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact with a $G$-invariant volume form and $b_{1}(M)=0$,
(3) $c=d \beta$ with $\beta$ invariant under $G$ or

## Existence of multi-moment maps

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact with a $G$-invariant volume form and $b_{1}(M)=0$,
(3) $c=d \beta$ with $\beta$ invariant under $G$, or
(4) $b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})$.

## EXISTENCE OF MULTI-MOMENT MAPS

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2. $M$ is compact with a $G$-invariant volume form and $b_{1}(M)=0$,
(3) $c=d \beta$ with $\beta$ invariant under $G$ or
(4) $b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})$.

Cf. the results for symplectic moment maps, noting

## EXISTENCE OF MULTI-MOMENT MAPS

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact with a $G$-invariant volume form and $b_{1}(M)=0$,
(3) $c=d \beta$ with $\beta$ invariant under $G$ or
(4) $b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})$.

Cf. the results for symplectic moment maps, noting

- a symplectic manifold has a canonical volume form $\omega^{n}$,


## Existence of multi-moment maps

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact with a $G$-invariant volume form and $b_{1}(M)=0$,
(3) $c=d \beta$ with $\beta$ invariant under $G$ or
(4) $b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})$.

Cf. the results for symplectic moment maps, noting

- a symplectic manifold has a canonical volume form $\omega^{n}$,
- $G$ is semi-simple if and only if $b_{1}(\mathfrak{g})=0=b_{2}(\mathfrak{g})$.


## Existence of multi-moment maps

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact with a $G$-invariant volume form and $b_{1}(M)=0$,
(3) $c=d \beta$ with $\beta$ invariant under $G$ or
(4) $b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})$.

Cf. the results for symplectic moment maps, noting

- a symplectic manifold has a canonical volume form $\omega^{n}$,
- $G$ is semi-simple if and only if $b_{1}(\mathfrak{g})=0=b_{2}(\mathfrak{g})$.

For item 4,

## Existence of multi-moment maps

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact with a $G$-invariant volume form and $b_{1}(M)=0$,
(3) $c=d \beta$ with $\beta$ invariant under $G$, or
(4) $b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})$.

Cf. the results for symplectic moment maps, noting

- a symplectic manifold has a canonical volume form $\omega^{n}$,
- $G$ is semi-simple if and only if $b_{1}(\mathfrak{g})=0=b_{2}(\mathfrak{g})$.

For item $4, d: \Lambda^{2} \mathfrak{g}^{*} \rightarrow \Lambda^{3} \mathfrak{g}^{*}$ induces a map $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$;

## Existence of multi-moment maps

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form c. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2. $M$ is compact with a $G$-invariant volume form and $b_{1}(M)=0$,
(3) $c=d \beta$ with $\beta$ invariant under $G$ or
(4) $b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})$.

Cf. the results for symplectic moment maps, noting

- a symplectic manifold has a canonical volume form $\omega^{n}$,
- $G$ is semi-simple if and only if $b_{1}(\mathfrak{g})=0=b_{2}(\mathfrak{g})$.

For item $4, d: \Lambda^{2} \mathfrak{g}^{*} \rightarrow \Lambda^{3} \mathfrak{g}^{*}$ induces a map $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$; injective only if $b_{2}(\mathfrak{g})=0$

## Existence of multi-moment maps

## Theorem

Suppose $G$ acts on $M$ preserving the closed three-form $c$. Then a multi-moment map $v: M \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$ exists if either
(1) $G$ is compact and $b_{1}(M)=0$,
(2) $M$ is compact with a $G$-invariant volume form and $b_{1}(M)=0$,
(3) $c=d \beta$ with $\beta$ invariant under $G$ or
(4) $b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})$.

Cf. the results for symplectic moment maps, noting

- a symplectic manifold has a canonical volume form $\omega^{n}$,
- $G$ is semi-simple if and only if $b_{1}(\mathfrak{g})=0=b_{2}(\mathfrak{g})$.

For item $4, d: \Lambda^{2} \mathfrak{g}^{*} \rightarrow \Lambda^{3} \mathfrak{g}^{*}$ induces a map $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$; injective only if $b_{2}(\mathfrak{g})=0$ and surjective only if $b_{3}(\mathfrak{g})=0$.

## Examples I

## Extended phase space <br> $M=\Lambda^{2} T^{*} N, G \subset \operatorname{Diff}(N)$.

## Examples I

> ExTENDED PHASE SPACE
> $M=\Lambda^{2} T^{*} N, G \subset \operatorname{Diff}(N)$. Here $c=d \beta$, so we are case 3 above.

## Examples I

ExTENDED PHASE SPACE
$M=\Lambda^{2} T^{*} N, G \subset \operatorname{Diff}(N)$. Here $c=d \beta$, so we are case 3 above. This has a multi-moment map with $v(\mathrm{p})=\beta(p)$.

$$
M^{8}=S U(3)
$$

## EXAMPLES I

## EXTENDED PHASE SPACE

$M=\Lambda^{2} T^{*} N, G \subset \operatorname{Diff}(N)$. Here $c=d \beta$, so we are case 3 above. This has a multi-moment map with $v(\mathrm{p})=\beta(p)$.

$$
M^{8}=S U(3)
$$

This carries a hypercomplex structure $I, J, K$ found by Joyce (1992)

## Examples I

## ExTENDED PHASE SPACE

$M=\Lambda^{2} T^{*} N, G \subset \operatorname{Diff}(N)$. Here $c=d \beta$, so we are case 3 above. This has a multi-moment map with $v(\mathrm{p})=\beta(p)$.

$$
M^{8}=S U(3)
$$

This carries a hypercomplex structure $I, J, K$ found by Joyce (1992) compatible with the bi-invariant metric.

## Examples I

## ExTENDED PHASE SPACE

$M=\Lambda^{2} T^{*} N, G \subset \operatorname{Diff}(N)$. Here $c=d \beta$, so we are case 3 above. This has a multi-moment map with $v(\mathrm{p})=\beta(p)$.

$$
M^{8}=S U(3)
$$

This carries a hypercomplex structure $I, J, K$ found by Joyce (1992) compatible with the bi-invariant metric. Taking $c_{I}=d F_{I}$, etc.,

## Examples I

## ExTENDED PHASE SPACE

$M=\Lambda^{2} T^{*} N, G \subset \operatorname{Diff}(N)$. Here $c=d \beta$, so we are case 3 above. This has a multi-moment map with $v(\mathrm{p})=\beta(p)$.

## $M^{8}=S U(3)$

This carries a hypercomplex structure $I, J, K$ found by Joyce (1992) compatible with the bi-invariant metric. Taking $c_{I}=d F_{I}$, etc., case 3 above gives three multi-moment maps

$$
v_{I}, v_{J}, v_{K}: M=\operatorname{SU}(3) \rightarrow \mathcal{P}_{\mathfrak{s u}(3)}^{*}
$$

for the left action of $\operatorname{SU}(3)$.

## Examples I

## Extended phase space

$M=\Lambda^{2} T^{*} N, G \subset \operatorname{Diff}(N)$. Here $c=d \beta$, so we are case 3 above. This has a multi-moment map with $v(\mathrm{p})=\beta(p)$.

## $M^{8}=\operatorname{SU}(3)$

This carries a hypercomplex structure $I, J, K$ found by Joyce (1992) compatible with the bi-invariant metric. Taking $c_{I}=d F_{I}$, etc., case 3 above gives three multi-moment maps

$$
v_{I}, v_{J}, v_{K}: M=\operatorname{SU}(3) \rightarrow \mathcal{P}_{\mathfrak{s u}(3)}^{*}
$$

for the left action of $\operatorname{SU}(3)$. Each image is the homogeneous space $F_{1,2}\left(\mathbb{C}^{3}\right)=\operatorname{SU}(3) / T^{2}$.

## Examples I

## Extended phase space

$M=\Lambda^{2} T^{*} N, G \subset \operatorname{Diff}(N)$. Here $c=d \beta$, so we are case 3 above. This has a multi-moment map with $v(\mathrm{p})=\beta(p)$.

## $M^{8}=\operatorname{SU}(3)$

This carries a hypercomplex structure $I, J, K$ found by Joyce (1992) compatible with the bi-invariant metric. Taking $c_{I}=d F_{I}$, etc., case 3 above gives three multi-moment maps

$$
v_{I}, v_{J}, v_{K}: M=\operatorname{SU}(3) \rightarrow \mathcal{P}_{\mathfrak{s u}(3)}^{*}
$$

for the left action of $\operatorname{SU}(3)$. Each image is the homogeneous space $F_{1,2}\left(\mathbb{C}^{3}\right)=S U(3) / T^{2}$. We get an injection

$$
\left(v_{I}, v_{J}, v_{K}\right): \operatorname{SU}(3) \hookrightarrow\left(F_{1,2}\left(\mathbb{C}^{3}\right)\right)^{3}
$$

## Examples II

## $M^{8}=S U(3)$ AGAIN

## Examples II

## $M^{8}=S U(3)$ AGAIN

carries a bi-invariant closed 3-form $c(X, Y, Z)=\langle X,[Y, Z]\rangle$, $X, Y, Z \in \mathfrak{s u}(3)$.

## Examples II

## $M^{8}=S U(3)$ AGAIN

carries a bi-invariant closed 3-form $c(X, Y, Z)=\langle\mathrm{X},[\mathrm{Y}, \mathrm{Z}]\rangle$, $X, Y, Z \in \mathfrak{s u}(3) . M^{8}$ is simply-connected, so $b_{1}(M)=0$.

## Examples II

## $M^{8}=S U(3)$ AGAIN

carries a bi-invariant closed 3-form $c(X, Y, Z)=\langle\mathrm{X},[\mathrm{Y}, \mathrm{Z}]\rangle$, $X, Y, Z \in \mathfrak{s u}(3) . M^{8}$ is simply-connected, so $b_{1}(M)=0$. $S U(3)$ acts on the left,

## Examples II

## $M^{8}=S U(3)$ AGAIN

carries a bi-invariant closed 3-form $c(X, Y, Z)=\langle X,[Y, Z]\rangle$, $X, Y, Z \in \mathfrak{s u}(3) . M^{8}$ is simply-connected, so $b_{1}(M)=0$.
$\operatorname{SU}(3)$ acts on the left, but $c$ is 0 on $\mathcal{P}_{\mathfrak{s u}(3)}$. So although $v_{\mathfrak{s u}(3)}$ exists, it is trivial.

## Examples II

## $M^{8}=S U(3)$ AGAIN

carries a bi-invariant closed 3-form $c(X, Y, Z)=\langle X,[Y, Z]\rangle$, $X, Y, Z \in \mathfrak{s u}(3) . M^{8}$ is simply-connected, so $b_{1}(M)=0$.
$\operatorname{SU}(3)$ acts on the left, but $c$ is 0 on $\mathcal{P}_{\mathfrak{s u}(3)}$. So although $v_{\mathfrak{s u}(3)}$ exists, it is trivial.
Instead, take $G=S U(3) \times U(1)$ acting as $(g, z) \cdot A=g A z^{-1}$.

## Examples II

## $M^{8}=S U(3)$ AGAIN

carries a bi-invariant closed 3-form $c(X, Y, Z)=\langle X,[Y, Z]\rangle$, $X, Y, Z \in \mathfrak{s u}(3) . M^{8}$ is simply-connected, so $b_{1}(M)=0$.
$\operatorname{SU}(3)$ acts on the left, but $c$ is 0 on $\mathcal{P}_{\mathfrak{s u}(3)}$. So although $v_{\mathfrak{s u}(3)}$ exists, it is trivial.
Instead, take $G=S U(3) \times U(1)$ acting as $(g, z) \cdot A=g A z^{-1}$. Now

$$
\operatorname{ker} v_{*}=[\mathfrak{s u}(3), \mathfrak{u}(1)]^{\perp} \cong \mathfrak{u}(2)
$$

## Examples II

## $M^{8}=S U(3)$ AGAIN

carries a bi-invariant closed 3-form $c(X, Y, Z)=\langle X,[Y, Z]\rangle$, $X, Y, Z \in \mathfrak{s u}(3) . M^{8}$ is simply-connected, so $b_{1}(M)=0$.
$\operatorname{SU}(3)$ acts on the left, but $c$ is 0 on $\mathcal{P}_{\mathfrak{s u}(3)}$. So although $v_{\mathfrak{s u}(3)}$ exists, it is trivial.
Instead, take $G=S U(3) \times U(1)$ acting as $(g, z) \cdot A=g A z^{-1}$. Now

$$
\operatorname{ker} v_{*}=[\mathfrak{s u}(3), \mathfrak{u}(1)]^{\perp} \cong \mathfrak{u}(2)
$$

and

$$
v: \operatorname{SU}(3) \rightarrow \mathbb{C P}(2) \subset \mathfrak{s u}(3) \subset \mathfrak{s u}(3)+\mathcal{P}_{\mathfrak{s u}(3)}=\mathcal{P}_{\mathfrak{s u}(3)+\mathfrak{u}(1)}
$$

## Examples II

## $M^{8}=S U(3)$ AGAIN

carries a bi-invariant closed 3-form $c(X, Y, Z)=\langle X,[Y, Z]\rangle$, $X, Y, Z \in \mathfrak{s u}(3) . M^{8}$ is simply-connected, so $b_{1}(M)=0$.
$\operatorname{SU}(3)$ acts on the left, but $c$ is 0 on $\mathcal{P}_{\mathfrak{s u}(3)}$. So although $v_{\mathfrak{s u}(3)}$ exists, it is trivial.
Instead, take $G=S U(3) \times U(1)$ acting as $(g, z) \cdot A=g A z^{-1}$. Now

$$
\operatorname{ker} v_{*}=[\mathfrak{s u}(3), \mathfrak{u}(1)]^{\perp} \cong \mathfrak{u}(2)
$$

and

$$
v: \operatorname{SU}(3) \rightarrow \mathbb{C P}(2) \subset \mathfrak{s u}(3) \subset \mathfrak{s u}(3)+\mathcal{P}_{\mathfrak{s u}(3)}=\mathcal{P}_{\mathfrak{s u}(3)+\mathfrak{u}(1)}
$$

is the description of $S U(3)$ as a hypercomplex (HKT) Swann bundle over the quaternionic Kähler $\mathbb{C P}(2)$.

## Examples III

## Homogeneous spaces and orbits

## Examples III

## Homogeneous spaces and orbits <br> Homogeneous strong manifolds (G/H,c)

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$.

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.

If $b_{2}(\mathfrak{g})=0$

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.
If $b_{2}(\mathfrak{g})=0$ then $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$ is injective.

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.
If $b_{2}(\mathfrak{g})=0$ then $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$ is injective. For $\Psi=d_{\mathcal{P}} \beta$,

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.
If $b_{2}(\mathfrak{g})=0$ then $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$ is injective. For $\Psi=d_{\mathcal{P}} \beta$, the orbits $\mathcal{O}_{\beta}=G \cdot \beta \hookrightarrow \mathcal{P}_{\mathfrak{g}}$ and $G \cdot \Psi$ are identified

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.
If $b_{2}(\mathfrak{g})=0$ then $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$ is injective. For $\Psi=d_{\mathcal{P}} \beta$, the orbits $\mathcal{O}_{\beta}=G \cdot \beta \hookrightarrow \mathcal{P}_{\mathfrak{g}}$ and $G \cdot \Psi$ are identified and the inclusion $\mathcal{O}_{\beta}$

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.
If $b_{2}(\mathfrak{g})=0$ then $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$ is injective. For $\Psi=d_{\mathcal{P}} \beta$, the orbits $\mathcal{O}_{\beta}=G \cdot \beta \hookrightarrow \mathcal{P}_{\mathfrak{g}}$ and $G \cdot \Psi$ are identified and the inclusion $\mathcal{O}_{\beta}$ induces the multi-moment map for the strong geometry on $G / H$.

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.
If $b_{2}(\mathfrak{g})=0$ then $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$ is injective. For $\Psi=d_{\mathcal{P}} \beta$, the orbits $\mathcal{O}_{\beta}=G \cdot \beta \hookrightarrow \mathcal{P}_{\mathfrak{g}}$ and $G \cdot \Psi$ are identified and the inclusion $\mathcal{O}_{\beta}$ induces the multi-moment map for the strong geometry on $G / H$.

## Theorem

If $b_{2}(\mathfrak{g})=0$, each $\mathcal{O}_{\beta} \subset \mathcal{P}_{\mathfrak{g}}^{*}$ arises as the image of a multi-moment map for a strong geometry.

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.
If $b_{2}(\mathfrak{g})=0$ then $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$ is injective. For $\Psi=d_{\mathcal{P}} \beta$, the orbits $\mathcal{O}_{\beta}=G \cdot \beta \hookrightarrow \mathcal{P}_{\mathfrak{g}}$ and $G \cdot \Psi$ are identified and the inclusion $\mathcal{O}_{\beta}$ induces the multi-moment map for the strong geometry on $G / H$.

## Theorem

If $b_{2}(\mathfrak{g})=0$, each $\mathcal{O}_{\beta} \subset \mathcal{P}_{\mathfrak{g}}^{*}$ arises as the image of a multi-moment map for a strong geometry. That geometry may be realised on $\mathcal{O}_{\beta}$ if and only if

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.
If $b_{2}(\mathfrak{g})=0$ then $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$ is injective. For $\Psi=d_{\mathcal{P}} \beta$, the orbits $\mathcal{O}_{\beta}=G \cdot \beta \hookrightarrow \mathcal{P}_{\mathfrak{g}}$ and $G \cdot \Psi$ are identified and the inclusion $\mathcal{O}_{\beta}$ induces the multi-moment map for the strong geometry on $G / H$.

## Theorem

If $b_{2}(\mathfrak{g})=0$, each $\mathcal{O}_{\beta} \subset \mathcal{P}_{\mathfrak{g}}^{*}$ arises as the image of a multi-moment map for a strong geometry. That geometry may be realised on $\mathcal{O}_{\beta}$ if and only if $\operatorname{Liestab}_{G} \beta=\operatorname{ker} d_{\mathcal{P}} \beta$.

## Examples III

## Homogeneous spaces and orbits

Homogeneous strong manifolds $(G / H, c)$ fibre over orbits $G \cdot \Psi$ in $Z^{3}(\mathfrak{g})$ via $c_{e H}(X, Y, Z)=\Psi(X, Y, Z)$. Holds for any $\Psi$ and all $H \subset G$ closed with $\left.\mathfrak{h} \subset \operatorname{ker} \Psi=\{X \in \mathfrak{g}: X\lrcorner \Psi_{0}=0\right\}$.
If $b_{2}(\mathfrak{g})=0$ then $d_{\mathcal{P}}: \mathcal{P}_{\mathfrak{g}}^{*} \rightarrow Z^{3}(\mathfrak{g})$ is injective. For $\Psi=d_{\mathcal{P}} \beta$, the orbits $\mathcal{O}_{\beta}=G \cdot \beta \hookrightarrow \mathcal{P}_{\mathfrak{g}}$ and $G \cdot \Psi$ are identified and the inclusion $\mathcal{O}_{\beta}$ induces the multi-moment map for the strong geometry on $G / H$.

## Theorem

If $b_{2}(\mathfrak{g})=0$, each $\mathcal{O}_{\beta} \subset \mathcal{P}_{\mathfrak{g}}^{*}$ arises as the image of a multi-moment map for a strong geometry. That geometry may be realised on $\mathcal{O}_{\beta}$ if and only if $\operatorname{Lie} \operatorname{stab}_{G} \beta=\operatorname{ker} d_{\mathcal{P}} \beta$. In this case $\mathcal{O}_{\beta}$ is 2 -plectic.

## Outline

(1) Background

Symplectic Geometry
Strong Geometry
Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields
Lie kernels
Existence
(2,3)-trivial Lie algebras
(3) $G_{2}$ Holonomy
Reduction
Four-dimensional geometry

## (2,3)-trivial Lie algebras I

## ( 2,3 )-trivial Lie algebras I

## DEFINITION

A Lie algebra $\mathfrak{g}$ is (cohomologically) $(2,3)$-trivial if

$$
b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})
$$

## ( 2,3 )-trivial Lie algebras I

## DEFINITION

A Lie algebra $\mathfrak{g}$ is (cohomologically) $(2,3)$-trivial if

$$
b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})
$$

## Theorem

Let $\mathfrak{g}$ be a $(2,3)$-trivial Lie algebra. Then $\mathfrak{g}$ is solvable

## ( 2,3 )-trivial Lie algebras I

## Definition

A Lie algebra $\mathfrak{g}$ is (cohomologically) $(2,3)$-trivial if

$$
b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})
$$

## Theorem

Let $\mathfrak{g}$ be a $(2,3)$-trivial Lie algebra. Then $\mathfrak{g}$ is solvable but not nilpotent

## ( 2,3 )-trivial Lie algebras I

## Definition

A Lie algebra $\mathfrak{g}$ is (cohomologically) $(2,3)$-trivial if

$$
b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})
$$

## Theorem

Let $\mathfrak{g}$ be a $(2,3)$-trivial Lie algebra. Then $\mathfrak{g}$ is solvable but not nilpotent and is not a product of smaller dimensional algebras.

## ( 2,3 )-trivial Lie algebras I

## Definition

A Lie algebra $\mathfrak{g}$ is (cohomologically) $(2,3)$-trivial if

$$
b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})
$$

## Theorem

Let $\mathfrak{g}$ be a $(2,3)$-trivial Lie algebra. Then $\mathfrak{g}$ is solvable but not nilpotent and is not a product of smaller dimensional algebras. Writing $\mathfrak{k}=\mathfrak{g}^{\prime}$ for the derived algebra,

## ( 2,3 )-trivial Lie algebras I

## Definition

A Lie algebra $\mathfrak{g}$ is (cohomologically) $(2,3)$-trivial if

$$
b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})
$$

## Theorem

Let $\mathfrak{g}$ be a $(2,3)$-trivial Lie algebra. Then $\mathfrak{g}$ is solvable but not nilpotent and is not a product of smaller dimensional algebras. Writing $\mathfrak{k}=\mathfrak{g}^{\prime}$ for the derived algebra, $\mathfrak{k}$ is nilpotent

## ( 2,3 )-trivial Lie algebras I

## DEFINITION

A Lie algebra $\mathfrak{g}$ is (cohomologically) $(2,3)$-trivial if

$$
b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})
$$

## Theorem

Let $\mathfrak{g}$ be a $(2,3)$-trivial Lie algebra. Then $\mathfrak{g}$ is solvable but not nilpotent and is not a product of smaller dimensional algebras. Writing $\mathfrak{k}=\mathfrak{g}^{\prime}$ for the derived algebra, $\mathfrak{k}$ is nilpotent and $\mathfrak{g} / \mathfrak{k}$ is one-dimensional.

## ( 2,3 )-trivial Lie algebras I

## DEFINITION

A Lie algebra $\mathfrak{g}$ is (cohomologically) $(2,3)$-trivial if

$$
b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})
$$

## Theorem

Let $\mathfrak{g}$ be a $(2,3)$-trivial Lie algebra. Then $\mathfrak{g}$ is solvable but not nilpotent and is not a product of smaller dimensional algebras. Writing $\mathfrak{k}=\mathfrak{g}^{\prime}$ for the derived algebra, $\mathfrak{k}$ is nilpotent and $\mathfrak{g} / \mathfrak{k}$ is one-dimensional.
A one-dimensional solvable extension $\mathfrak{g}=\mathbb{R} X+\mathfrak{k}$ of a nilpotent algebra $\mathfrak{k}$ is (2,3)-trivial

## (2,3)-trivial Lie algebras I

## DEFINITION

A Lie algebra $\mathfrak{g}$ is (cohomologically) $(2,3)$-trivial if

$$
b_{2}(\mathfrak{g})=0=b_{3}(\mathfrak{g})
$$

## Theorem

Let $\mathfrak{g}$ be a $(2,3)$-trivial Lie algebra. Then $\mathfrak{g}$ is solvable but not nilpotent and is not a product of smaller dimensional algebras. Writing $\mathfrak{k}=\mathfrak{g}^{\prime}$ for the derived algebra, $\mathfrak{k}$ is nilpotent and $\mathfrak{g} / \mathfrak{k}$ is one-dimensional.
A one-dimensional solvable extension $\mathfrak{g}=\mathbb{R} X+\mathfrak{k}$ of a nilpotent algebra $\mathfrak{k}$ is $(2,3)$-trivial if and only if the fixed-point spaces $H^{i}(\mathfrak{k})^{X}$ are trivial for $i=1,2$ and 3 .

## (2,3)-TRIVIAL Lie algebras II

- Using the theorem it easy to classify the (2,3)-trivial algebras in small dimensions. Up to dimension 3 we have


## (2,3)-TRIVIAL Lie algebras II

- Using the theorem it easy to classify the (2,3)-trivial algebras in small dimensions. Up to dimension 3 we have
- $(0,21)$,
- $(0,21+31,31)$,
- $(0,21, \lambda 31), \quad|\lambda| \in(0,1)$,
- $(0, \lambda 21+31,-21+\lambda 31), \quad \lambda \geqslant 0$.


## (2,3)-TRIVIAL Lie algebras II

- Using the theorem it easy to classify the (2,3)-trivial algebras in small dimensions. Up to dimension 3 we have
- $(0,21)$,
- $(0,21+31,31)$,
- $(0,21, \lambda 31), \quad|\lambda| \in(0,1)$,
- $(0, \lambda 21+31,-21+\lambda 31), \quad \lambda \geqslant 0$.
- If $\mathfrak{k}$ admits a positive grading $\mathfrak{k}=\oplus_{i \geqslant 1} \mathfrak{k}_{i},\left[\mathfrak{k}_{i}, \mathfrak{k}_{j}\right] \subset \mathfrak{k}_{i+j}$,


## (2,3)-trivial Lie algebras II

- Using the theorem it easy to classify the (2,3)-trivial algebras in small dimensions. Up to dimension 3 we have
- $(0,21)$,
- $(0,21+31,31)$,
- $(0,21, \lambda 31), \quad|\lambda| \in(0,1)$,
- $(0, \lambda 21+31,-21+\lambda 31), \quad \lambda \geqslant 0$.
- If $\mathfrak{k}$ admits a positive grading $\mathfrak{k}=\oplus_{i \geqslant 1} \mathfrak{k}_{i},\left[\mathfrak{k}_{i}, \mathfrak{k}_{j}\right] \subset \mathfrak{k}_{i+j}$, then $\mathfrak{k}=\mathfrak{g}^{\prime}$ for some (2,3)-trivial algebra $\mathfrak{g}$.


## (2,3)-trivial Lie algebras II

- Using the theorem it easy to classify the (2,3)-trivial algebras in small dimensions. Up to dimension 3 we have
- $(0,21)$,
- $(0,21+31,31)$,
- $(0,21, \lambda 31), \quad|\lambda| \in(0,1)$,
- $(0, \lambda 21+31,-21+\lambda 31), \quad \lambda \geqslant 0$.
- If $\mathfrak{k}$ admits a positive grading $\mathfrak{k}=\oplus_{i \geqslant 1} \mathfrak{k}_{i},\left[\mathfrak{k}_{i}, \mathfrak{k}_{j}\right] \subset \mathfrak{k}_{i+j}$, then $\mathfrak{k}=\mathfrak{g}^{\prime}$ for some (2,3)-trivial algebra $\mathfrak{g}$.
- Nilpotent algebras of maximal rank, as studied in association with Kac-Moody algebras, fall in to this class.


## ( 2,3 )-trivial Lie algebras II

- Using the theorem it easy to classify the (2,3)-trivial algebras in small dimensions. Up to dimension 3 we have
- $(0,21)$,
- $(0,21+31,31)$,
- $(0,21, \lambda 31), \quad|\lambda| \in(0,1)$,
- $(0, \lambda 21+31,-21+\lambda 31), \quad \lambda \geqslant 0$.
- If $\mathfrak{k}$ admits a positive grading $\mathfrak{k}=\oplus_{i \geqslant 1} \mathfrak{k}_{i},\left[\mathfrak{k}_{i}, \mathfrak{k}_{j}\right] \subset \mathfrak{k}_{i+j}$, then $\mathfrak{k}=\mathfrak{g}^{\prime}$ for some (2,3)-trivial algebra $\mathfrak{g}$.
- Nilpotent algebras of maximal rank, as studied in association with Kac-Moody algebras, fall in to this class.
- All nilpotent algebras of dimension at most 6 admit a positive grading.


## (2,3)-trivial Lie algebras II

- Using the theorem it easy to classify the (2,3)-trivial algebras in small dimensions. Up to dimension 3 we have
- $(0,21)$,
- $(0,21+31,31)$,
- $(0,21, \lambda 31), \quad|\lambda| \in(0,1)$,
- $(0, \lambda 21+31,-21+\lambda 31), \quad \lambda \geqslant 0$.
- If $\mathfrak{k}$ admits a positive grading $\mathfrak{k}=\oplus_{i \geqslant 1} \mathfrak{k}_{i},\left[\mathfrak{k}_{i}, \mathfrak{k}_{j}\right] \subset \mathfrak{k}_{i+j}$, then $\mathfrak{k}=\mathfrak{g}^{\prime}$ for some (2,3)-trivial algebra $\mathfrak{g}$.
- Nilpotent algebras of maximal rank, as studied in association with Kac-Moody algebras, fall in to this class.
- All nilpotent algebras of dimension at most 6 admit a positive grading.
- There exist 7-dimensional nilpotent Lie algebras $\mathfrak{n}$ with $\operatorname{Der}(\mathfrak{n})$ nilpotent.


## (2,3)-trivial Lie algebras II

- Using the theorem it easy to classify the (2,3)-trivial algebras in small dimensions. Up to dimension 3 we have
- $(0,21)$,
- $(0,21+31,31)$,
- $(0,21, \lambda 31), \quad|\lambda| \in(0,1)$,
- $(0, \lambda 21+31,-21+\lambda 31), \quad \lambda \geqslant 0$.
- If $\mathfrak{k}$ admits a positive grading $\mathfrak{k}=\oplus_{i \geqslant 1} \mathfrak{k}_{i},\left[\mathfrak{k}_{i}, \mathfrak{k}_{j}\right] \subset \mathfrak{k}_{i+j}$, then $\mathfrak{k}=\mathfrak{g}^{\prime}$ for some (2,3)-trivial algebra $\mathfrak{g}$.
- Nilpotent algebras of maximal rank, as studied in association with Kac-Moody algebras, fall in to this class.
- All nilpotent algebras of dimension at most 6 admit a positive grading.
- There exist 7-dimensional nilpotent Lie algebras $\mathfrak{n}$ with $\operatorname{Der}(\mathfrak{n})$ nilpotent. These can not be the derived algebra of a (2,3)-trivial Lie algebra.


## (2,3)-trivial Lie algebras II

- Using the theorem it easy to classify the (2,3)-trivial algebras in small dimensions. Up to dimension 3 we have
- $(0,21)$,
- $(0,21+31,31)$,
- $(0,21, \lambda 31), \quad|\lambda| \in(0,1)$,
- $(0, \lambda 21+31,-21+\lambda 31), \quad \lambda \geqslant 0$.
- If $\mathfrak{k}$ admits a positive grading $\mathfrak{k}=\oplus_{i \geqslant 1} \mathfrak{k}_{i},\left[\mathfrak{k}_{i}, \mathfrak{k}_{j}\right] \subset \mathfrak{k}_{i+j}$, then $\mathfrak{k}=\mathfrak{g}^{\prime}$ for some (2,3)-trivial algebra $\mathfrak{g}$.
- Nilpotent algebras of maximal rank, as studied in association with Kac-Moody algebras, fall in to this class.
- All nilpotent algebras of dimension at most 6 admit a positive grading.
- There exist 7-dimensional nilpotent Lie algebras $\mathfrak{n}$ with $\operatorname{Der}(\mathfrak{n})$ nilpotent. These can not be the derived algebra of a ( 2,3 )-trivial Lie algebra.
- There exist unimodular (2,3)-trivial Lie groups admitting compact discrete quotients ( $\operatorname{dim} G \geqslant 5$ ).


## Outline

(1) BACKGROUND

Symplectic Geometry
Strong Geometry
Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields
Lie kernels
Existence
(2,3)-trivial Lie algebras
(3) $G_{2}$ HOLONOMY

## Reduction

Four-dimensional geometry

## $G_{2}$ STRUCTURES WITH TORUS SYMMETRY

Let $\left(M^{7}, g, \phi\right)$ be a manifold with holonomy $G_{2}$,

## $G_{2}$ STRUCTURES WITH TORUS SYMMETRY

Let $\left(M^{7}, g, \phi\right)$ be a manifold with holonomy $G_{2}$, meaning that $d \phi=0, d * \phi=0$ and that at each point there is an orthonormal coframe such that

$$
\phi=e_{123}+e_{145}+e_{167}+e_{246}-e_{257}-e_{356}-e_{347} .
$$

## $G_{2}$ STRUCTURES WITH TORUS SYMMETRY

Let $\left(M^{7}, g, \phi\right)$ be a manifold with holonomy $G_{2}$, meaning that $d \phi=0, d * \phi=0$ and that at each point there is an orthonormal coframe such that

$$
\phi=e_{123}+e_{145}+e_{167}+e_{246}-e_{257}-e_{356}-e_{347} .
$$

The metric $g$ is then Ricci-flat with holonomy contained in $G_{2}$.

## $G_{2}$ STRUCTURES WITH TORUS SYMMETRY

Let $\left(M^{7}, g, \phi\right)$ be a manifold with holonomy $G_{2}$, meaning that $d \phi=0, d * \phi=0$ and that at each point there is an orthonormal coframe such that

$$
\phi=e_{123}+e_{145}+e_{167}+e_{246}-e_{257}-e_{356}-e_{347}
$$

The metric $g$ is then Ricci-flat with holonomy contained in $G_{2}$. Suppose $T^{2}$ acts preserving the $G_{2}$-structure,

## $G_{2}$ STRUCTURES WITH TORUS SYMMETRY

Let $\left(M^{7}, g, \phi\right)$ be a manifold with holonomy $G_{2}$, meaning that $d \phi=0, d * \phi=0$ and that at each point there is an orthonormal coframe such that

$$
\phi=e_{123}+e_{145}+e_{167}+e_{246}-e_{257}-e_{356}-e_{347} .
$$

The metric $g$ is then Ricci-flat with holonomy contained in $G_{2}$. Suppose $T^{2}$ acts preserving the $G_{2}$-structure, generated by $U_{i}$. Then a multi-moment map $v$ exists, e.g. if $b_{1}(M)=0$,

## $G_{2}$ STRUCTURES WITH TORUS SYMMETRY

Let $\left(M^{7}, g, \phi\right)$ be a manifold with holonomy $G_{2}$, meaning that $d \phi=0, d * \phi=0$ and that at each point there is an orthonormal coframe such that

$$
\phi=e_{123}+e_{145}+e_{167}+e_{246}-e_{257}-e_{356}-e_{347} .
$$

The metric $g$ is then Ricci-flat with holonomy contained in $G_{2}$. Suppose $T^{2}$ acts preserving the $G_{2}$-structure, generated by $U_{i}$. Then a multi-moment map $v$ exists, e.g. if $b_{1}(M)=0$, and

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

## $G_{2}$ STRUCTURES WITH TORUS SYMMETRY

Let $\left(M^{7}, g, \phi\right)$ be a manifold with holonomy $G_{2}$, meaning that $d \phi=0, d * \phi=0$ and that at each point there is an orthonormal coframe such that

$$
\phi=e_{123}+e_{145}+e_{167}+e_{246}-e_{257}-e_{356}-e_{347}
$$

The metric $g$ is then Ricci-flat with holonomy contained in $G_{2}$. Suppose $T^{2}$ acts preserving the $G_{2}$-structure, generated by $U_{i}$. Then a multi-moment map $v$ exists, e.g. if $b_{1}(M)=0$, and

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

with

$$
\left.\left.\left.\omega_{0}=U_{1}\right\lrcorner U_{2}\right\lrcorner * \phi, \quad \omega_{i}=U_{i}\right\lrcorner \phi, \quad\left(g_{\left.u u g_{V V}-g_{U V}^{2}\right) h^{2}=1 .} .\right.
$$

## Reduction of $G_{2}$ structures

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

## Reduction of $G_{2}$ structures

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

Let $\mathcal{X}=v^{-1}(t)$.

## Reduction of $G_{2}$ structures

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

Let $\mathcal{X}=v^{-1}(t)$. Suppose $T^{2}$ acts freely and put $M=\mathcal{X} / T^{2}$.

## Reduction of $G_{2}$ structures

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

Let $\mathcal{X}=v^{-1}(t)$. Suppose $T^{2}$ acts freely and put $M=\mathcal{X} / T^{2}$.

## Proposition

The half-flat SU(3)-manifold $\mathcal{X}$

## Reduction of $G_{2}$ structures

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

Let $\mathcal{X}=v^{-1}(t)$. Suppose $T^{2}$ acts freely and put $M=\mathcal{X} / T^{2}$.

## Proposition

The half-flat SU(3)-manifold $\mathcal{X}$ is a principal $T^{2}$-bundle over $M^{4}$

## Reduction of $G_{2}$ structures

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

Let $\mathcal{X}=v^{-1}(t)$. Suppose $T^{2}$ acts freely and put $M=\mathcal{X} / T^{2}$.

## Proposition

The half-flat SU(3)-manifold $\mathcal{X}$ is a principal $T^{2}$-bundle over $M^{4}$ with $\theta_{i}$ as connection one forms.

## Reduction of $G_{2}$ structures

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

Let $\mathcal{X}=v^{-1}(t)$. Suppose $T^{2}$ acts freely and put $M=\mathcal{X} / T^{2}$.

## Proposition

The half-flat SU(3)-manifold $\mathcal{X}$ is a principal $T^{2}$-bundle over $M^{4}$ with $\theta_{i}$ as connection one forms. The forms $\omega_{j}, j=0,1,2$, descend to $M^{4}$

## Reduction of $G_{2}$ structures

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

Let $\mathcal{X}=v^{-1}(t)$. Suppose $T^{2}$ acts freely and put $M=\mathcal{X} / T^{2}$.

## Proposition

The half-flat SU(3)-manifold $\mathcal{X}$ is a principal $T^{2}$-bundle over $M^{4}$ with $\theta_{i}$ as connection one forms. The forms $\omega_{j}, j=0,1,2$, descend to $M^{4}$ as pointwise linearly independent symplectic forms

## Reduction of $G_{2}$ structures

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

Let $\mathcal{X}=v^{-1}(t)$. Suppose $T^{2}$ acts freely and put $M=\mathcal{X} / T^{2}$.

## Proposition

The half-flat SU(3)-manifold $\mathcal{X}$ is a principal $T^{2}$-bundle over $M^{4}$ with $\theta_{i}$ as connection one forms. The forms $\omega_{j}, j=0,1,2$, descend to $M^{4}$ as pointwise linearly independent symplectic forms that are self-dual for the induced metric.

## Reduction of $G_{2}$ structures

$$
\phi=h^{2} \omega_{0} \wedge d v+d v \wedge \theta_{1} \wedge \theta_{2}+\sum_{i=1}^{2} \theta_{i} \wedge \omega_{i}
$$

Let $\mathcal{X}=v^{-1}(t)$. Suppose $T^{2}$ acts freely and put $M=\mathcal{X} / T^{2}$.

## Proposition

The half-flat SU(3)-manifold $\mathcal{X}$ is a principal $T^{2}$-bundle over $M^{4}$ with $\theta_{i}$ as connection one forms. The forms $\omega_{j}, j=0,1,2$, descend to $M^{4}$ as pointwise linearly independent symplectic forms that are self-dual for the induced metric.

One has

$$
\begin{gathered}
h^{2} \omega_{0}^{2}=g_{u u}^{-1} \omega_{1}^{2}=g_{V V}^{-1} \omega_{2}^{2}=2 \operatorname{vol}_{M} \\
\omega_{0} \wedge \omega_{1}=0=\omega_{0} \wedge \omega_{2}, \quad \omega_{1} \wedge \omega_{2}=2 g_{U V} \operatorname{vol}_{M}
\end{gathered}
$$

## Outline

(1) Background

> Symplectic Geometry
> Strong Geometry
> Covariant Moment Maps
(2) Multi-moment maps

Commuting vector fields
Lie kernels
Existence
(2,3)-trivial Lie algebras
(3) $G_{2}$ HOLONOMY

## Reduction

## Four-dimensional geometry

## Four-dimensional geometry

$\Lambda_{+}=\operatorname{span}_{\mathbb{R}}\left\{\omega_{0}, \omega_{1}, \omega_{2}\right\}$ defines a conformal structure $\mathcal{C}$ on $M^{4}$.

## FOUR-DIMENSIONAL GEOMETRY

$\Lambda_{+}=\operatorname{span}_{\mathbb{R}}\left\{\omega_{0}, \omega_{1}, \omega_{2}\right\}$ defines a conformal structure $\mathcal{C}$ on $M^{4}$. Call such a triple of symplectic forms coherent

## Four-dimensional geometry

$\Lambda_{+}=\operatorname{span}_{\mathbb{R}}\left\{\omega_{0}, \omega_{1}, \omega_{2}\right\}$ defines a conformal structure $\mathcal{C}$ on $M^{4}$. Call such a triple of symplectic forms coherent if $\omega_{0} \wedge \omega_{i}=0, i=1,2$, and

## Four-dimensional geometry

$\Lambda_{+}=\operatorname{span}_{\mathbb{R}}\left\{\omega_{0}, \omega_{1}, \omega_{2}\right\}$ defines a conformal structure $\mathcal{C}$ on $M^{4}$. Call such a triple of symplectic forms coherent if $\omega_{0} \wedge \omega_{i}=0, i=1,2$, and $Q=\left(\left\langle\omega_{i}, \omega_{j}\right\rangle\right)_{i, j=1,2}$ is positive definite.

## Four-dimensional geometry

$\Lambda_{+}=\operatorname{span}_{\mathbb{R}}\left\{\omega_{0}, \omega_{1}, \omega_{2}\right\}$ defines a conformal structure $\mathcal{C}$ on $M^{4}$. Call such a triple of symplectic forms coherent if $\omega_{0} \wedge \omega_{i}=0, i=1,2$, and $Q=\left(\left\langle\omega_{i}, \omega_{j}\right\rangle\right)_{i, j=1,2}$ is positive definite. Write $h=\sqrt{\operatorname{det} Q}$ and let $g \in \mathcal{C}$ satisfy $h^{2} \omega_{0}^{2}=2 \operatorname{vol}_{g}$.

## Proposition

Suppose $\left(\omega_{j}, j=0,1,2\right)$ is a coherent triple of symplectic forms on $M^{4}$.

## Four-dimensional geometry

$\Lambda_{+}=\operatorname{span}_{\mathbb{R}}\left\{\omega_{0}, \omega_{1}, \omega_{2}\right\}$ defines a conformal structure $\mathcal{C}$ on $M^{4}$. Call such a triple of symplectic forms coherent if $\omega_{0} \wedge \omega_{i}=0, i=1,2$, and $Q=\left(\left\langle\omega_{i}, \omega_{j}\right\rangle\right)_{i, j=1,2}$ is positive definite. Write $h=\sqrt{\operatorname{det} Q}$ and let $g \in \mathcal{C}$ satisfy $h^{2} \omega_{0}^{2}=2 \operatorname{vol}_{g}$.

## Proposition

Suppose $\left(\omega_{j}, j=0,1,2\right)$ is a coherent triple of symplectic forms on $M^{4}$. Let $\mathcal{X} \rightarrow M$ be a $T^{2}$-bundle with connection one-forms $\theta_{i}$, $i=1,2$.

## Four-dimensional geometry

$\Lambda_{+}=\operatorname{span}_{\mathbb{R}}\left\{\omega_{0}, \omega_{1}, \omega_{2}\right\}$ defines a conformal structure $\mathcal{C}$ on $M^{4}$. Call such a triple of symplectic forms coherent if $\omega_{0} \wedge \omega_{i}=0, i=1,2$, and $Q=\left(\left\langle\omega_{i}, \omega_{j}\right\rangle\right)_{i, j=1,2}$ is positive definite. Write $h=\sqrt{\operatorname{det} Q}$ and let $g \in \mathcal{C}$ satisfy $h^{2} \omega_{0}^{2}=2 \operatorname{vol}_{g}$.

## Proposition

Suppose $\left(\omega_{j}, j=0,1,2\right)$ is a coherent triple of symplectic forms on $M^{4}$. Let $\mathcal{X} \rightarrow M$ be a $T^{2}$-bundle with connection one-forms $\theta_{i}$, $i=1,2$. Then

$$
\sigma=h \omega_{0}+h^{-1} \theta_{1} \wedge \theta_{2}, \quad \psi_{+}=\omega_{1} \wedge \theta_{1}+\omega_{2} \wedge \theta_{2}
$$

## Four-dimensional geometry

$\Lambda_{+}=\operatorname{span}_{\mathbb{R}}\left\{\omega_{0}, \omega_{1}, \omega_{2}\right\}$ defines a conformal structure $\mathcal{C}$ on $M^{4}$. Call such a triple of symplectic forms coherent if $\omega_{0} \wedge \omega_{i}=0, i=1,2$, and $Q=\left(\left\langle\omega_{i}, \omega_{j}\right\rangle\right)_{i, j=1,2}$ is positive definite. Write $h=\sqrt{\operatorname{det} Q}$ and let $g \in \mathcal{C}$ satisfy $h^{2} \omega_{0}^{2}=2 \operatorname{vol}_{g}$.

## Proposition

Suppose $\left(\omega_{j}, j=0,1,2\right)$ is a coherent triple of symplectic forms on $M^{4}$. Let $\mathcal{X} \rightarrow M$ be a $T^{2}$-bundle with connection one-forms $\theta_{i}$, $i=1,2$. Then

$$
\sigma=h \omega_{0}+h^{-1} \theta_{1} \wedge \theta_{2}, \quad \psi_{+}=\omega_{1} \wedge \theta_{1}+\omega_{2} \wedge \theta_{2}
$$

defines a half-flat SU(3)-structure on $\mathcal{X}$ if and only if

## Four-dimensional geometry

$\Lambda_{+}=\operatorname{span}_{\mathbb{R}}\left\{\omega_{0}, \omega_{1}, \omega_{2}\right\}$ defines a conformal structure $\mathcal{C}$ on $M^{4}$. Call such a triple of symplectic forms coherent if $\omega_{0} \wedge \omega_{i}=0, i=1,2$, and $Q=\left(\left\langle\omega_{i}, \omega_{j}\right\rangle\right)_{i, j=1,2}$ is positive definite. Write $h=\sqrt{\operatorname{det} Q}$ and let $g \in \mathcal{C}$ satisfy $h^{2} \omega_{0}^{2}=2 \operatorname{vol}_{g}$.

## Proposition

Suppose $\left(\omega_{j}, j=0,1,2\right)$ is a coherent triple of symplectic forms on $M^{4}$. Let $\mathcal{X} \rightarrow M$ be a $T^{2}$-bundle with connection one-forms $\theta_{i}$, $i=1,2$. Then

$$
\sigma=h \omega_{0}+h^{-1} \theta_{1} \wedge \theta_{2}, \quad \psi_{+}=\omega_{1} \wedge \theta_{1}+\omega_{2} \wedge \theta_{2}
$$

defines a half-flat SU(3)-structure on $\mathcal{X}$ if and only if $\left(d \theta_{1}^{+}, d \theta_{2}^{+}\right)=\left(\omega_{1}, \omega_{2}\right) A$ with $\langle A, Q\rangle=0$.

## LIFTING

## LIfTING

## Theorem <br> If the data on $M^{4}$ is analytic,

## Lifting

## Theorem

If the data on $M^{4}$ is analytic, then the flow

$$
\psi_{+}^{\prime}=d(h \sigma) \quad\left(\frac{1}{2} \sigma^{2}\right)^{\prime}=-d\left(h \psi_{-}\right)
$$

with initial data $\left(X, \sigma, \psi_{+}\right)$defined above

## LIfTING

## Theorem

If the data on $M^{4}$ is analytic, then the flow

$$
\psi_{+}^{\prime}=d(h \sigma) \quad\left(\frac{1}{2} \sigma^{2}\right)^{\prime}=-d\left(h \psi_{-}\right)
$$

with initial data $\left(X, \sigma, \psi_{+}\right)$defined above defines a unique metric with holonomy $G_{2}$ on an open neighbourhood of $X \times\{0\}$ in $X \times \mathbb{R}$.

## LIfTING

## Theorem

If the data on $M^{4}$ is analytic, then the flow

$$
\psi_{+}^{\prime}=d(h \sigma) \quad\left(\frac{1}{2} \sigma^{2}\right)^{\prime}=-d\left(h \psi_{-}\right)
$$

with initial data $\left(X, \sigma, \psi_{+}\right)$defined above defines a unique metric with holonomy $G_{2}$ on an open neighbourhood of $X \times\{0\}$ in $X \times \mathbb{R}$. Every $G_{2}$ holonomy structure with effective $T^{2}$ symmetry arises in this way.

## Lifting

## Theorem

If the data on $M^{4}$ is analytic, then the flow

$$
\psi_{+}^{\prime}=d(h \sigma) \quad\left(\frac{1}{2} \sigma^{2}\right)^{\prime}=-d\left(h \psi_{-}\right)
$$

with initial data $\left(X, \sigma, \psi_{+}\right)$defined above defines a unique metric with holonomy $G_{2}$ on an open neighbourhood of $X \times\{0\}$ in $X \times \mathbb{R}$. Every $G_{2}$ holonomy structure with effective $T^{2}$ symmetry arises in this way.

The related flow with $h \equiv 1$ has been studied by Hitchin (2001).

## LIfting

## Theorem

If the data on $M^{4}$ is analytic, then the flow

$$
\psi_{+}^{\prime}=d(h \sigma) \quad\left(\frac{1}{2} \sigma^{2}\right)^{\prime}=-d\left(h \psi_{-}\right)
$$

with initial data $\left(X, \sigma, \psi_{+}\right)$defined above defines a unique metric with holonomy $G_{2}$ on an open neighbourhood of $X \times\{0\}$ in $X \times \mathbb{R}$. Every $G_{2}$ holonomy structure with effective $T^{2}$ symmetry arises in this way.

The related flow with $h \equiv 1$ has been studied by Hitchin (2001). However, it does not preserve the multi-moment map structure.

## LIfting

## Theorem

If the data on $M^{4}$ is analytic, then the flow

$$
\psi_{+}^{\prime}=d(h \sigma) \quad\left(\frac{1}{2} \sigma^{2}\right)^{\prime}=-d\left(h \psi_{-}\right)
$$

with initial data $\left(X, \sigma, \psi_{+}\right)$defined above defines a unique metric with holonomy $G_{2}$ on an open neighbourhood of $X \times\{0\}$ in $X \times \mathbb{R}$. Every $G_{2}$ holonomy structure with effective $T^{2}$ symmetry arises in this way.

The related flow with $h \equiv 1$ has been studied by Hitchin (2001). However, it does not preserve the multi-moment map structure. Bryant (2010) has provided examples of initial data for the Hitchin flow that have no solution.

## Example

$M^{4} \rightarrow T^{4} /\{ \pm 1\}$ a Kummer surface, with $\omega_{c}=\omega_{1}+i \omega_{2}$ complex symplectic and integral.

## Example

$M^{4} \rightarrow T^{4} /\{ \pm 1\}$ a Kummer surface, with $\omega_{c}=\omega_{1}+i \omega_{2}$ complex symplectic and integral. Let $\omega_{0}$ be any compatible Kähler form.

## EXAMPLE

$M^{4} \rightarrow T^{4} /\{ \pm 1\}$ a Kummer surface, with $\omega_{c}=\omega_{1}+i \omega_{2}$ complex symplectic and integral. Let $\omega_{0}$ be any compatible Kähler form. Then the $T^{2}$-bundle with curvatures $\left(\omega_{2},-\omega_{1}\right)$ carries half-flat $S U(3)$-structures on its total space for each choice of compatible conformal structure on $M^{4}$.

## Example

$M^{4} \rightarrow T^{4} /\{ \pm 1\}$ a Kummer surface, with $\omega_{c}=\omega_{1}+i \omega_{2}$ complex symplectic and integral. Let $\omega_{0}$ be any compatible Kähler form. Then the $T^{2}$-bundle with curvatures $\left(\omega_{2},-\omega_{1}\right)$ carries half-flat $S U(3)$-structures on its total space for each choice of compatible conformal structure on $M^{4}$. Any analytic choice of $\omega_{1}$ gives a flow to a holonomy $G_{2}$-metric.

## Example

$M^{4} \rightarrow T^{4} /\{ \pm 1\}$ a Kummer surface, with $\omega_{c}=\omega_{1}+i \omega_{2}$ complex symplectic and integral. Let $\omega_{0}$ be any compatible Kähler form. Then the $T^{2}$-bundle with curvatures $\left(\omega_{2},-\omega_{1}\right)$ carries half-flat $S U(3)$-structures on its total space for each choice of compatible conformal structure on $M^{4}$. Any analytic choice of $\omega_{1}$ gives a flow to a holonomy $G_{2}$-metric.

More general than Apostolov and Salamon (2004): we do not need a hyperKähler triple $\omega_{i}$.

## Example

$M^{4} \rightarrow T^{4} /\{ \pm 1\}$ a Kummer surface, with $\omega_{c}=\omega_{1}+i \omega_{2}$ complex symplectic and integral. Let $\omega_{0}$ be any compatible Kähler form. Then the $T^{2}$-bundle with curvatures $\left(\omega_{2},-\omega_{1}\right)$ carries half-flat $S U(3)$-structures on its total space for each choice of compatible conformal structure on $M^{4}$. Any analytic choice of $\omega_{1}$ gives a flow to a holonomy $G_{2}$-metric.

More general than Apostolov and Salamon (2004): we do not need a hyperKähler triple $\omega_{i}$. However, if the triple is hyperKähler we can be explicit.

## Example

$M^{4} \rightarrow T^{4} /\{ \pm 1\}$ a Kummer surface, with $\omega_{c}=\omega_{1}+i \omega_{2}$ complex symplectic and integral. Let $\omega_{0}$ be any compatible Kähler form. Then the $T^{2}$-bundle with curvatures $\left(\omega_{2},-\omega_{1}\right)$ carries half-flat $S U(3)$-structures on its total space for each choice of compatible conformal structure on $M^{4}$. Any analytic choice of $\omega_{1}$ gives a flow to a holonomy $G_{2}$-metric.

More general than Apostolov and Salamon (2004): we do not need a hyperKähler triple $\omega_{i}$. However, if the triple is hyperKähler we can be explicit.

Donaldson (2006) asks whether the underlying compact manifold is always hyperKähler.

## Summary

## Summary

- Multi-moment maps are defined $v:(M, c) \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$, where $\mathcal{P}_{\mathfrak{g}}=\operatorname{ker}\left([\cdot, \cdot]: \Lambda^{2} \mathfrak{g} \rightarrow \mathfrak{g}\right)$.


## Summary

- Multi-moment maps are defined $v:(M, c) \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$, where $\mathcal{P}_{\mathfrak{g}}=\operatorname{ker}\left([\cdot, \cdot]: \Lambda^{2} \mathfrak{g} \rightarrow \mathfrak{g}\right)$.
- These take values in a vector space and exist under weak topological assumptions on $M$ or under cohomological assumptions on $\mathfrak{g}$.


## Summary

- Multi-moment maps are defined $v:(M, c) \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$, where $\mathcal{P}_{\mathfrak{g}}=\operatorname{ker}\left([\cdot, \cdot]: \Lambda^{2} \mathfrak{g} \rightarrow \mathfrak{g}\right)$.
- These take values in a vector space and exist under weak topological assumptions on $M$ or under cohomological assumptions on $\mathfrak{g}$.
- Homogeneous examples may be described via orbits in $\Lambda^{*} \mathfrak{g}^{*}$.


## Summary

- Multi-moment maps are defined $v:(M, c) \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$, where $\mathcal{P}_{\mathfrak{g}}=\operatorname{ker}\left([\cdot, \cdot]: \Lambda^{2} \mathfrak{g} \rightarrow \mathfrak{g}\right)$.
- These take values in a vector space and exist under weak topological assumptions on $M$ or under cohomological assumptions on $\mathfrak{g}$.
- Homogeneous examples may be described via orbits in $\Lambda^{*} \mathfrak{g}^{*}$.
- $(2,3)$-trivial Lie algebras may be classified in small dimensions and described and as certain one-dimensional solvable extensions of nilpotent algebras in general.


## Summary

- Multi-moment maps are defined $v:(M, c) \rightarrow \mathcal{P}_{\mathfrak{g}}^{*}$, where $\mathcal{P}_{\mathfrak{g}}=\operatorname{ker}\left([\cdot, \cdot]: \Lambda^{2} \mathfrak{g} \rightarrow \mathfrak{g}\right)$.
- These take values in a vector space and exist under weak topological assumptions on $M$ or under cohomological assumptions on $\mathfrak{g}$.
- Homogeneous examples may be described via orbits in $\Lambda^{*} \mathfrak{g}^{*}$.
- $(2,3)$-trivial Lie algebras may be classified in small dimensions and described and as certain one-dimensional solvable extensions of nilpotent algebras in general.
- $G_{2}$ holonomy manifolds with $T^{2}$-symmetry correspond via multi-moment map reduction to coherent symplectic triples on $M^{4}$.


## References I

V. Apostolov and S. Salamon. Kähler reduction of metrics with holonomy G2. Comm. Math. Phys., 246(1):43-61, March 2004.
John C. Baez, Alexander E. Hoffnung, and Christopher L. Rogers. Categorified symplectic geometry and the classical string. Comm. Math. Phys., 293(3):701-725, 2010. ISSN 0010-3616. doi: $10.1007 / \mathrm{s} 00220-009-0951-9$. URL http://dx.doi.org/10.1007/s00220-009-0951-9.
Robert L. Bryant. Nonembeddings and nonextentsion results in special holonomy. In The Many Facets of Geometry: A Tribute to Nigel Hitchin. Oxford University Press, 2010.

## References II

J. F. Cariñena, M. Crampin, and L. A. Ibort. On the multisymplectic formalism for first order field theories. Differential Geom. Appl., 1(4):345-374, 1991. ISSN 0926-2245. doi: 10.1016/0926-2245(91)90013-Y. URL http://dx.doi.org/10.1016/0926-2245(91)90013-Y.
S. K. Donaldson. Two-forms on four-manifolds and elliptic equations. In Inspired by S. S. Chern, volume 11 of Nankai Tracts Math., pages 153-172. World Sci. Publ., Hackensack, NJ, 2006.
P. Gauduchon. La 1-forme de torsion d'une variété hermitienne compacte. Math. Ann., 267:495-518, 1984.
Mark J. Gotay, James Isenberg, Jerrold E. Marsden, and Richard Montgomery. Momentum maps and classical relativistic fields. part I: Covariant field theory, January 1998. eprint arXiv:physics/9801019[math-ph].

## References III

N. J. Hitchin. Stable forms and special metrics. In Global differential geometry: the mathematical legacy of Alfred Gray (Bilbao, 2000), volume 288 of Contemp. Math., pages 70-89. Amer. Math. Soc., Providence, RI, 2001.
D. Joyce. Compact hypercomplex and quaternionic manifolds. J. Differential Geom., 35:743-761, 1992.

