

The Angle Function in Contact Geometry

Philippe Rukimbira

Department of Mathematics and Statistics
Florida International University
Miami, Florida

AIMS, Mbour, May 22, 2018

Outline

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

1 Introduction

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Outline

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

1 Introduction

2 Preliminaries

Outline

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

1 Introduction

2 Preliminaries

3 Condition to be a sphere

Outline

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

1 Introduction

2 Preliminaries

3 Condition to be a sphere

4 Week Stability of Almost Regular Contact Foliations

Outline

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

1 Introduction

2 Preliminaries

3 Condition to be a sphere

4 Week Stability of Almost Regular Contact Foliations

5 Circle Invariant Contact Forms

Outline

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

1 Introduction

2 Preliminaries

3 Condition to be a sphere

4 Week Stability of Almost Regular Contact Foliations

5 Circle Invariant Contact Forms

6 Goldberg conjecture

Outline

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

1 Introduction

2 Preliminaries

3 Condition to be a sphere

4 Week Stability of Almost Regular Contact Foliations

5 Circle Invariant Contact Forms

6 Goldberg conjecture

7 References

Introduction

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Analysis of the angle function between Reeb vector field and other Riemannian geometric vector fields reveals information ranging from the number of closed characteristics to the Sasakian rigidity of shared K-contact metrics.

Introduction

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Analysis of the angle function between Reeb vector field and other Riemannian geometric vector fields reveals information ranging from the number of closed characteristics to the Sasakian rigidity of shared K-contact metrics.

In some contact metric structures, this angle function turns out to be isoparametric whose normalized gradient provides new examples of minimal unit vector fields on noncompact manifolds.

Preliminaries

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

A **contact form** on a $2n + 1$ -dimensional manifold M is a 1-form η such that $\eta \wedge (d\eta)^n$ is a volume form on M .

Preliminaries

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

A **contact form** on a $2n + 1$ -dimensional manifold M is a 1-form η such that $\eta \wedge (d\eta)^n$ is a volume form on M .

There is always a unique vector field Z , the characteristic vector field of η , which is determined by the equations $\eta(Z) = 1$ and $d\eta(Z, X) = 0$ for arbitrary X .

Preliminaries

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

A **contact form** on a $2n + 1$ -dimensional manifold M is a 1-form η such that $\eta \wedge (d\eta)^n$ is a volume form on M .

There is always a unique vector field Z , the characteristic vector field of η , which is determined by the equations $\eta(Z) = 1$ and $d\eta(Z, X) = 0$ for arbitrary X .

The distribution $D_p = \{V \in T_p M : \eta(V) = 0\}$ is called the contact distribution of η . Clearly, D is a symplectic vector bundle with symplectic form $d\eta$.

On a contact manifold (M, η, Z) , there is also a non-unique Riemannian metric g and a partial complex operator J adapted to η in the sense that the identities $g(Z, Z) = 1$ and

$$2g(X, JY) = d\eta(X, Y), \quad J^2X = -X + \eta(X)Z$$

hold for any vector fields X, Y on M .

On a contact manifold (M, η, Z) , there is also a non-unique Riemannian metric g and a partial complex operator J adapted to η in the sense that the identities $g(Z, Z) = 1$ and

$$2g(X, JY) = d\eta(X, Y), \quad J^2X = -X + \eta(X)Z$$

hold for any vector fields X, Y on M .

Assuming that (M, g) is a complete Riemannian manifold, let $\psi_t, t \in \mathbb{R}$ denote the 1-parameter group of diffeomorphisms generated by Z . The contact form η is invariant under the 1-parameter group ψ_t , that is, $\psi_t^*\eta = \eta$.

On a contact manifold (M, η, Z) , there is also a non-unique Riemannian metric g and a partial complex operator J adapted to η in the sense that the identities $g(Z, Z) = 1$ and

$$2g(X, JY) = d\eta(X, Y), \quad J^2X = -X + \eta(X)Z$$

hold for any vector fields X, Y on M .

Assuming that (M, g) is a complete Riemannian manifold, let $\psi_t, t \in \mathbb{R}$ denote the 1-parameter group of diffeomorphisms generated by Z . The contact form η is invariant under the 1-parameter group ψ_t , that is, $\psi_t^*\eta = \eta$.

If ψ_t is also a 1-parameter group of isometries of g , then the contact metric manifold is called a **K -contact manifold**.

On a K -contact manifold, one has the identity

$$\nabla_X Z = -JX$$

valid for any tangent vector X .

On a K -contact manifold, one has the identity

$$\nabla_X Z = -JX$$

valid for any tangent vector X .

If the identity

$$(\nabla_X J)Y = g(X, Y)Z - \eta(Y)X$$

is satisfied for any vector fields X and Y on M , then the contact metric structure (M, η, Z, J, g) is called a **Sasakian** structure.

More generally; given a unit Killing vector field Z on a Riemannian manifold (M, g) , Z is the Reeb field of a Sasakian structure on M if and only if the following identity is satisfied:

$$\nabla_X(\nabla Z)Y = g(Z, Y)X - g(X, Y)Z$$

for any vector fields X and Y on M .

Condition to be a sphere

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Theorem (Obata, 1965)

Let (M, g) be a complete simply connected Riemannian space of dimension n . In order for M to admit a non-trivial solution ρ for the system of differential equations

$$\begin{aligned} (\nabla^2 d\rho)(X, Y, Z) = \\ -c[2d\rho(X)g(Y, Z) + d\rho(Y)g(X, Z) + d\rho(Z)g(X, Y)], \end{aligned}$$

it is necessary and sufficient that M is isometric with a sphere S^n of radius $\frac{1}{\sqrt{c}}$ in the Euclidean $(n+1)$ -space E^{n+1} .

Condition to be a sphere

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Theorem (Obata, 1965)

Let (M, g) be a complete simply connected Riemannian space of dimension n . In order for M to admit a non-trivial solution ρ for the system of differential equations

$$\begin{aligned} (\nabla^2 d\rho)(X, Y, Z) = \\ -c[2d\rho(X)g(Y, Z) + d\rho(Y)g(X, Z) + d\rho(Z)g(X, Y)], \end{aligned}$$

it is necessary and sufficient that M is isometric with a sphere S^n of radius $\frac{1}{\sqrt{c}}$ in the Euclidean $(n+1)$ -space E^{n+1} .

An example of such a ρ is $\rho = \operatorname{div} W$ where W is an infinitesimal projective transformation.

In this case [**Okumura, 1962**], $d\rho = (n + 1)\mu$, where μ is the 1-form determined by

$$(L_W \nabla)(U, V) = \mu(V)U + \mu(U)V$$

or, equivalently:

$$(\nabla_U \nabla W)V = R(U, W)V + \mu(V)U + \mu(U)V.$$

Another instance when such a ρ exists is in the presence of two Sasakian structures.

Another instance when such a ρ exists is in the presence of two Sasakian structures.

If (M, g, ξ_1, ξ_2) are two Sasakian structures, then $\rho = g(\xi_1, \xi_2)$ satisfies the above differential equations [Tachibana-Yu, 1970]

Existence of closed characteristics

Theorem (Banyaga-Rukimbira, 1994)

Let \mathcal{F}' be a contact foliation which is a C^1 -perturbation of an almost regular contact foliation \mathcal{F} on a compact manifold M . Then \mathcal{F}' has at least two compact leaves.

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Existence of closed characteristics

Theorem (Banyaga-Rukimbira, 1994)

Let \mathcal{F}' be a contact foliation which is a C^1 -perturbation of an almost regular contact foliation \mathcal{F} on a compact manifold M . Then \mathcal{F}' has at least two compact leaves.

Indeed:

Let $\gamma(t)$ be the unique geodesic joining p and $\phi_T(p)$, where T is the period of the almost regular contact flow ϕ_t and define

$$S(p) = \int \alpha(\gamma'(t))dt = \int g(\xi, \gamma'(t))dt.$$

Where g is an adapted Riemannian metric.

Existence of closed characteristics

Theorem (Banyaga-Rukimbira, 1994)

Let \mathcal{F}' be a contact foliation which is a C^1 -perturbation of an almost regular contact foliation \mathcal{F} on a compact manifold M . Then \mathcal{F}' has at least two compact leaves.

Indeed:

Let $\gamma(t)$ be the unique geodesic joining p and $\phi_T(p)$, where T is the period of the almost regular contact flow ϕ_t and define

$$S(p) = \int \alpha(\gamma'(t))dt = \int g(\xi, \gamma'(t))dt.$$

Where g is an adapted Riemannian metric.

The idea of the proof is to show that for a sufficiently small perturbation, if $\gamma'(0) \neq 0$ or $\gamma'(0) \neq \lambda \xi_p$, then $D_p S \neq 0$.

More specifically: $D_p S(J\gamma'(0)) \neq 0$, where J is the transverse almost contact structure.

As a consequence, any critical point of \mathbf{S} corresponds thus to a periodic orbit for ξ_α .

Circle invariant contact forms

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Theorem

Let M be a $2n + 1$ -dimensional compact manifold with a circle invariant contact form α . If Z is the infinitesimal generator of the circle action and $\alpha(Z) \neq 0$ everywhere on M , then α admits a least $n + 1$ closed characteristics.

Circle invariant contact forms

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Theorem

Let M be a $2n + 1$ -dimensional compact manifold with a circle invariant contact form α . If Z is the infinitesimal generator of the circle action and $\alpha(Z) \neq 0$ everywhere on M , then α admits a least $n + 1$ closed characteristics.

Sketch of the proof:

Z is the Reeb field of $\beta = \frac{1}{\alpha(Z)}\alpha$. The quotient V -manifold Σ carries a symplectic form and since $(d\beta)^n \neq 0$ everywhere, one sees that $\text{cuplength}(\Sigma) \geq n$.

It is also known from classical Lusternick-Shnirelman Theory that

$$\text{cat}(M) \geq \text{cuplength}(M) + 1$$

The circle invariant function $\alpha(Z)$ should have at least $\text{cat}(\Sigma) \geq n + 1$ critical circles.

Goldberg conjecture in symplectic geometry

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

**Goldberg
conjecture**

References

**Any compact symplectic, Einstein manifold is Kähler.
[Goldberg, 1969].**

Goldberg conjecture in symplectic geometry

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

**Any compact symplectic, Einstein manifold is Kähler.
[Goldberg, 1969].**

Essentially still open. With an additional condition,

Theorem (Sekigawa, 1987)

Any compact almost kähler Einstein manifold with nonnegative scalar curvature is Kähler.

Problems

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

1. There are known restrictions on the cohomology of Kähler manifolds. It is interesting to understand to what extent do those restrictions apply to Almost Kähler Einstein manifolds.

Problems

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Statbility

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

1. There are known restrictions on the cohomology of Kähler manifolds. It is interesting to understand to what extent do those restrictions apply to Almost kähler Einstein manifolds.
2. Suppose an Einstein compact manifold M admits a compatible Kähler structure and let ω be any other adapted symplectic structure. Is ω necessarily Kähler?

Contact Goldberg conjecture

Any compact, $2n + 1$ -dimensional contact Einstein manifold is Sasakian.

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

**Goldberg
conjecture**

References

Contact Goldberg conjecture

Any compact, $2n + 1$ -dimensional contact Einstein manifold is Sasakian.

In general, the conjecture is still open. But, since K-contact Einstein manifolds have positive scalar curvature, one expected Sekigawa type results to hold on these manifolds.

Indeed:

Theorem (Boyer-Galicki, 2001)

Any compact, K-contact Einstein manifold is Sasakian.

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Statbility

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Contact Goldberg conjecture

Any compact, $2n + 1$ -dimensional contact Einstein manifold is Sasakian.

In general, the conjecture is still open. But, since K-contact Einstein manifolds have positive scalar curvature, one expected Sekigawa type results to hold on these manifolds.

Indeed:

Theorem (Boyer-Galicki, 2001)

Any compact, K-contact Einstein manifold is Sasakian.

An affirmative answer to the contact Goldeberg conjecture would actually follow from an affirmative answer to the following question: **On a compact, $2n+1$ -dimensional manifold, does any Einstein contact metric admit a compatible Sasakian structure?**

Contact Goldberg conjecture

Any compact, $2n + 1$ -dimensional contact Einstein manifold is Sasakian.

In general, the conjecture is still open. But, since K-contact Einstein manifolds have positive scalar curvature, one expected Sekigawa type results to hold on these manifolds.

Indeed:

Theorem (Boyer-Galicki, 2001)

Any compact, K-contact Einstein manifold is Sasakian.

An affirmative answer to the contact Goldeberg conjecture would actually follow from an affirmative answer to the following question: **On a compact, $2n+1$ -dimensional manifold, does any Einstein contact metric admit a compatible Sasakian structure?**

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Statbility

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Proposition

Let (M, g, β) be a compact Einstein Sasakian manifold, and let α be another compatible contact form on (M, g) . Then α is also a Sasakian form.

Proof: Easy exercise.

Proposition

Let (M, g, β) be a compact Einstein Sasakian manifold, and let α be another compatible contact form on (M, g) . Then α is also a Sasakian form.

Proof: Easy exercise.

Dropping the Einstein condition, we ask:

Suppose a K-contact manifold (M, α, g, X) admits some Sasakian structure (β, g, Z) . Is α necessarily Sasakian?

Proposition

Let (M, g, β) be a compact Einstein Sasakian manifold, and let α be another compatible contact form on (M, g) . Then α is also a Sasakian form.

Proof: Easy exercise.

Dropping the Einstein condition, we ask:

Suppose a K-contact manifold (M, α, g, X) admits some Sasakian structure (β, g, Z) . Is α necessarily Sasakian?

Two distinct cases:

1. Case I: $[Z, X] \neq 0$.
2. Case II: $[Z, X] = 0$.

Case I:

Let ψ_t be the one parameter group of isometries generated by X . Then $(g, \psi_1^* \alpha, \psi_{1*} Z, \psi_{1*}^{-1} J \psi_{1*})$ are structure tensors of a second Sasakian structure on M .

Case I:

Let ψ_t be the one parameter group of isometries generated by X . Then $(g, \psi_1^* \alpha, \psi_{1*} Z, \psi_{1*}^{-1} J \psi_{1*})$ are structure tensors of a second Sasakian structure on M .

By the theorem of Tachibana and Wu, 1970,

- i) If $g(Z, \psi_{1*} Z)$ is constant, then M supports a 3-Sasakian structure. (3 complex structures satisfying quaternionic identities)

Case I:

Let ψ_t be the one parameter group of isometries generated by X . Then $(g, \psi_1^* \alpha, \psi_{1*} Z, \psi_{1*}^{-1} J \psi_{1*})$ are structure tensors of a second Sasakian structure on M .

By the theorem of Tachibana and Wu, 1970,

- i) If $g(Z, \psi_{1*} Z)$ is constant, then M supports a 3-Sasakian structure. (3 complex structures satisfying quaternionic identities)
- ii) If $g(Z, \psi_{1*} Z)$ is nontrivial, then (M, g) is finitely covered by the Euclidean unit sphere.

Case II:

Proposition

If $[X, Z] = 0$, then $g(X, Z)$ is a constant function if and only if $X = \pm Z$.

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References

Case II:

Proposition

If $[X, Z] = 0$, then $g(X, Z)$ is a constant function if and only if $X = \pm Z$.

Proof: Suppose $X \neq \pm Z$. Let ϕ and J denote the two almost complex structures on the respective contact distributions.

Case II:

Proposition

If $[X, Z] = 0$, then $g(X, Z)$ is a constant function if and only if $X = \pm Z$.

Proof: Suppose $X \neq \pm Z$. Let ϕ and J denote the two almost complex structures on the respective contact distributions. Then from $\nabla_X Z - \nabla_Z X = 0$, it follows that $-JX + \phi Z = 0$. That is

$$\phi Z = JX.$$

Case II:

Proposition

If $[X, Z] = 0$, then $g(X, Z)$ is a constant function if and only if $X = \pm Z$.

Proof: Suppose $X \neq \pm Z$. Let ϕ and J denote the two almost complex structures on the respective contact distributions. Then from $\nabla_X Z - \nabla_Z X = 0$, it follows that $-JX + \phi Z = 0$. That is

$$\phi Z = JX.$$

On the other hand, the gradient of $f = g(X, Z)$ is easily seen to be

$$\nabla f = 2JX = 2\phi Z.$$

Since $Z \neq \pm X$, one has

$$2JX = 2\phi Z \neq 0,$$

so $f = g(Z, X)$ is not a constant function.

Since $Z \neq \pm X$, one has

$$2JX = 2\phi Z \neq 0,$$

so $f = g(Z, X)$ is not a constant function.

The function $f = g(X, Z)$ in this case is actually what is known as **isoparametric**; that is

$$\|\nabla f\| = a(f) \text{ and } \Delta f = b(f)$$

for some functions a and b defined on the range of f .

Since $Z \neq \pm X$, one has

$$2JX = 2\phi Z \neq 0,$$

so $f = g(Z, X)$ is not a constant function.

The function $f = g(X, Z)$ in this case is actually what is known as **isoparametric**; that is

$$\|\nabla f\| = a(f) \text{ and } \Delta f = b(f)$$

for some functions a and b defined on the range of f .

Defined on the complement of the critical set of f ,

$$N = \frac{\nabla f}{\|\nabla f\|}$$

is a geodesic, minimal unit vector field (**Rukimbira, 2015**).

Theorem

Let $(M, g, \alpha, Z, \beta, X)$ be a non-trivial bi-K-ontact structure on a closed manifold M , one of them being Sasakian. Then $[Z, X] \neq 0$.

Theorem

Let $(M, g, \alpha, Z, \beta, X)$ be a non-trivial bi-K-ontact structure on a closed manifold M , one of them being Sasakian. Then $[Z, X] \neq 0$.

Sketch of proof:

Suppose $[Z, X] = 0$. Then the angle function $f = g(Z, X)$ has exactly 2 critical submanifolds Σ_{-1} and Σ_1 . Moreover, each of these is totally geodesic.

Theorem

Let $(M, g, \alpha, Z, \beta, X)$ be a non-trivial bi-K-ontact structure on a closed manifold M , one of them being Sasakian. Then $[Z, X] \neq 0$.

Sketch of proof:

Suppose $[Z, X] = 0$. Then the angle function $f = g(Z, X)$ has exactly 2 critical submanifolds Σ_{-1} and Σ_1 . Moreover, each of these is totally geodesic.

Let γ be the minimal geodesic realizing the distance between Σ_{-1} and Σ_1 and \bar{Z} denotes the parallel translate of Z along the geodesic γ .

Since

$$\nabla_N Z = -\frac{1}{\|JX\|} J^2 X = \frac{1}{\|JX\|} (X - \alpha(X)Z),$$

one sees that \bar{Z} stays in the X, Z plane along γ .

Since

$$\nabla_N Z = -\frac{1}{\|JX\|} J^2 X = \frac{1}{\|JX\|} (X - \alpha(X)Z),$$

one sees that \bar{Z} stays in the X, Z plane along γ .

This vector field \bar{Z} along γ provides a negative second variation for the energy functional along γ ; contradicting its minimizing property.

References

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References



Blair, D.E., *Riemannian Geometry of Contact and Symplectic Manifolds*, Birkhäuser, 2002.



Banyaga, A., Rukimbira, P., *Weak Stability of Almost Regular Contact Foliations*, Journal of Geometry, Vol. 50 (1994), 16–27.



Goldberg, S.I., *Integrability of almost kähler manifolds*, Proc. Amer. Math. Soc. 21(1969), 96-100.



Obata, M., *Riemannian manifolds admitting a solution of a certain system of differential equations*, Proc. of the United States-Japan seminar in differential geometry, 1965, 101-114.



Okumura, M., *On infinitesimal conformal and projective transformations of normal contact spaces*, Tôhoku Math. J. 14 (1962), 398-412.

References (ctd)

The Angle
Function in
Contact
Geometry

Philippe
Rukimbira

Introduction

Preliminaries

Condition to
be a sphere

Week
Stability

Circle
Invariant
Contact Forms

Goldberg
conjecture

References



Rukimbira, P. *Isoparametric functions, harmonic and minimal unit vector fields in K-contact geometry*, J. Geom. 106 (2015), 97-107.



Sekigawa, K., *On some compact Einstein, almost Kählerian manifolds*, J. Math. Soc. Japan, 39 (1987), 677-684.



Tachibana, S., Yu, W.N., *On a Riemannian manifold admitting more than one Sasakian structures*, Tôhoku Math. Journ. 22 (1970), 536-540.