

Curves

Definition

$$\gamma : [a, b] \rightarrow \mathbb{R}^n \text{ continuous path} \\ \gamma([a, b]) \text{ curve}$$

A path is **closed** if $\gamma(a) = \gamma(b)$.

A path is **simple** if γ is injective.

A **Jordan path** is a simple closed curve (in German only simple is required for a path to be a Jordan path).

A path is **smooth** if $\gamma \in C^1([a, b])$ and $\gamma' \neq \mathbf{0}$.

A path is **piecewise smooth** if it can be separated into a finite number of smooth paths.

A curve has any of the properties mentioned above if there exists a path for which the property holds true. We then call the path a **parametrization** of the curve.

The parametrization of a curve is (in general) not unique.

Special curves

Some curves can be expressed as

$$f_1(x_1, \dots, x_n), \dots, f_{n-1}(x_1, \dots, x_n) = 0 \text{ implicite form}$$

A curve is called algebraic iff it is expressible in implicite form where f are polynomial functions.

Jordan-curve theorem

The complement of the image of a simple-closed curve in \mathbb{R}^2 consists of two distinct components. The interior is bounded while the exterior is unbounded. The curve is the boundary of both components.

Parametrization of well-known curves

Line segment from $a \in \mathbb{R}^n$ to $b \in \mathbb{R}^n$ (simple)
 $\gamma(t) = a + t(b - a) = (1 - t)a + tb \quad 0 \leq t \leq 1$

Circle with radius r in \mathbb{R}^2 and $x^2 + y^2 = r^2$ (simple and closed)

$$\gamma(t) = \begin{bmatrix} r \cdot \cos t \\ r \cdot \sin t \end{bmatrix} \quad 0 \leq t \leq 2\pi$$

Ellipse $\frac{x^2}{a^2} + \frac{y^2}{b^2} = 1, \quad a > b > 0$ (simple and closed)

$$\gamma(t) = \begin{bmatrix} a \cdot \cos t \\ b \cdot \sin t \end{bmatrix} \quad 0 \leq t \leq 2\pi$$

Hyperbola $\frac{x^2}{a^2} - \frac{y^2}{b^2} = 1$ (simple)

$$\gamma(t) = \begin{bmatrix} \pm a \cdot \cosh t \\ b \cdot \sinh t \end{bmatrix} \quad t \in \mathbb{R}$$

Parametrization of a curve in explicite form (simple, not closed)

$$\gamma(t) = \begin{bmatrix} f_1(t) \\ \vdots \\ f_{n-1}(t) \\ t \end{bmatrix}$$

Parametrization of a curve in (explicite) polar coordinates $r(\varphi)$

$$\gamma(t) = \begin{bmatrix} r(\varphi) \cdot \cos \varphi \\ r(\varphi) \cdot \sin \varphi \end{bmatrix}$$

Equivalence

$$\gamma : I \rightarrow \mathbb{R}^n \sim \beta : J \rightarrow \mathbb{R}^n \iff \\ \exists h : J \rightarrow I, \text{ bijective, continuous, increasing} \\ \forall t \in J : \beta(t) = \gamma(h(t))$$

Curves which are equivalent are said to have the same orientation.

If h is decreasing the orientation is reversed.

For two simple curves γ and β the bijection h is unique; thus, up to equivalence and orientation the parametrization of a simple curve is unique.

Arc length

A curve is called rectifiable if its arc length L is finite.

If $\gamma : [a, b] \rightarrow \mathbb{R}^n$ is differentiable then
 $s(t) = \int_a^t \|\gamma'(\tau)\|_2 d\tau$
 $L(\gamma) = \int_a^b \|\gamma'(t)\|_2 dt$

Every continuous differentiable curve is rectifiable.

Every piecewise continuous differentiable curve is rectifiable.

Arc length (special cases)

$$f \in C^1([a, b]) \\ \implies L = \int_a^b \sqrt{1 + f'(x)^2} dx$$

$$r(\varphi) \in C^1([\alpha, \beta]) \\ r \text{ is piecewise simple} \\ L = \int_\alpha^\beta \sqrt{r^2(\varphi) + (r'(\varphi))^2} d\varphi$$

Every function in polar coordinates with $\beta - \alpha < 2\pi$ is a simple curve.

Natural parameter

A rectifiable piecewise simple curve has a parametrization with the arc-length as its parameter ($\gamma(s)$). Then $\|\gamma'(s)\|_2 = 1$. We call this parametrization **natural**.

There exist exactly two different natural parametrizations (up to the choice of a starting point of a closed curve); these two have a different orientation.

Polar coordinate system

$$\mathbf{F}(r, \varphi) = \begin{bmatrix} r \cdot \cos \varphi \\ r \cdot \sin \varphi \end{bmatrix}$$

$$\mathbf{F}^{-1}(x, y) = \begin{bmatrix} \sqrt{x^2 + y^2} \\ \arctan \frac{y}{x} \end{bmatrix}$$

$$y \in \mathbb{R}, x \in (0, \infty), r \in (0, \infty), \varphi \in \left(-\frac{\pi}{2}, \frac{\pi}{2}\right)$$

Velocity/Acceleration

$$\gamma'(t) \text{ velocity} \\ \gamma''(t) \text{ acceleration} \\ \|\gamma'(s)\|_2 = 1 \text{ arc length } s$$

Curvature in \mathbb{R}^2

$$\mathbf{T}(t) = \frac{\gamma'(t)}{\|\gamma'(t)\|_2} = \gamma'(s) \text{ unit tangent-vector} \\ \mathbf{N}(t) = \frac{(\gamma'(t))^\perp}{\|\gamma'(t)\|_2} \text{ unit normal-vector}$$

$$\kappa(s) = \|\gamma''(s)\| \text{ curvature} \\ r(s) = 1/\kappa(s) \text{ radius of curvature} \\ \kappa = \frac{y''}{(1+(y')^2)^{3/2}} \text{ } y(x) \\ \kappa = \frac{x'y'' - y'x''}{((x')^2 + (y')^2)^{3/2}} \text{ } x(t), y(t)$$

Tangent

$$\mathbf{x}(t) = \gamma(t_0) + t \cdot \gamma'(t_0), \quad t \in \mathbb{R}$$

Torsion in \mathbb{R}^3

$$\mathbf{T}(t) = \frac{\gamma'}{\|\gamma'\|_2} \\ \mathbf{N}(t) = \frac{\mathbf{T}'}{\|\mathbf{T}'\|_2} \\ \mathbf{B}(t) = \mathbf{T} \times \mathbf{N} \text{ binormal-unit-vector} \\ \langle \mathbf{T}, \mathbf{N} \rangle = 0$$

$$\kappa(t) = \frac{\|\mathbf{T}'(t)\|_2}{\|\gamma'\|_2} = \mathbf{T}'(s) \\ \kappa(t) = \frac{\|\gamma' \times \gamma''\|_2}{\|\gamma'\|_2^3} \\ \tau(t) = \frac{\det[\gamma', \gamma'', \gamma''']}{\|\gamma' \times \gamma''\|_2^2} \text{ torsion}$$

Frenet-Serret formulas in \mathbb{R}^3

$$\mathbf{T}'(s) = \kappa \mathbf{N} \\ \mathbf{N}'(s) = -\kappa \mathbf{T} + \tau \mathbf{B} \\ \mathbf{B}'(s) = -\tau \mathbf{N}$$

Osculating plane

$$\mathbf{E}(\lambda, \mu) = \gamma(t_0) + \lambda \mathbf{T}(t_0) + \mu \mathbf{N}(t_0)$$

A bijective, partially continuous differentiable function $\mathbf{F} : U \rightarrow V$ ($u, v \in \mathbb{R}^n$ and open) is called **diffeomorphism** iff \mathbf{F}^{-1} is partially continuous differentiable. We say $\mathbf{x} = \mathbf{F}(\mathbf{u})$ defines **local coordinates** $\mathbf{u} = (u_1, \dots, u_n)$.

Spherical coordinate system

$$\mathbf{F}(r, \varphi, \theta) = \begin{bmatrix} r \cdot \sin \theta \cos \varphi \\ r \cdot \sin \theta \sin \varphi \\ r \cdot \cos \theta \end{bmatrix}, \quad \mathbf{F}^{-1}(x, y, z) = \begin{bmatrix} \sqrt{x^2 + y^2 + z^2} \\ \arctan \left(\frac{\sqrt{x^2 + y^2}}{z} \right) \\ \arctan \frac{y}{x} \end{bmatrix}$$

$$y, z \in \mathbb{R}, x \in (0, \infty), r \in (0, \infty), \varphi \in \left(-\frac{\pi}{2}, \frac{\pi}{2}\right), \theta \in \left(-\frac{\pi}{2}, \frac{\pi}{2}\right)$$

Cylindrical coordinate system

$$\mathbf{F}(r, \varphi, \theta) = \begin{bmatrix} r \cdot \cos \varphi \\ r \cdot \sin \varphi \\ z \end{bmatrix}, \quad \mathbf{F}^{-1}(x, y, z) = \begin{bmatrix} \sqrt{x^2 + y^2} \\ \arctan \frac{y}{x} \\ z \end{bmatrix}$$

$$y, z \in \mathbb{R}, x \in (0, \infty), r \in (0, \infty), \varphi \in \left(-\frac{\pi}{2}, \frac{\pi}{2}\right)$$