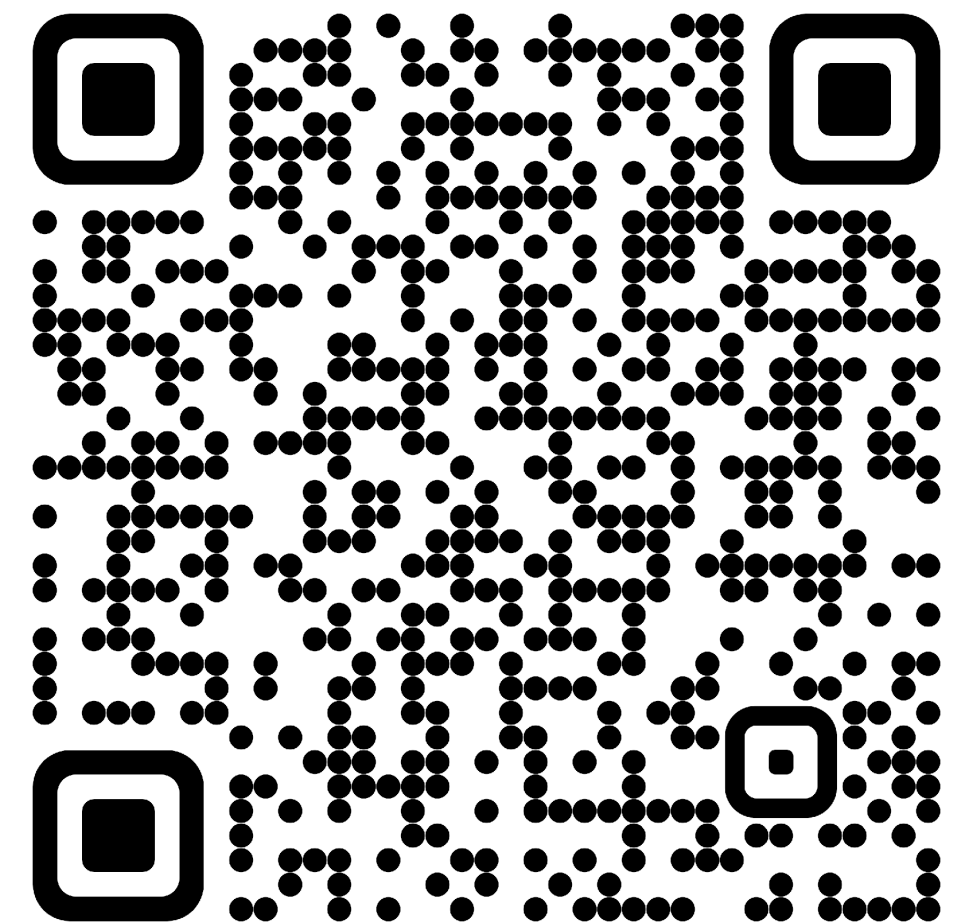


Non-lorentzian spacetimes

Homogeneous spacetimes with low coisotropy



Exactly 7 years ago
in IFWGP XXVIII!

ICMAT



Homogeneous kinematical spacetimes

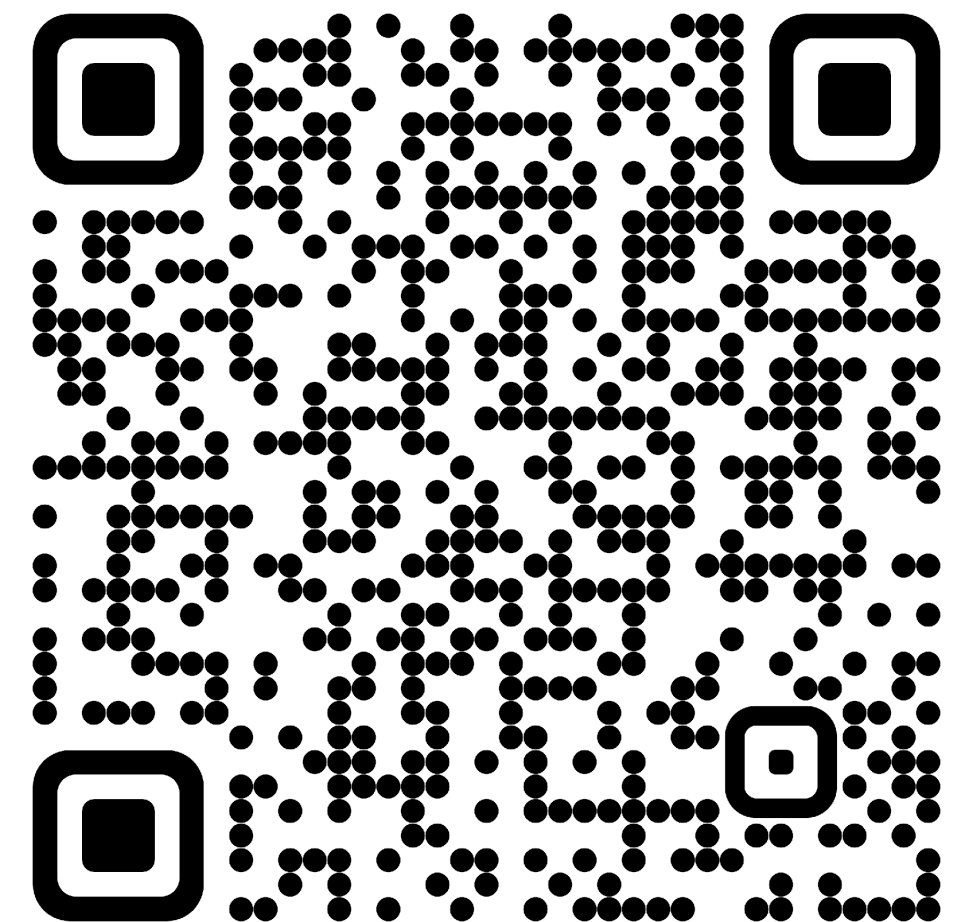
José Miguel Figueroa-O'Farrill



XXVIII International Fall Workshop on Geometry and Physics
ICMAT, Madrid, 2 September 2019

Non-lorentzian spacetimes

Homogeneous spacetimes with low coisotropy



Based on the following papers

reviews KLAAs spatially isotropic Lifshitz/conformal/coisotropy-one

arXiv:1711.05676, arXiv:1711.06111, arXiv:1711.07363, arXiv:1809.03603, arXiv:2204.13609

arXiv:1802.04048 (with **Tomasz Andrzejewski**)

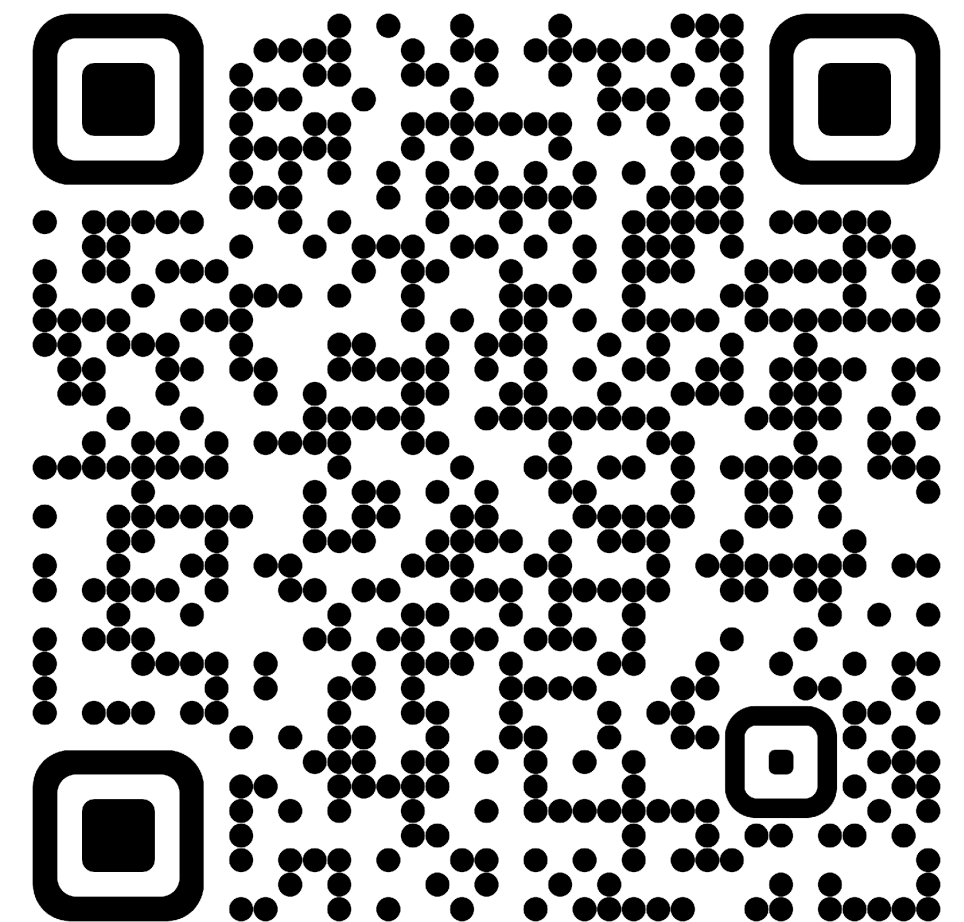
arXiv:1809.01224 (with **Stefan Prohazka**)

arXiv:1905.00034, arXiv:2206.11806 (with **Ross Grassie** and **Stefan Prohazka**)

arXiv:2206.12177 (with **Eric Bergshoeff** and **Joaquim Gomis**)

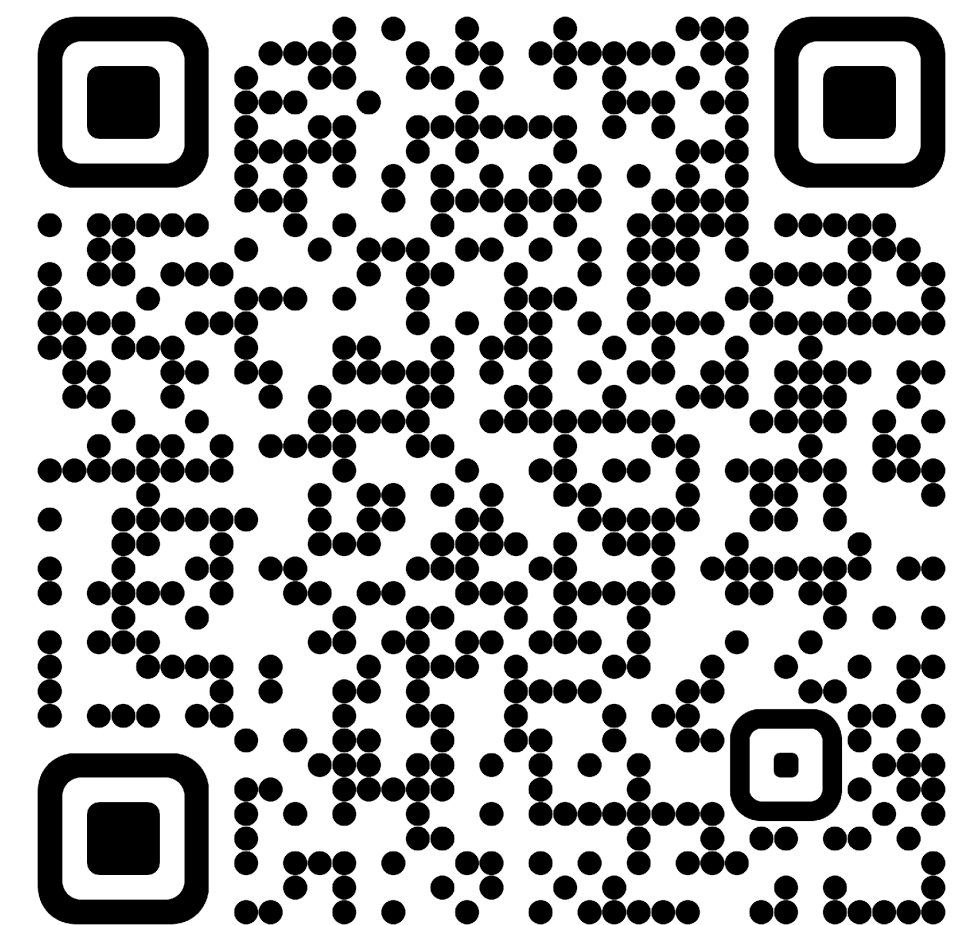
work in progress (with **Jarah Fluxman**, **Ross Grassie** and **Stefan Prohazka**)

work in progress (with **Juanma Lorenzo-Naveiro**)



Plan

- The original spacetime
- Kinematical Lie algebras
- Spatially isotropic homogeneous spacetimes
- Breaking isotropy:
 - Lifshitz Lie algebras
 - Classification of $(3,2)$ -KLAs
- Outlook



The original spacetime

The birth of “spacetime”

“Von Stund’ an sollen Raum für sich und
Zeit für sich völlig zu Schatten
herabsinken und noch eine Art Union der
beiden soll Selbständigkeit bewahren.”

Hermann Minkowski

The birth of “spacetime”

“Henceforth space by itself, and time by itself, are doomed to fade away into mere shadows, and only a kind of union of the two will preserve an independent reality.”

Hermann Minkowski

Minkowski spacetime

Minkowski spacetime

- an affine space $\mathbb{A}^4$

Minkowski spacetime

- an affine space $\mathbb{A}^4$
- a global chart (t, x, y, z)

Minkowski spacetime

- an affine space $\mathbb{A}^4$
- a global chart (t, x, y, z)
- a lorentzian metric $\eta = -c^2 dt^2 + dx^2 + dy^2 + dz^2$

Minkowski spacetime

- an affine space $\mathbb{A}^4$
- a global chart (t, x, y, z)
- a lorentzian metric $\eta = -c^2 dt^2 + dx^2 + dy^2 + dz^2$
- c the **speed of light**

Symmetries

Symmetries

- Automorphism (i.e., isometry) group is the Poincaré group G

Symmetries

- Automorphism (i.e., isometry) group is the Poincaré group G
- $G \subset \text{Aff}(4, \mathbb{R}) \subset \text{GL}(5, \mathbb{R})$

Symmetries

- Automorphism (i.e., isometry) group is the Poincaré group G
- $G \subset \text{Aff}(4, \mathbb{R}) \subset \text{GL}(5, \mathbb{R})$
- Lie algebra $\mathfrak{g} = \langle L_{\mu\nu}, P_\mu \rangle$ with $\mu, \nu = 0, 1, 2, 3$

Symmetries

- Automorphism (i.e., isometry) group is the Poincaré group G
- $G \subset \text{Aff}(4, \mathbb{R}) \subset \text{GL}(5, \mathbb{R})$
- Lie algebra $\mathfrak{g} = \langle L_{\mu\nu}, P_\mu \rangle$ with $\mu, \nu = 0, 1, 2, 3$

$$[L_{\mu\nu}, L_{\rho\sigma}] = \eta_{\nu\rho} L_{\mu\sigma} - \eta_{\mu\rho} L_{\nu\sigma} - \eta_{\nu\sigma} L_{\mu\rho} + \eta_{\mu\sigma} L_{\nu\rho}$$

$$[L_{\mu\nu}, P_\rho] = \eta_{\nu\rho} P_\mu - \eta_{\mu\rho} P_\nu$$

$$[P_\mu, P_\nu] = 0$$

Symmetries

- Automorphism (i.e., isometry) group is the Poincaré group G
- $G \subset \text{Aff}(4, \mathbb{R}) \subset \text{GL}(5, \mathbb{R})$
- Lie algebra $\mathfrak{g} = \langle L_{ab}, B_a := L_{0a}, P_a, H := P_0 \rangle$ with $a, b = 1, 2, 3$

$$[L_{ab}, H] = 0$$

$$[L_{ab}, B_c] = \delta_{bc} B_a - \delta_{ac} B_b$$

$$[L_{ab}, P_c] = \delta_{bc} P_a - \delta_{ac} P_b$$

$$[L_{ab}, L_{cd}] = \delta_{bc} L_{ad} - \delta_{ac} L_{bd} - \delta_{bd} L_{ac} + \delta_{ad} L_{bc}$$

$$[B_a, B_b] = c^2 L_{ab}$$

$$[B_a, P_b] = \delta_{ab} H$$

$$[B_a, H] = c^2 P_a$$

$$[P_a, P_b] = 0$$

$$[H, P_a] = 0$$

Kinematical Lie algebras

Kinematical Lie algebra

(with d -dimensional spatial isotropy)

Kinematical Lie algebra

(with d -dimensional spatial isotropy)

- The Poincaré Lie algebra (as a Lie subalgebra of vector fields on Minkowski spacetime) consists of rotations (L_{ab}), boosts (B_a), spatial (P_a) and temporal (H) translations

Kinematical Lie algebra

(with d -dimensional spatial isotropy)

- The Poincaré Lie algebra (as a Lie subalgebra of vector fields on Minkowski spacetime) consists of rotations (L_{ab}), boosts (B_a), spatial (P_a) and temporal (H) translations
- Relative to the rotation subalgebra, B_a and P_a transform as the vector (fundamental) representation and H is a scalar

Kinematical Lie algebra

(with d -dimensional spatial isotropy)

- The Poincaré Lie algebra (as a Lie subalgebra of vector fields on Minkowski spacetime) consists of rotations (L_{ab}), boosts (B_a), spatial (P_a) and temporal (H) translations
- Relative to the rotation subalgebra, B_a and P_a transform as the vector (fundamental) representation and H is a scalar
- A **kinematical Lie algebra** $\mathfrak{g}$ is a real Lie algebra with generators L_{ab}, B_a, P_a, H such that $L_{ab} = -L_{ba}$ generates a subalgebra $\mathfrak{r} \cong \mathfrak{so}(d)$, relative to which $\mathfrak{g} = \mathfrak{ad} \oplus 2V \oplus \mathbb{R}$, where $\mathfrak{ad} \cong \wedge^2 V$ and $V \cong \mathbb{R}^d$

Kinematical Lie algera

(with d -dimensional spatial isotropy)

- The Poincaré Lie algebra (as a Lie subalgebra of vector fields on Minkowski spacetime) consists of rotations (L_{ab}), boosts (B_a), spatial (P_a) and temporal (H) translations
- Relative to the rotation subalgebra, B_a and P_a transform as the vector (fundamental) representation and H is a scalar
- A **kinematical Lie algebra** $\mathfrak{g}$ is a real Lie algebra with generators L_{ab}, B_a, P_a, H such that $L_{ab} = -L_{ba}$ generates a subalgebra $\mathfrak{r} \cong \mathfrak{so}(d)$, relative to which $\mathfrak{g} = \mathfrak{ad} \oplus 2V \oplus \mathbb{R}$, where $\mathfrak{ad} \cong \wedge^2 V$ and $V \cong \mathbb{R}^d$
- **Morand** (2023) introduced a general class of Lie algebras — (s, v) -**KLAs** — with a similar definition except that $\mathfrak{g} = \mathfrak{ad} \oplus vV \oplus s\mathbb{R}$. So kinematical Lie algebras are (1,2)-KLAs

Classification of $(1,2)$ –KLAs

Classification of (1,2)–KLAs

- **Bacry + Lévy-Leblond** (1968): $d = 3$ and with **parity** ($B_a \mapsto -B_a$, $P_a \mapsto -P_a$) and **time-reversal** ($B_a \mapsto -B_a$, $H \mapsto -H$) automorphisms

Classification of (1,2)–KLAs

- **Bacry + Lévy-Leblond** (1968): $d = 3$ and with **parity** ($B_a \mapsto -B_a, P_a \mapsto -P_a$) and **time-reversal** ($B_a \mapsto -B_a, H \mapsto -H$) automorphisms
- **Bacry + Nuyts** (1986): $d = 3$

Classification of (1,2)–KLAs

- **Bacry + Lévy-Leblond** (1968): $d = 3$ and with **parity** ($B_a \mapsto -B_a, P_a \mapsto -P_a$) and **time-reversal** ($B_a \mapsto -B_a, H \mapsto -H$) automorphisms
- **Bacry + Nuyts** (1986): $d = 3$
- **JMF** (2018): $d > 3$

Classification of (1,2)–KLAs

- **Bacry + Lévy-Leblond** (1968): $d = 3$ and with **parity** ($B_a \mapsto -B_a, P_a \mapsto -P_a$) and **time-reversal** ($B_a \mapsto -B_a, H \mapsto -H$) automorphisms
- **Bacry + Nuyts** (1986): $d = 3$
- **JMF** (2018): $d > 3$
- **Andrzejewski + JMF** (2018): $d = 2$

Kinematical Lie algebras (generic d)

Name	Additional nonzero Lie brackets					Comments
$\mathfrak{s}$						
$\mathfrak{g}$	$[\mathbf{H}, \mathbf{B}] = -\mathbf{P}$					
$\mathfrak{n}^0$	$[\mathbf{H}, \mathbf{B}] = \mathbf{B} + \mathbf{P} \quad [\mathbf{H}, \mathbf{P}] = \mathbf{P}$					
$\mathfrak{n}_\gamma^+$	$[\mathbf{H}, \mathbf{B}] = \gamma \mathbf{B} \quad [\mathbf{H}, \mathbf{P}] = \mathbf{P}$					$\gamma \in [-1, 1]$
$\mathfrak{n}_\chi^-$	$[\mathbf{H}, \mathbf{B}] = \chi \mathbf{B} + \mathbf{P} \quad [\mathbf{H}, \mathbf{P}] = \chi \mathbf{P} - \mathbf{B}$					$\chi \geq 0$
$\mathfrak{c}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$					
$\mathfrak{iso}(d, 1)$ $\mathfrak{iso}(d+1)$	$[\mathbf{H}, \mathbf{B}] = -\varepsilon \mathbf{P}$		$[\mathbf{B}, \mathbf{B}] = \varepsilon \mathbf{L}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$		$\varepsilon = \pm 1$
$\mathfrak{so}(d+1, 1)$	$[\mathbf{H}, \mathbf{B}] = \mathbf{B}$	$[\mathbf{H}, \mathbf{P}] = -\mathbf{P}$		$[\mathbf{B}, \mathbf{P}] = \mathbf{H} + \mathbf{L}$		
$\mathfrak{so}(d, 2)$ $\mathfrak{so}(d+2)$	$[\mathbf{H}, \mathbf{B}] = -\varepsilon \mathbf{P}$	$[\mathbf{H}, \mathbf{P}] = \varepsilon \mathbf{B}$	$[\mathbf{B}, \mathbf{B}] = \varepsilon \mathbf{L}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$	$[\mathbf{P}, \mathbf{P}] = \varepsilon \mathbf{L}$	$\varepsilon = \pm 1$

(Not shown are the Lie brackets involving the rotations, which are common to all KLAs)

Spatially isotropic
homogeneous spacetimes

Infinitesimal description: Klein pairs

Infinitesimal description: Klein pairs

- Let $\mathfrak{g} = \langle L_{ab}, B_a, P_a, H \rangle$ be a kinematical Lie algebra

Infinitesimal description: Klein pairs

- Let $\mathfrak{g} = \langle L_{ab}, B_a, P_a, H \rangle$ be a kinematical Lie algebra
- Let $\mathfrak{h} = \langle L_{ab}, V_a \rangle$ be a Lie subalgebra, where $V_a = \alpha B_a + \beta P_a \neq 0$

Infinitesimal description: Klein pairs

- Let $\mathfrak{g} = \langle L_{ab}, B_a, P_a, H \rangle$ be a kinematical Lie algebra
- Let $\mathfrak{h} = \langle L_{ab}, V_a \rangle$ be a Lie subalgebra, where $V_a = \alpha B_a + \beta P_a \neq 0$
- A **Klein pair** $(\mathfrak{g}, \mathfrak{h})$ is **effective** if $\mathfrak{h}$ does not contain any (nonzero) ideal of $\mathfrak{g}$

Infinitesimal description: Klein pairs

- Let $\mathfrak{g} = \langle L_{ab}, B_a, P_a, H \rangle$ be a kinematical Lie algebra
- Let $\mathfrak{h} = \langle L_{ab}, V_a \rangle$ be a Lie subalgebra, where $V_a = \alpha B_a + \beta P_a \neq 0$
- A **Klein pair** $(\mathfrak{g}, \mathfrak{h})$ is **effective** if $\mathfrak{h}$ does not contain any (nonzero) ideal of $\mathfrak{g}$
- It is **geometrically realisable** if there exists a Lie group G with Lie algebra $\mathfrak{g}$ such that the connected Lie subgroup corresponding to $\mathfrak{h}$ is closed

Infinitesimal description: Klein pairs

- Let $\mathfrak{g} = \langle L_{ab}, B_a, P_a, H \rangle$ be a kinematical Lie algebra
- Let $\mathfrak{h} = \langle L_{ab}, V_a \rangle$ be a Lie subalgebra, where $V_a = \alpha B_a + \beta P_a \neq 0$
- A **Klein pair** $(\mathfrak{g}, \mathfrak{h})$ is **effective** if $\mathfrak{h}$ does not contain any (nonzero) ideal of $\mathfrak{g}$
- It is **geometrically realisable** if there exists a Lie group G with Lie algebra $\mathfrak{g}$ such that the connected Lie subgroup corresponding to $\mathfrak{h}$ is closed
- Two Klein pairs $(\mathfrak{g}, \mathfrak{h})$ and $(\mathfrak{g}', \mathfrak{h}')$ are **isomorphic** if there is a Lie algebra isomorphism $\varphi: \mathfrak{g} \rightarrow \mathfrak{g}'$ with $\varphi(\mathfrak{h}) = \mathfrak{h}'$

Fundamental result

Fundamental result

- Isomorphism classes of **geometrically realisable, effective Klein pairs** $(\mathfrak{g}, \mathfrak{h})$ are in bijection with isomorphism classes of **simply-connected spatially isotropic homogeneous spacetimes**

Fundamental result

- Isomorphism classes of **geometrically realisable, effective Klein pairs** $(\mathfrak{g}, \mathfrak{h})$ are in bijection with isomorphism classes of **simply-connected spatially isotropic homogeneous spacetimes**
- **JMF+Prohazka** (2019): classification of geometrically realisable, effective Klein pairs (for any d)

Fundamental result

- Isomorphism classes of **geometrically realisable, effective Klein pairs** $(\mathfrak{g}, \mathfrak{h})$ are in bijection with isomorphism classes of **simply-connected spatially isotropic homogeneous spacetimes**
- **JMF+Prohazka** (2019): classification of geometrically realisable, effective Klein pairs (for any d)
- They fall into a small number of geometries: **riemannian, lorentzian, galilean, carrollian, aristotelian,...**

Fundamental result

- Isomorphism classes of **geometrically realisable, effective Klein pairs** $(\mathfrak{g}, \mathfrak{h})$ are in bijection with isomorphism classes of **simply-connected spatially isotropic homogeneous spacetimes**
- **JMF+Prohazka** (2019): classification of geometrically realisable, effective Klein pairs (for any d)
- They fall into a small number of geometries: **riemannian, lorentzian, galilean, carrollian, aristotelian,...**
- Aristotelian Lie algebras have no boosts: they are the $(1,1)$ -KLAs.

Fundamental result

- Isomorphism classes of **geometrically realisable, effective Klein pairs** $(\mathfrak{g}, \mathfrak{h})$ are in bijection with isomorphism classes of **simply-connected spatially isotropic homogeneous spacetimes**
- **JMF+Prohazka** (2019): classification of geometrically realisable, effective Klein pairs (for any d)
- They fall into a small number of geometries: **riemannian, lorentzian, galilean, carrollian, aristotelian,...**
- Aristotelian Lie algebras have no boosts: they are the $(1,1)$ -KLAs.
- An aristotelian Klein pair $(\mathfrak{a}, \mathfrak{r})$ is automatically effective and geometrically realisable.

Non-lorentzian geometries

Non-lorentzian geometries

- Carrollian geometry is the geometry of null hypersurfaces in lorentzian manifolds

Non-lorentzian geometries

- Carrollian geometry is the geometry of null hypersurfaces in lorentzian manifolds
- A **carrollian manifold** is a triple (M, κ, h) where $\kappa \in \mathcal{X}(M)$ (nowhere zero) and $h \in \Gamma(\odot^2 T^*M)$ positive-semidefinite corank-one with $h(\kappa, -) = 0$

Non-lorentzian geometries

- Carrollian geometry is the geometry of null hypersurfaces in lorentzian manifolds
- A **carrollian manifold** is a triple (M, κ, h) where $\kappa \in \mathcal{X}(M)$ (nowhere zero) and $h \in \Gamma(\odot^2 T^*M)$ positive-semidefinite corank-one with $h(\kappa, -) = 0$
- It is the Cartan geometry modelled on Carroll spacetime

Non-lorentzian geometries

- Carrollian geometry is the geometry of null hypersurfaces in lorentzian manifolds
- A **carrollian manifold** is a triple (M, κ, h) where $\kappa \in \mathcal{X}(M)$ (nowhere zero) and $h \in \Gamma(\odot^2 T^*M)$ positive-semidefinite corank-one with $h(\kappa, -) = 0$
- It is the Cartan geometry modelled on Carroll spacetime
- Galilean geometry is the geometry of null Kaluza-Klein reductions of lorentzian manifolds

Non-lorentzian geometries

- Carrollian geometry is the geometry of null hypersurfaces in lorentzian manifolds
- A **carrollian manifold** is a triple (M, κ, h) where $\kappa \in \mathcal{X}(M)$ (nowhere zero) and $h \in \Gamma(\odot^2 T^*M)$ positive-semidefinite corank-one with $h(\kappa, -) = 0$
- It is the Cartan geometry modelled on Carroll spacetime
- Galilean geometry is the geometry of null Kaluza-Klein reductions of lorentzian manifolds
- A **galilean manifold** is a triple (M, τ, γ) where $\tau \in \Omega^1(M)$ (nowhere zero) and $\gamma \in \Gamma(\odot^2 TM)$ positive-semidefinite corank-one with $\gamma(\tau, -) = 0$

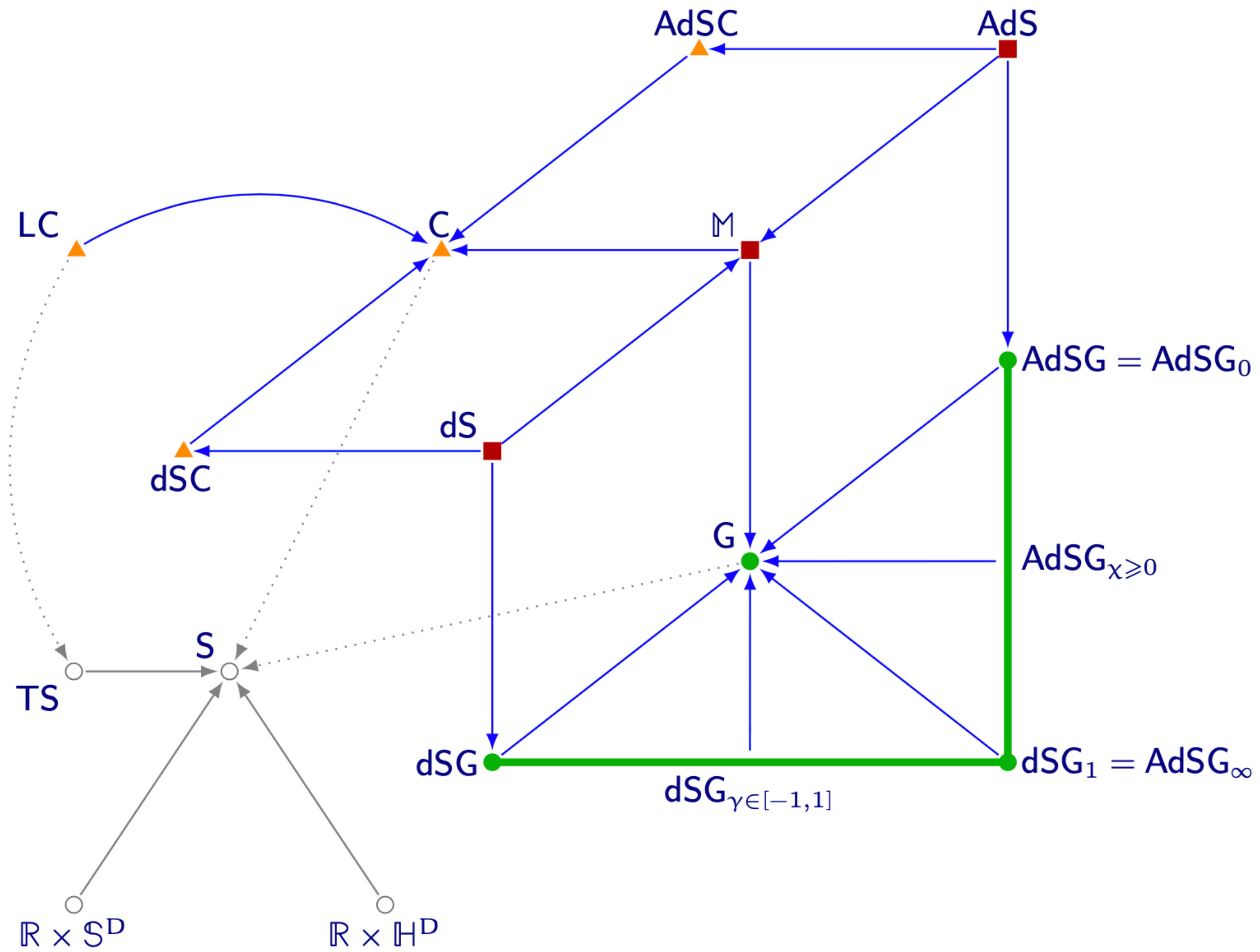
Non-lorentzian geometries

- Carrollian geometry is the geometry of null hypersurfaces in lorentzian manifolds
- A **carrollian manifold** is a triple (M, κ, h) where $\kappa \in \mathcal{X}(M)$ (nowhere zero) and $h \in \Gamma(\odot^2 T^*M)$ positive-semidefinite corank-one with $h(\kappa, -) = 0$
- It is the Cartan geometry modelled on Carroll spacetime
- Galilean geometry is the geometry of null Kaluza-Klein reductions of lorentzian manifolds
- A **galilean manifold** is a triple (M, τ, γ) where $\tau \in \Omega^1(M)$ (nowhere zero) and $\gamma \in \Gamma(\odot^2 TM)$ positive-semidefinite corank-one with $\gamma(\tau, -) = 0$
- It is the Cartan geometry modelled on Galilei spacetime

Spatially isotropic homogeneous spacetimes

$(d + 1)$ -dimensional and generic d and in a basis where $\mathfrak{h} = \langle L_{ab}, B_a \rangle$

Name	Klein pair	Nonzero Lie brackets in addition to $[\mathbf{L}, \mathbf{L}] = \mathbf{L}$, $[\mathbf{L}, \mathbf{B}] = \mathbf{B}$, $[\mathbf{L}, \mathbf{P}] = \mathbf{P}$			
Minkowski	$(\mathfrak{iso}(d, 1), \mathfrak{so}(d, 1))$	$[\mathbf{H}, \mathbf{B}] = -\mathbf{P}$		$[\mathbf{B}, \mathbf{B}] = \mathbf{L}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$
de Sitter	$(\mathfrak{so}(d + 1, 1), \mathfrak{so}(d, 1))$	$[\mathbf{H}, \mathbf{B}] = -\mathbf{P}$	$[\mathbf{H}, \mathbf{P}] = -\mathbf{B}$	$[\mathbf{B}, \mathbf{B}] = \mathbf{L}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$ $[\mathbf{P}, \mathbf{P}] = -\mathbf{L}$
anti de Sitter	$(\mathfrak{so}(d, 2), \mathfrak{so}(d, 1))$	$[\mathbf{H}, \mathbf{B}] = -\mathbf{P}$	$[\mathbf{H}, \mathbf{P}] = \mathbf{B}$	$[\mathbf{B}, \mathbf{B}] = \mathbf{L}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$ $[\mathbf{P}, \mathbf{P}] = \mathbf{L}$
euclidean	$(\mathfrak{iso}(d + 1), \mathfrak{so}(d + 1))$	$[\mathbf{H}, \mathbf{B}] = \mathbf{P}$		$[\mathbf{B}, \mathbf{B}] = -\mathbf{L}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$
sphere	$(\mathfrak{so}(d + 2), \mathfrak{so}(d + 1))$	$[\mathbf{H}, \mathbf{B}] = \mathbf{P}$	$[\mathbf{H}, \mathbf{P}] = -\mathbf{B}$	$[\mathbf{B}, \mathbf{B}] = -\mathbf{L}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$ $[\mathbf{P}, \mathbf{P}] = -\mathbf{L}$
hyperbolic	$(\mathfrak{so}(d + 1, 1), \mathfrak{so}(d + 1))$	$[\mathbf{H}, \mathbf{B}] = \mathbf{P}$	$[\mathbf{H}, \mathbf{P}] = \mathbf{B}$	$[\mathbf{B}, \mathbf{B}] = -\mathbf{L}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$ $[\mathbf{P}, \mathbf{P}] = \mathbf{L}$
Galilei	$(\mathfrak{g}, \mathfrak{iso}(d))$	$[\mathbf{H}, \mathbf{B}] = -\mathbf{P}$			
de Sitter–Galilei	$(\mathfrak{n}_{\gamma=-1}^+, \mathfrak{iso}(d))$	$[\mathbf{H}, \mathbf{B}] = -\mathbf{P}$	$[\mathbf{H}, \mathbf{P}] = -\mathbf{B}$		
torsional de Sitter–Galilei	$(\mathfrak{n}_{\gamma \in (-1, 1)}^+, \mathfrak{iso}(d))$	$[\mathbf{H}, \mathbf{B}] = -\mathbf{P}$	$[\mathbf{H}, \mathbf{P}] = \gamma \mathbf{B} + (1 + \gamma) \mathbf{P}$		
torsional de Sitter–Galilei	$(\mathfrak{n}^0, \mathfrak{iso}(d))$	$[\mathbf{H}, \mathbf{B}] = -\mathbf{P}$	$[\mathbf{H}, \mathbf{P}] = \mathbf{B} + 2\mathbf{P}$		
anti de Sitter–Galilei	$(\mathfrak{n}_{\chi=0}^-, \mathfrak{iso}(d))$	$[\mathbf{H}, \mathbf{B}] = -\mathbf{P}$	$[\mathbf{H}, \mathbf{P}] = \mathbf{B}$		
torsional anti de Sitter–Galilei	$(\mathfrak{n}_{\chi>0}^-, \mathfrak{iso}(d))$	$[\mathbf{H}, \mathbf{B}] = -\mathbf{P}$	$[\mathbf{H}, \mathbf{P}] = (1 + \chi^2) \mathbf{B} + 2\chi \mathbf{P}$		
Carroll	$(\mathfrak{c}, \mathfrak{iso}(d))$			$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$	
de Sitter–Carroll	$(\mathfrak{iso}(d + 1), \mathfrak{iso}(d))$		$[\mathbf{H}, \mathbf{P}] = -\mathbf{B}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$	$[\mathbf{P}, \mathbf{P}] = -\mathbf{L}$
anti de Sitter–Carroll	$(\mathfrak{iso}(d, 1), \mathfrak{iso}(d))$		$[\mathbf{H}, \mathbf{P}] = \mathbf{B}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H}$	$[\mathbf{P}, \mathbf{P}] = \mathbf{L}$
lightcone	$(\mathfrak{so}(d + 1, 1), \mathfrak{iso}(d))$	$[\mathbf{H}, \mathbf{B}] = \mathbf{B}$	$[\mathbf{H}, \mathbf{P}] = -\mathbf{P}$	$[\mathbf{B}, \mathbf{P}] = \mathbf{H} + \mathbf{L}$	



Breaking isotropy

Breaking isotropy of homogeneous spacetimes

Breaking isotropy of homogeneous spacetimes

- Let $\mathfrak{k} = \mathfrak{so}(V) \oplus 2V \oplus \mathbb{R}$ be a kinematical Lie algebra with spatial isotropy: $\mathbf{SO}(V)$ acts transitively on $\mathbb{P}V$ and consider an effective geometrically realisable Klein pair $(\mathfrak{k}, \mathfrak{h})$

Breaking isotropy of homogeneous spacetimes

- Let $\mathfrak{k} = \mathfrak{so}(V) \oplus 2V \oplus \mathbb{R}$ be a kinematical Lie algebra with spatial isotropy: $\mathbf{SO}(V)$ acts transitively on $\mathbb{P}V$ and consider an effective geometrically realisable Klein pair $(\mathfrak{k}, \mathfrak{h})$
- $\mathfrak{k}/\mathfrak{h} \cong V \oplus \mathbb{R}$

Breaking isotropy of homogeneous spacetimes

- Let $\mathfrak{k} = \mathfrak{so}(V) \oplus 2V \oplus \mathbb{R}$ be a kinematical Lie algebra with spatial isotropy: $\mathbf{SO}(V)$ acts transitively on $\mathbb{P}V$ and consider an effective geometrically realisable Klein pair $(\mathfrak{k}, \mathfrak{h})$
- $\mathfrak{k}/\mathfrak{h} \cong V \oplus \mathbb{R}$
- Fix a line $\ell = \mathbb{R}v_0 \in \mathbb{P}V$

Breaking isotropy of homogeneous spacetimes

- Let $\mathfrak{k} = \mathfrak{so}(V) \oplus 2V \oplus \mathbb{R}$ be a kinematical Lie algebra with spatial isotropy: $\mathbf{SO}(V)$ acts transitively on $\mathbb{P}V$ and consider an effective geometrically realisable Klein pair $(\mathfrak{k}, \mathfrak{h})$
- $\mathfrak{k}/\mathfrak{h} \cong V \oplus \mathbb{R}$
- Fix a line $\ell = \mathbb{R}v_0 \in \mathbb{P}V$
- Let $\mathfrak{g} \subset \mathfrak{k}$ be the centraliser of ℓ

Breaking isotropy of homogeneous spacetimes

- Let $\mathfrak{k} = \mathfrak{so}(V) \oplus 2V \oplus \mathbb{R}$ be a kinematical Lie algebra with spatial isotropy: $\mathbf{SO}(V)$ acts transitively on $\mathbb{P}V$ and consider an effective geometrically realisable Klein pair $(\mathfrak{k}, \mathfrak{h})$
- $\mathfrak{k}/\mathfrak{h} \cong V \oplus \mathbb{R}$
- Fix a line $\ell = \mathbb{R}v_0 \in \mathbb{P}V$
- Let $\mathfrak{g} \subset \mathfrak{k}$ be the centraliser of ℓ
- There are precisely three spatially isotropic Klein pairs $(\mathfrak{k}, \mathfrak{h})$ for which $(\mathfrak{g}, \mathfrak{h} \cap \mathfrak{g})$ is the Klein pair of a homogeneous spacetime: those of Minkowski, Galilei and Carroll spacetimes

Two kinds of Lie algebras

Two kinds of Lie algebras

- The surviving rotations are those which fix ℓ , namely $\mathfrak{so}(\ell^\perp)$

Two kinds of Lie algebras

- The surviving rotations are those which fix ℓ , namely $\mathfrak{so}(\ell^\perp)$
- For Minkowski and Carroll, $\mathfrak{g} = \mathfrak{so}(\ell^\perp) \oplus 2\ell^\perp \oplus 2\mathbb{R}$ (as a vector space)

Two kinds of Lie algebras

- The surviving rotations are those which fix ℓ , namely $\mathfrak{so}(\ell^\perp)$
- For Minkowski and Carroll, $\mathfrak{g} = \mathfrak{so}(\ell^\perp) \oplus 2\ell^\perp \oplus 2\mathbb{R}$ (as a vector space)
- For Galilei, $\mathfrak{g} = \mathfrak{so}(\ell^\perp) \oplus 2\ell^\perp \oplus 3\mathbb{R}$

Two kinds of Lie algebras

- The surviving rotations are those which fix ℓ , namely $\mathfrak{so}(\ell^\perp)$
- For Minkowski and Carroll, $\mathfrak{g} = \mathfrak{so}(\ell^\perp) \oplus 2\ell^\perp \oplus 2\mathbb{R}$ (as a vector space)
- For Galilei, $\mathfrak{g} = \mathfrak{so}(\ell^\perp) \oplus 2\ell^\perp \oplus 3\mathbb{R}$
- So we get either a $(2,2)$ –KLA or a $(3,2)$ –KLA

Two kinds of Lie algebras

- The surviving rotations are those which fix ℓ , namely $\mathfrak{so}(\ell^\perp)$
- For Minkowski and Carroll, $\mathfrak{g} = \mathfrak{so}(\ell^\perp) \oplus 2\ell^\perp \oplus 2\mathbb{R}$ (as a vector space)
- For Galilei, $\mathfrak{g} = \mathfrak{so}(\ell^\perp) \oplus 2\ell^\perp \oplus 3\mathbb{R}$
- So we get either a $(2,2)$ –KLA or a $(3,2)$ –KLA
- This suggests classifying $(2,2)$ – and $(3,2)$ –KLAs

Lifshitz Lie algebras

Lifshitz Lie algebras

(Anisotropy under scaling)

Lifshitz Lie algebras

(Anisotropy under scaling)

- **Lifshitz Lie algebras** are precisely the $(2,1)$ –KLAs: the idea is to replace $\mathfrak{so}(V)$ with $\mathfrak{co}(V) = \mathfrak{so}(V) \oplus \mathbb{R}D$ by adding a **dilatation** generator to an aristotelian Lie algebra

Lifshitz Lie algebras

(Anisotropy under scaling)

- **Lifshitz Lie algebras** are precisely the $(2,1)$ –KLAs: the idea is to replace $\mathfrak{so}(V)$ with $\mathfrak{co}(V) = \mathfrak{so}(V) \oplus \mathbb{R}D$ by adding a **dilatation** generator to an aristotelian Lie algebra
- The dilatation generator can have different weights on space and on time: **anisotropy**

Lifshitz Lie algebras

(Anisotropy under scaling)

- **Lifshitz Lie algebras** are precisely the $(2,1)$ –KLAs: the idea is to replace $\mathfrak{so}(V)$ with $\mathfrak{co}(V) = \mathfrak{so}(V) \oplus \mathbb{R}D$ by adding a **dilatation** generator to an aristotelian Lie algebra
- The dilatation generator can have different weights on space and on time: **anisotropy**
- Every Lifshitz Lie algebra $\mathfrak{l}$ fits into a short exact sequence

$$0 \longrightarrow \mathfrak{a} \longrightarrow \mathfrak{l} \longrightarrow \mathbb{R} \longrightarrow 0$$

Lifshitz Lie algebras

(Anisotropy under scaling)

- **Lifshitz Lie algebras** are precisely the $(2,1)$ –KLAs: the idea is to replace $\mathfrak{so}(V)$ with $\mathfrak{co}(V) = \mathfrak{so}(V) \oplus \mathbb{R}D$ by adding a **dilatation** generator to an aristotelian Lie algebra
- The dilatation generator can have different weights on space and on time: **anisotropy**
- Every Lifshitz Lie algebra $\mathfrak{l}$ fits into a short exact sequence

$$0 \longrightarrow \mathfrak{a} \longrightarrow \mathfrak{l} \longrightarrow \mathbb{R} \longrightarrow 0$$

where $\mathfrak{a}$ is an aristotelian Lie algebra and $1 \in \mathbb{R}$ acts on $\mathfrak{a}$ as a **grading element**

Boost-extended Lifshitz Lie algebras

(Adding boosts of Lifshitz Lie algebras)

Boost-extended Lifshitz Lie algebras

(Adding boosts of Lifshitz Lie algebras)

- Adding boosts to a Lifshitz Lie algebras, results in a $(2,2)$ –KLA.

Boost-extended Lifshitz Lie algebras

(Adding boosts of Lifshitz Lie algebras)

- Adding boosts to a Lifshitz Lie algebras, results in a $(2,2)$ –KLA.
- Let $\mathfrak{b}$ be a $(2,2)$ –KLA. Then it fits in a short exact sequence

$$0 \longrightarrow \mathfrak{k} \longrightarrow \mathfrak{b} \longrightarrow \mathbb{R} \longrightarrow 0$$

Boost-extended Lifshitz Lie algebras

(Adding boosts of Lifshitz Lie algebras)

- Adding boosts to a Lifshitz Lie algebras, results in a $(2,2)$ –KLA.
- Let $\mathfrak{b}$ be a $(2,2)$ –KLA. Then it fits in a short exact sequence

$$0 \longrightarrow \mathfrak{k} \longrightarrow \mathfrak{b} \longrightarrow \mathbb{R} \longrightarrow 0$$

where $\mathfrak{k}$ is a kinematical Lie algebra (i.e., a $(1,2)$ –KLA) and $1 \in \mathbb{R}$ acts on $\mathfrak{k}$ as a derivation

Classification of $(3,2)$ –KLAs

Structure

Structure

- As a vector space, a $(3,2)$ -KLA $\mathfrak{g} = \mathfrak{so}(V) \oplus 2V \oplus 3\mathbb{R}$ and let $\dim V = n$

Structure

- As a vector space, a $(3,2)$ -KLA $\mathfrak{g} = \mathfrak{so}(V) \oplus 2V \oplus 3\mathbb{R}$ and let $\dim V = n$
- For $n > 3$ the adjoint, vector and scalar representations of $\mathfrak{so}(n)$ are mutually non-isomorphic

Structure

- As a vector space, a $(3,2)$ -KLA $\mathfrak{g} = \mathfrak{so}(V) \oplus 2V \oplus 3\mathbb{R}$ and let $\dim V = n$
- For $n > 3$ the adjoint, vector and scalar representations of $\mathfrak{so}(n)$ are mutually non-isomorphic
- For $n = 3$, the adjoint and the vector representations are isomorphic

Structure

- As a vector space, a $(3,2)$ -KLA $\mathfrak{g} = \mathfrak{so}(V) \oplus 2V \oplus 3\mathbb{R}$ and let $\dim V = n$
- For $n > 3$ the adjoint, vector and scalar representations of $\mathfrak{so}(n)$ are mutually non-isomorphic
- For $n = 3$, the adjoint and the vector representations are isomorphic
- For $n = 2$, the adjoint and the scalar representations are isomorphic

Structure

- As a vector space, a $(3,2)$ -KLA $\mathfrak{g} = \mathfrak{so}(V) \oplus 2V \oplus 3\mathbb{R}$ and let $\dim V = n$
- For $n > 3$ the adjoint, vector and scalar representations of $\mathfrak{so}(n)$ are mutually non-isomorphic
- For $n = 3$, the adjoint and the vector representations are isomorphic
- For $n = 2$, the adjoint and the scalar representations are isomorphic
- For $n = 1$, the adjoint is trivial and the scalar and vector are isomorphic: any 5-dimensional real Lie algebra is a $(3,2)$ -KLA

Structure

(cont'd)

Structure

(cont'd)

- 5-dimensional real Lie algebras have been classified and we will ignore them in this talk

Structure

(cont'd)

- 5-dimensional real Lie algebras have been classified and we will ignore them in this talk
- $(3,2)$ –KLAs with $n = 2$ is the subject of ongoing work, so we will not discuss them either

Structure

(cont'd)

- 5-dimensional real Lie algebras have been classified and we will ignore them in this talk
- $(3,2)$ -KLAs with $n = 2$ is the subject of ongoing work, so we will not discuss them either
- We will concentrate in $n \geq 3$ which we will break up into the *generic* $n > 3$ case and the *special* $n = 3$ case

Structure

(cont'd)

- 5-dimensional real Lie algebras have been classified and we will ignore them in this talk
- $(3,2)$ -KLAs with $n = 2$ is the subject of ongoing work, so we will not discuss them either
- We will concentrate in $n \geq 3$ which we will break up into the *generic* $n > 3$ case and the *special* $n = 3$ case
- Recall that these are transitive Lie algebras for coisotropy-one homogeneous spacetimes of dimension $n + 2$

Some notation

Some notation

- We will let V denote the vector representation of $\mathfrak{so}(V)$

Some notation

- We will let V denote the vector representation of $\mathfrak{so}(V)$
- We let $\langle -, - \rangle$ denote the **inner product** on V with **musical isomorphism** $\flat: V \rightarrow V^*$

Some notation

- We will let V denote the vector representation of $\mathfrak{so}(V)$
- We let $\langle -, - \rangle$ denote the **inner product** on V with **musical isomorphism** $b: V \rightarrow V^*$
- There is an $\mathfrak{so}(V)$ -equivariant isomorphism $\wedge^2 V \rightarrow \mathfrak{so}(V)$ sending $v_1 \wedge v_2 \mapsto v_1 \wedge v_2$, where

Some notation

- We will let V denote the vector representation of $\mathfrak{so}(V)$
- We let $\langle -, - \rangle$ denote the **inner product** on V with **musical isomorphism** $\flat: V \rightarrow V^*$
- There is an $\mathfrak{so}(V)$ -equivariant isomorphism $\wedge^2 V \rightarrow \mathfrak{so}(V)$ sending $v_1 \wedge v_2 \mapsto v_1 \lrcorner v_2$, where

$$(v_1 \lrcorner v_2)(v) = -i_v \flat(v_1 \wedge v_2) = \langle v, v_2 \rangle v_1 - \langle v, v_1 \rangle v_2$$

Structure theorem for $(3,2)$ –KLAs with $n > 3$

Structure theorem for $(3,2)$ –KLAs with $n > 3$

As a vector space, a $(3,2)$ –KLA $\mathfrak{g}$ with $n = \dim V > 3$ is given by $\mathfrak{g} = \mathfrak{so}(V) \oplus \mathfrak{b} \oplus (V \otimes W)$, with $\mathfrak{b}$ a 3-dimensional (**Bianchi**) Lie algebra and $\rho: \mathfrak{b} \rightarrow \mathfrak{gl}(W)$ a 2-dimensional representation.

Structure theorem for $(3,2)$ –KLAs with $n > 3$

As a vector space, a $(3,2)$ –KLA $\mathfrak{g}$ with $n = \dim V > 3$ is given by $\mathfrak{g} = \mathfrak{so}(V) \oplus \mathfrak{b} \oplus (V \otimes W)$, with $\mathfrak{b}$ a 3-dimensional (**Bianchi**) Lie algebra and $\rho: \mathfrak{b} \rightarrow \mathfrak{gl}(W)$ a 2-dimensional representation.

The subspace $\mathfrak{so}(V) \oplus \mathfrak{b}$ is a (direct sum) Lie subalgebra and it acts on $V \otimes W$ in the obvious way:

Structure theorem for $(3,2)$ –KLAs with $n > 3$

As a vector space, a $(3,2)$ –KLA $\mathfrak{g}$ with $n = \dim V > 3$ is given by $\mathfrak{g} = \mathfrak{so}(V) \oplus \mathfrak{b} \oplus (V \otimes W)$, with $\mathfrak{b}$ a 3-dimensional (**Bianchi**) Lie algebra and $\rho: \mathfrak{b} \rightarrow \mathfrak{gl}(W)$ a 2-dimensional representation.

The subspace $\mathfrak{so}(V) \oplus \mathfrak{b}$ is a (direct sum) Lie subalgebra and it acts on $V \otimes W$ in the obvious way:

$$[X, v \otimes w] = Xv \otimes w$$

$$[B, v \otimes w] = v \otimes \rho(B)w$$

Structure theorem for $(3,2)$ –KLAs with $n > 3$

(cont'd)

Structure theorem for $(3,2)$ –KLAs with $n > 3$

(cont'd)

The remaining Lie brackets are determined by a $\mathfrak{b}$ -equivariant $\varphi: \wedge^2 W \rightarrow \mathfrak{b}$

Structure theorem for $(3,2)$ –KLAs with $n > 3$

(cont'd)

The remaining Lie brackets are determined by a $\mathfrak{b}$ -equivariant $\varphi: \wedge^2 W \rightarrow \mathfrak{b}$

$$[v_1 \otimes w_1, v_2 \otimes w_2] = \alpha(w_1, w_2)v_1 \wedge v_2 + \langle v_1, v_2 \rangle \varphi(w_1 \wedge w_2)$$

Structure theorem for $(3,2)$ –KLAs with $n > 3$

(cont'd)

The remaining Lie brackets are determined by a $\mathfrak{b}$ -equivariant $\varphi: \wedge^2 W \rightarrow \mathfrak{b}$

$$[v_1 \otimes w_1, v_2 \otimes w_2] = \alpha(w_1, w_2)v_1 \wedge v_2 + \langle v_1, v_2 \rangle \varphi(w_1 \wedge w_2)$$

where $\alpha: W \times W \rightarrow \mathbb{R}$ is the unique $\mathfrak{b}$ -invariant symmetric bilinear form satisfying

Structure theorem for $(3,2)$ –KLAs with $n > 3$

(cont'd)

The remaining Lie brackets are determined by a $\mathfrak{b}$ -equivariant $\varphi: \wedge^2 W \rightarrow \mathfrak{b}$

$$[v_1 \otimes w_1, v_2 \otimes w_2] = \alpha(w_1, w_2)v_1 \wedge v_2 + \langle v_1, v_2 \rangle \varphi(w_1 \wedge w_2)$$

where $\alpha: W \times W \rightarrow \mathbb{R}$ is the unique $\mathfrak{b}$ -invariant symmetric bilinear form satisfying

$$\rho(\varphi(w_1, w_2))w_3 = \alpha(w_2, w_3)w_1 - \alpha(w_1, w_3)w_2$$

Equivalence criteria

($n > 3$)

Equivalence criteria

$(n > 3)$

Let $(\mathfrak{b}, \rho, \alpha, \varphi)$ and $(\mathfrak{b}', \rho', \alpha', \varphi')$ be the data of two $(3,2)$ –KLAs $\mathfrak{g}$ and $\mathfrak{g}'$ with $n = \dim V > 3$.

Fix an $\mathfrak{so}(V)$ subalgebra of $\mathfrak{g}$ and $\mathfrak{g}'$ and consider w.l.o.g. isomorphisms $f: \mathfrak{g} \rightarrow \mathfrak{g}'$ which are the identity on $\mathfrak{so}(V)$: **relative isomorphisms**. Every relative isomorphism f is given by

Equivalence criteria

$(n > 3)$

Let $(\mathfrak{b}, \rho, \alpha, \varphi)$ and $(\mathfrak{b}', \rho', \alpha', \varphi')$ be the data of two $(3,2)$ -KLAs $\mathfrak{g}$ and $\mathfrak{g}'$ with $n = \dim V > 3$.

Fix an $\mathfrak{so}(V)$ subalgebra of $\mathfrak{g}$ and $\mathfrak{g}'$ and consider w.l.o.g. isomorphisms $f: \mathfrak{g} \rightarrow \mathfrak{g}'$ which are the identity on $\mathfrak{so}(V)$: **relative isomorphisms**. Every relative isomorphism f is given by

$$f(X) = X, \quad f(B) = \psi(B), \quad f(v \otimes w) = v \otimes h(w)$$

Equivalence criteria

$(n > 3)$

Let $(\mathfrak{b}, \rho, \alpha, \varphi)$ and $(\mathfrak{b}', \rho', \alpha', \varphi')$ be the data of two $(3,2)$ -KLAs $\mathfrak{g}$ and $\mathfrak{g}'$ with $n = \dim V > 3$.

Fix an $\mathfrak{so}(V)$ subalgebra of $\mathfrak{g}$ and $\mathfrak{g}'$ and consider w.l.o.g. isomorphisms $f: \mathfrak{g} \rightarrow \mathfrak{g}'$ which are the identity on $\mathfrak{so}(V)$: **relative isomorphisms**. Every relative isomorphism f is given by

$$f(X) = X, \quad f(B) = \psi(B), \quad f(v \otimes w) = v \otimes h(w)$$

for $X \in \mathfrak{so}(V)$, $B \in \mathfrak{b}$, $v \in V$ and $w \in W$, where $\psi: \mathfrak{b} \rightarrow \mathfrak{b}'$ is a Lie algebra isomorphism and $h: W \rightarrow W'$ is a vector space isomorphism so that

Equivalence criteria

$(n > 3)$

Let $(\mathfrak{b}, \rho, \alpha, \varphi)$ and $(\mathfrak{b}', \rho', \alpha', \varphi')$ be the data of two $(3,2)$ -KLAs $\mathfrak{g}$ and $\mathfrak{g}'$ with $n = \dim V > 3$.

Fix an $\mathfrak{so}(V)$ subalgebra of $\mathfrak{g}$ and $\mathfrak{g}'$ and consider w.l.o.g. isomorphisms $f: \mathfrak{g} \rightarrow \mathfrak{g}'$ which are the identity on $\mathfrak{so}(V)$: **relative isomorphisms**. Every relative isomorphism f is given by

$$f(X) = X, \quad f(B) = \psi(B), \quad f(v \otimes w) = v \otimes h(w)$$

for $X \in \mathfrak{so}(V)$, $B \in \mathfrak{b}$, $v \in V$ and $w \in W$, where $\psi: \mathfrak{b} \rightarrow \mathfrak{b}'$ is a Lie algebra isomorphism and $h: W \rightarrow W'$ is a vector space isomorphism so that

$$\rho' \circ \psi = \text{Ad}(h) \circ \rho, \quad \alpha = h^* \alpha', \quad \psi \circ \varphi = h^* \varphi'$$

Remark about equivalent representations

The condition

$$\rho' \circ \psi = \text{Ad}(h) \circ \rho$$

is **strictly weaker** than equivalence of the representations ρ and ρ' .

So we need only classify real 2-dimensional representations of Bianchi Lie algebras up to the above notion of equivalence.

Classification for $n > 3$

Classification for $n > 3$

Let $\mathfrak{g} = \mathfrak{so}(V) \oplus \mathfrak{b} \oplus (V \otimes W)$ be a $(3,2)$ –KLA with data $(\mathfrak{b}, \rho, \alpha, \varphi)$. Then exactly one of the following three situations occurs:

Classification for $n > 3$

Let $\mathfrak{g} = \mathfrak{so}(V) \oplus \mathfrak{b} \oplus (V \otimes W)$ be a $(3,2)$ -KLA with data $(\mathfrak{b}, \rho, \alpha, \varphi)$. Then exactly one of the following three situations occurs:

1. $V \otimes W$ is abelian, so that $\varphi = 0$ and hence $\alpha = 0$

Classification for $n > 3$

Let $\mathfrak{g} = \mathfrak{so}(V) \oplus \mathfrak{b} \oplus (V \otimes W)$ be a $(3,2)$ -KLA with data $(\mathfrak{b}, \rho, \alpha, \varphi)$. Then exactly one of the following three situations occurs:

1. $V \otimes W$ is abelian, so that $\varphi = 0$ and hence $\alpha = 0$
2. $0 \neq [V \otimes W, V \otimes W] \subset \mathfrak{b}$, so that $\alpha = 0$ but $\varphi \neq 0$

Classification for $n > 3$

Let $\mathfrak{g} = \mathfrak{so}(V) \oplus \mathfrak{b} \oplus (V \otimes W)$ be a $(3,2)$ -KLA with data $(\mathfrak{b}, \rho, \alpha, \varphi)$. Then exactly one of the following three situations occurs:

1. $V \otimes W$ is abelian, so that $\varphi = 0$ and hence $\alpha = 0$
2. $0 \neq [V \otimes W, V \otimes W] \subset \mathfrak{b}$, so that $\alpha = 0$ but $\varphi \neq 0$
3. $\alpha \neq 0$ and hence $\varphi \neq 0$

Classification for $n > 3$

Let $\mathfrak{g} = \mathfrak{so}(V) \oplus \mathfrak{b} \oplus (V \otimes W)$ be a $(3,2)$ -KLA with data $(\mathfrak{b}, \rho, \alpha, \varphi)$. Then exactly one of the following three situations occurs:

1. $V \otimes W$ is abelian, so that $\varphi = 0$ and hence $\alpha = 0$
2. $0 \neq [V \otimes W, V \otimes W] \subset \mathfrak{b}$, so that $\alpha = 0$ but $\varphi \neq 0$
3. $\alpha \neq 0$ and hence $\varphi \neq 0$

There are tables in the paper with all isomorphism classes of such Lie algebras.

Structure theorem for $(3,2)$ –KLAs with $n = 3$

Structure theorem for $(3,2)$ –KLAs with $n = 3$

- When $n = 3$ the adjoint and vector representations of $\mathfrak{so}(3)$ are equivalent

Structure theorem for $(3,2)$ –KLAs with $n = 3$

- When $n = 3$ the adjoint and vector representations of $\mathfrak{so}(3)$ are equivalent
- This changes the structure theorem by the addition of a $\mathfrak{b}$ -equivariant symmetric bilinear
 $\sigma: W \times W \rightarrow W$

Structure theorem for $(3,2)$ –KLAs with $n = 3$

- When $n = 3$ the adjoint and vector representations of $\mathfrak{so}(3)$ are equivalent
- This changes the structure theorem by the addition of a $\mathfrak{b}$ -equivariant symmetric bilinear $\sigma: W \times W \rightarrow W$
- We now have

$$[v_1 \otimes w_1, v_2 \otimes w_2] = \alpha(w_1, w_2) v_1 \wedge v_2 + \langle v_1, v_2 \rangle \varphi(w_1 \wedge w_2) + (v_1 \times v_2) \otimes \sigma(w_1, w_2)$$

Structure theorem for $(3,2)$ –KLAs with $n = 3$

- When $n = 3$ the adjoint and vector representations of $\mathfrak{so}(3)$ are equivalent
- This changes the structure theorem by the addition of a $\mathfrak{b}$ -equivariant symmetric bilinear $\sigma: W \times W \rightarrow W$
- We now have

$$[v_1 \otimes w_1, v_2 \otimes w_2] = \alpha(w_1, w_2) v_1 \wedge v_2 + \langle v_1, v_2 \rangle \varphi(w_1 \wedge w_2) + (v_1 \times v_2) \otimes \sigma(w_1, w_2)$$

where now $\alpha: W \times W \rightarrow \mathbb{R}$ is uniquely characterised by

$$\rho(\varphi(w_1, w_2)) w_3 + \sigma(\sigma(w_2, w_3), w_1) - \sigma(\sigma(w_1, w_3), w_2) = \alpha(w_2, w_3) w_1 - \alpha(w_1, w_3) w_2$$

Structure theorem

(cont'd)

Structure theorem

(cont'd)

- In addition, α , σ and φ must obey the following two conditions:

Structure theorem

(cont'd)

- In addition, α , σ and φ must obey the following two conditions:

$$\alpha(\sigma(w_1, w_3), w_2) = \alpha(\sigma(w_2, w_3), w_1)$$

Structure theorem

(cont'd)

- In addition, α , σ and φ must obey the following two conditions:

$$\alpha(\sigma(w_1, w_3), w_2) = \alpha(\sigma(w_2, w_3), w_1)$$

and

Structure theorem

(cont'd)

- In addition, α , σ and φ must obey the following two conditions:

$$\alpha(\sigma(w_1, w_3), w_2) = \alpha(\sigma(w_2, w_3), w_1)$$

and

$$\varphi(\sigma(w_1, w_2) \wedge w_3 + \sigma(w_2, w_3) \wedge w_1 + \sigma(w_3, w_1) \wedge w_2) = 0$$

Equivalence criteria

($n = 3$)

Equivalence criteria

($n = 3$)

- Let $\Phi = (\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$ denote the data defining a $(3,2)$ -KLA $\mathfrak{g}(\Phi)$ with $n = \dim V = 3$

Equivalence criteria

($n = 3$)

- Let $\Phi = (\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$ denote the data defining a $(3,2)$ -KLA $\mathfrak{g}(\Phi)$ with $n = \dim V = 3$
- An isomorphism $f: \mathfrak{g}(\Phi) \rightarrow \mathfrak{g}(\Phi')$ which is the identity on a fixed $\mathfrak{so}(3)$ subalgebra takes the form

Equivalence criteria

($n = 3$)

- Let $\Phi = (\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$ denote the data defining a $(3,2)$ -KLA $\mathfrak{g}(\Phi)$ with $n = \dim V = 3$
- An isomorphism $f: \mathfrak{g}(\Phi) \rightarrow \mathfrak{g}(\Phi')$ which is the identity on a fixed $\mathfrak{so}(3)$ subalgebra takes the form

$$f(X) = X, \quad f(B) = \psi(B), \quad f(v \otimes w) = v \otimes h(w) + \mu(w)\varepsilon(v)$$

Equivalence criteria

$(n = 3)$

- Let $\Phi = (\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$ denote the data defining a $(3,2)$ -KLA $\mathfrak{g}(\Phi)$ with $n = \dim V = 3$
- An isomorphism $f: \mathfrak{g}(\Phi) \rightarrow \mathfrak{g}(\Phi')$ which is the identity on a fixed $\mathfrak{so}(3)$ subalgebra takes the form

$$f(X) = X, \quad f(B) = \psi(B), \quad f(v \otimes w) = v \otimes h(w) + \mu(w)\varepsilon(v)$$

for all $X \in \mathfrak{so}(3)$, $B \in \mathfrak{b}$, $v \in V$ and $w \in W$ and where $\varepsilon: V \rightarrow \mathfrak{so}(V)$ is such that $\varepsilon(v_1)v_2 = v_1 \times v_2$, $\psi: \mathfrak{b} \rightarrow \mathfrak{b}'$ is a Lie algebra isomorphism, $h: W \rightarrow W'$ and $\mu \in (W^*)^{\mathfrak{b}}$ satisfying

Equivalence criteria

($n = 3$)

- Let $\Phi = (\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$ denote the data defining a $(3,2)$ -KLA $\mathfrak{g}(\Phi)$ with $n = \dim V = 3$
- An isomorphism $f: \mathfrak{g}(\Phi) \rightarrow \mathfrak{g}(\Phi')$ which is the identity on a fixed $\mathfrak{so}(3)$ subalgebra takes the form

$$f(X) = X, \quad f(B) = \psi(B), \quad f(v \otimes w) = v \otimes h(w) + \mu(w)\varepsilon(v)$$

for all $X \in \mathfrak{so}(3)$, $B \in \mathfrak{b}$, $v \in V$ and $w \in W$ and where $\varepsilon: V \rightarrow \mathfrak{so}(V)$ is such that $\varepsilon(v_1)v_2 = v_1 \times v_2$, $\psi: \mathfrak{b} \rightarrow \mathfrak{b}'$ is a Lie algebra isomorphism, $h: W \rightarrow W'$ and $\mu \in (W^*)^{\mathfrak{b}}$ satisfying

$$\rho' \circ \psi = \text{Ad}(h) \circ \rho, \quad \alpha - \mu \circ \sigma + \mu \otimes \mu = h^* \alpha', \quad h \circ \sigma - \mu \otimes h - h \otimes \mu = h^* \sigma' \quad \psi \circ \varphi = h^* \varphi'$$

Classification for $\textcolor{blue}{n} = 3$

Classification for $n = 3$

- Let $\mathfrak{g}$ be a $(3,2)$ –KLA with $n = 3$ with data $(\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$. Then up to a relative isomorphism, $\mathfrak{g}$ belongs to exactly one of the following four classes of Lie algebras:

Classification for $n = 3$

- Let $\mathfrak{g}$ be a $(3,2)$ –KLA with $n = 3$ with data $(\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$. Then up to a relative isomorphism, $\mathfrak{g}$ belongs to exactly one of the following four classes of Lie algebras:
 1. $V \otimes W$ is abelian, so that $\varphi = 0$ and $\sigma = 0$ (and hence $\alpha = 0$)

Classification for $n = 3$

- Let $\mathfrak{g}$ be a $(3,2)$ –KLA with $n = 3$ with data $(\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$. Then up to a relative isomorphism, $\mathfrak{g}$ belongs to exactly one of the following four classes of Lie algebras:
 1. $V \otimes W$ is abelian, so that $\varphi = 0$ and $\sigma = 0$ (and hence $\alpha = 0$)
 2. $0 \neq [V \otimes W, V \otimes W] \subset \mathfrak{b}$, so that $\varphi \neq 0$ but $\alpha = 0$ and $\sigma = 0$

Classification for $n = 3$

- Let $\mathfrak{g}$ be a $(3,2)$ –KLA with $n = 3$ with data $(\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$. Then up to a relative isomorphism, $\mathfrak{g}$ belongs to exactly one of the following four classes of Lie algebras:
 1. $V \otimes W$ is abelian, so that $\varphi = 0$ and $\sigma = 0$ (and hence $\alpha = 0$)
 2. $0 \neq [V \otimes W, V \otimes W] \subset \mathfrak{b}$, so that $\varphi \neq 0$ but $\alpha = 0$ and $\sigma = 0$
 3. $0 \neq [V \otimes W, V \otimes W] \subset \mathfrak{so}(V) \oplus \mathfrak{b}$, so that $\alpha \neq 0$ but $\sigma = 0$

Classification for $n = 3$

- Let $\mathfrak{g}$ be a $(3,2)$ –KLA with $n = 3$ with data $(\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$. Then up to a relative isomorphism, $\mathfrak{g}$ belongs to exactly one of the following four classes of Lie algebras:
 1. $V \otimes W$ is abelian, so that $\varphi = 0$ and $\sigma = 0$ (and hence $\alpha = 0$)
 2. $0 \neq [V \otimes W, V \otimes W] \subset \mathfrak{b}$, so that $\varphi \neq 0$ but $\alpha = 0$ and $\sigma = 0$
 3. $0 \neq [V \otimes W, V \otimes W] \subset \mathfrak{so}(V) \oplus \mathfrak{b}$, so that $\alpha \neq 0$ but $\sigma = 0$
 4. $V \otimes W$ is a nonabelian ideal, so that $\alpha = 0$ and $\varphi = 0$, but $\sigma \neq 0$

Classification for $n = 3$

- Let $\mathfrak{g}$ be a $(3,2)$ –KLA with $n = 3$ with data $(\mathfrak{b}, \rho, \alpha, \varphi, \sigma)$. Then up to a relative isomorphism, $\mathfrak{g}$ belongs to exactly one of the following four classes of Lie algebras:
 1. $V \otimes W$ is abelian, so that $\varphi = 0$ and $\sigma = 0$ (and hence $\alpha = 0$)
 2. $0 \neq [V \otimes W, V \otimes W] \subset \mathfrak{b}$, so that $\varphi \neq 0$ but $\alpha = 0$ and $\sigma = 0$
 3. $0 \neq [V \otimes W, V \otimes W] \subset \mathfrak{so}(V) \oplus \mathfrak{b}$, so that $\alpha \neq 0$ but $\sigma = 0$
 4. $V \otimes W$ is a nonabelian ideal, so that $\alpha = 0$ and $\varphi = 0$, but $\sigma \neq 0$

Tables are given in the paper of the isomorphism classes of such $(3,2)$ –KLAs.

Outlook

Next steps in the programme

(Work in progress with Juanma Lorenzo-Naveiro)

Next steps in the programme

- Classification of $(3,2)$ –KLAs with $n = \dim V = 2$

Next steps in the programme

- Classification of $(3,2)$ –KLAs with $n = \dim V = 2$
- Classification of effective, geometrically realisable Klein pairs $(\mathfrak{g}, \mathfrak{h})$ where

Next steps in the programme

- Classification of $(3,2)$ –KLAs with $n = \dim V = 2$
- Classification of effective, geometrically realisable Klein pairs $(\mathfrak{g}, \mathfrak{h})$ where
 - $\mathfrak{g}$ is a $(2,2)$ –KLA and $\mathfrak{h} = \mathfrak{so}(V) \oplus V$ (as a vector space)

Next steps in the programme

- Classification of $(3,2)$ –KLAs with $n = \dim V = 2$
- Classification of effective, geometrically realisable Klein pairs $(\mathfrak{g}, \mathfrak{h})$ where
 - $\mathfrak{g}$ is a $(2,2)$ –KLA and $\mathfrak{h} = \mathfrak{so}(V) \oplus V$ (as a vector space)
 - $\mathfrak{g}$ is a $(3,2)$ –KLA and $\mathfrak{h} = \mathfrak{so}(V) \oplus V \oplus \mathbb{R}$ (as a vector space)

Next steps in the programme

- Classification of $(3,2)$ –KLAs with $n = \dim V = 2$
- Classification of effective, geometrically realisable Klein pairs $(\mathfrak{g}, \mathfrak{h})$ where
 - $\mathfrak{g}$ is a $(2,2)$ –KLA and $\mathfrak{h} = \mathfrak{so}(V) \oplus V$ (as a vector space)
 - $\mathfrak{g}$ is a $(3,2)$ –KLA and $\mathfrak{h} = \mathfrak{so}(V) \oplus V \oplus \mathbb{R}$ (as a vector space)
- For each such Klein pair, study the linear isotropy representation and determine the invariant geometric structures on the coisotropy-one homogeneous spacetimes

Watch this space!