
Contents

Foreword: MASS and REU at Penn State University	xi
Preface	xiii
Chapter 1. Various Ways of Representing Surfaces and Basic Examples	1
Lecture 1	1
a. First examples	1
b. Equations vs. other methods	4
c. Planar models	8
d. Projective plane and flat torus as factor spaces	9
Lecture 2	11
a. Equations for surfaces and local coordinates	11
b. Other ways of introducing local coordinates	14
c. Parametric representations	16
d. Metrics on surfaces	17
Lecture 3	18
a. More about the Möbius strip and projective plane	18
b. A first glance at geodesics	20
c. Parametric representations of curves	22
d. Difficulties with representation by embedding	24
e. Regularity conditions for parametrically defined surfaces	27

Lecture 4	28
a. Remarks on metric spaces and topology	28
b. Homeomorphisms and isometries	31
c. Other notions of dimension	32
d. Geodesics	33
Lecture 5	34
a. Isometries of the Euclidean plane	34
b. Isometries of the sphere and the elliptic plane	38
Lecture 6	39
a. Classification of isometries of the sphere and the elliptic plane	39
b. Area of a spherical triangle	41
Lecture 7	43
a. Spaces with lots of isometries	43
b. Symmetric spaces	45
c. Remarks concerning direct products	47
Chapter 2. Combinatorial Structure and Topological Classification of Surfaces	49
Lecture 8	49
a. Topology and combinatorial structure on surfaces	49
b. Triangulation	52
c. Euler characteristic	56
Lecture 9	58
a. Continuation of the proof of Theorem 2.4	58
b. Calculation of Euler characteristic	65
Lecture 10	67
a. From triangulations to maps	67
b. Examples	70
Lecture 11	73
a. Euler characteristic of planar models	73
b. Attaching handles	74
c. Orientability	77
d. Inverted handles and Möbius caps	79

Lecture 12	80
a. Non-orientable surfaces and Möbius caps	80
b. Calculation of Euler characteristic	81
c. Covering non-orientable surfaces	83
d. Classification of orientable surfaces	85
Lecture 13	86
a. Proof of the classification theorem	86
b. Non-orientable surfaces: Classification and models	91
Lecture 14	92
a. Chain complexes and Betti numbers	92
b. Homology of surfaces	94
c. A second interpretation of Euler characteristic	96
Lecture 15	98
a. Interpretation of the Betti numbers	98
b. Torsion in the first homology and non-orientability	100
c. Another derivation of interpretation of Betti numbers	101
Chapter 3. Differentiable Structure on Surfaces: Real and Complex	103
Lecture 16	103
a. Charts and atlases	103
b. First examples of atlases	106
Lecture 17	109
a. Differentiable manifolds	109
b. Diffeomorphisms	110
c. More examples of charts and atlases	113
Lecture 18	117
a. Embedded surfaces	117
b. Gluing surfaces	117
c. Quotient spaces	118
d. Removing singularities	120
Lecture 19	121
a. Riemann surfaces: Definition and first examples	121
b. Holomorphic equivalence of Riemann surfaces	125

c.	Conformal property of holomorphic functions and invariance of angles on Riemann surfaces	127
d.	Complex tori and the modular surface	129
	Lecture 20	130
a.	Differentiable functions on real surfaces	130
b.	Morse functions	135
c.	The third incarnation of Euler characteristic	138
	Lecture 21	141
a.	Functions with degenerate critical points	141
b.	Degree of a circle map	145
c.	Brouwer's fixed point theorem	149
	Lecture 22	150
a.	Zeros of a vector field and their indices	150
b.	Calculation of index	153
c.	Tangent vectors, tangent spaces, and the tangent bundle	155
	Chapter 4. Riemannian Metrics and Geometry of Surfaces	159
	Lecture 23	159
a.	Definition of a Riemannian metric	159
b.	Partitions of unity	163
	Lecture 24	165
a.	Existence of partitions of unity	165
b.	Global properties from local and infinitesimal	169
c.	Lengths, angles, and areas	170
	Lecture 25	172
a.	Geometry via a Riemannian metric	172
b.	Differential equations	174
c.	Geodesics	175
	Lecture 26	178
a.	First glance at curvature	178
b.	The hyperbolic plane: two conformal models	181
c.	Geodesics and distances on H^2	186
	Lecture 27	189
a.	Detailed discussion of geodesics and isometries in the upper half-plane model	189

b. The cross-ratio	193
c. Circles in the hyperbolic plane	196
Lecture 28	198
a. Three approaches to hyperbolic geometry	198
b. Characterisation of isometries	199
Lecture 29	204
a. Classification of isometries	204
b. Geometric interpretation of isometries	213
Lecture 30	217
a. Area of triangles in different geometries	217
b. Area and angular defect in hyperbolic geometry	218
Lecture 31	224
a. Hyperbolic metrics on surfaces of higher genus	224
b. Curvature, area, and Euler characteristic	228
Lecture 32	231
a. Geodesic polar coordinates	231
b. Curvature as an error term in the circle length formula	233
c. The Gauss-Bonnet Theorem	235
d. Comparison with traditional approach	240
Chapter 5. Topology and Smooth Structure Revisited	243
Lecture 33	243
a. Back to degree and index	243
b. The Fundamental Theorem of Algebra	246
Lecture 34	249
a. Jordan Curve Theorem	249
b. Another interpretation of genus	253
Lecture 35	255
a. A remark on tubular neighbourhoods	255
b. Proving the Jordan Curve Theorem	256
c. Poincaré-Hopf Index Formula	259
Lecture 36	260
a. Proving the Poincaré-Hopf Index Formula	260
b. Gradients and index formula for general functions	265
c. Fixed points and index formula for maps	267
d. The ubiquitous Euler characteristic	269

Suggested Reading	271
Hints	275
Index	283