SR: The laws of physics are invariant under transformations connecting inertial frames, and spacetime is isotropic in space and homogeneous in space-time. \( \mathcal{P} = \text{ISO}(1,3) \times \mathcal{T}^4 \)

GR: The laws of physics are invariant under diffeomorphisms of spacetime and the connection (gauge field) facilitating this invariance should be rendered dynamical by the introduction of an invariant field strength term. 

It will take time to digest all of this, especially the second half, but the first half will seem similar to what we did in SR, i.e. identify transformations and then demand laws be expressed in terms of true tensors under these transformations.

To get an idea of why the transformations in GR will be more complicated, consider SR where we can coordinatize M" globally with \((t, x, y, z)\) and notice \( T_{\mu \nu} \). This means that the Lorentz transformations (actually Poincaré) act the same everywhere, and it is in these coordinates that physical laws take their simplest form (preferred coordinates).

However we learned from the EEP that unless gravity is present, we will at best be able to describe things in terms of flat-space physics over a small region. We will not be able to extend this to a global symmetry of the entire space. Moreover, since each region can be made flat exclusively of the others, there is no preferred coordinate system. So we are going to need a much more general set of transformations that exhibit no preferred coordinates. \( \Rightarrow \) "General coordinate transformations" or "General Covariance".

But coordinates are really not physical, so much of this we should be able to consider in a coordinate independent form.
Einstein Equivalence Principle: Experiments performed over a short time in a small freely-falling lab give results indistinguishable from those obtained in an inertial frame in empty space.

This along with the absence of any gravitationally "neutral" objects lead us to define "inertial" frames as freely-falling frames (FFF) since:

\[
\begin{align*}
\text{Lab} \uparrow \mathbf{\hat{a}} & = \text{Lab} \uparrow \mathbf{\hat{a}} \\
\underbrace{\text{inertum}}_{\text{uniform}} & \\
\text{Lab} \downarrow \mathbf{\hat{a}} & = \text{Lab} \downarrow \mathbf{\hat{a}} \quad \text{freely-falling}
\end{align*}
\]

Small labs and short times are required to ensure approximate uniformity of \( \mathbf{\hat{a}} \), even if it changes w position.

2 important implications:
1. In an FFF we can use SR since this correctly describes physics in deep space (no gravity).
2. When looking for what type of spacetimes are allowed in GR they must be locally flat, i.e. a manifold.

**Non-Relativistic**
\[
\begin{align*}
q_{\mu \nu} &= (0,^0) \Rightarrow \text{Euclidean Space (in x,y,z,\ldots)} \\
&\text{Special Cases}
\end{align*}
\]

**Relativistic**
\[
\begin{align*}
q_{\mu \nu} &= (0,^\gamma) \Rightarrow \text{Hilbert Space (in t,x,y,z,\ldots)}
\end{align*}
\]

**pseudo-Relativistic**
\[
\begin{align*}
q_{\mu \nu} &= (-,^\gamma) \quad \text{with } a_1, a_2, \ldots > 0 \Rightarrow \text{Euclidean Signature}
\end{align*}
\]

**pseudo-Relativistic**
\[
\begin{align*}
q_{\mu \nu} &= (-,^\gamma) \quad \text{with } a_1, a_2, \ldots > 0 \Rightarrow \text{Lorentzian Signature}
\end{align*}
\]
So what is a manifold?

A $\mathbb{C}^p$ $n$-dimensional manifold is a set $M$ with a maximal atlas.

That's nice, but what do $\mathbb{C}^p$, maximal and atlas mean?

The set $M$ we have in mind is the collection of points in space (time).

Let's begin by breaking $M$ up into patches called charts:

A chart is a subset of $M$ with a one-to-one map $\phi: U_\alpha \rightarrow \mathbb{R}^n$ such that the image of $\phi$ is open in $\mathbb{R}^n$.

Okay, but what does one-to-one and open mean?

One-to-one (injective):

Aside: One-to-one + onto = bijective or invertible

Open: Open in $\mathbb{R}^n$ means the interior of an $(n-1)$-dimensional closed surface

Example:

\begin{align*}
\text{closed surface in } \mathbb{R}^2 &\quad \Rightarrow \\
\text{open in } \mathbb{R}^1 &
\end{align*}
Okay, these maps which define charts may sound abstract, but they really just boil down to our ability to choose "good" coordinates for the patch $U_{\alpha}$.

$U_{\alpha}$ takes a point in $U_{\alpha}$ and sends it to $(x, y) \in \mathbb{R}^d$.

Example: $(\theta, \phi)$ coordinates for a curved $S^d$ take values in $\mathbb{R}^d$.

Now that we know what a chart is, we can define an atlas:

An atlas on $M$ is a collection of charts $\{(U_{\alpha}, \varphi_{\alpha})\}$ such that:

1. The union of all charts $U_{\alpha}$ is equal to $M$.
2. The charts are sewn together with $C^0$ transition functions.

Okay, wait, what are $C^0$ transition functions?

Suppose two charts overlap:

Then: $p_\alpha = \varphi_\alpha(p) = \varphi_\alpha \circ \varphi_\beta^{-1}(p_\beta) : \mathbb{R}^d \to \mathbb{R}^d$

The transition map or transition function $\varphi_{\beta \alpha} = \varphi_\alpha \circ \varphi_\beta^{-1}$ gives:

$$\begin{cases} x_1 = f_\beta(x_1, y_1, z_1, \ldots) \\
y_1 = f_\beta(x_1, y_1, z_1, \ldots) \\
\vdots \end{cases}$$

But these are just coordinate changes!
Now that we are dealing with functions from $\mathbb{R}^n$ to $\mathbb{R}^m$ we can talk about calculus and in particular derivatives.

If the $p$th derivative of all $f_{\varphi \psi}$ exists and is continuous, then $\varphi \psi$ is $C^p$.

If $p = \infty$, i.e. $C^\infty$ then we call $\varphi \psi$ smooth.

Examples:

If the $C^\infty$ map $\varphi \psi$ is also invertible then we call it a diffeomorphism.

The coordinate transformations we will encounter will almost always be diffeomorphisms.

Last but not least we have to define maximal.

A maximal atlas is an equivalence class. This basically means that if I take one manifold, I may be able to cover it with different choices of atlases. But each choice is an equivalent good representation of the manifold so they belong to the maximal atlas.

Going back: A $C^\infty$-dimensional manifold is a set $M$ w/ a maximal atlas.
Let's put all this fancy math to use with an example.

Prove that $S^1$ (a circle) is a manifold.

To prove $S^1$ is a manifold we need only construct one representative element from the maximal atlas.

$S^1$ is 1D. You might think we could cover it with 1 chart, but it turns out we need at least 2 (you could use more if you like).

Let's label the points in our set $\mathcal{A}$ in 2 ways:

$$
\begin{array}{c}
\text{1} \\
\text{2}
\end{array}
$$

It may seem like we just coordinatized the $S^1$ (mapped it to $\mathbb{R}^1$), but remember we need an open subset of $\mathbb{R}^1$ and $(0,2\pi)$ is not (it contains $2\pi$).

So we use 2 charts as follows:

$U_1 \\
U_2$

$U_1$ w/ the coordinate systems above

$U_1 \cap U_2 = \phi_1 \circ \phi_2^{-1}$

The maps are so trivial that it is easy to see that they are one-to-one and image is open in $\mathbb{R}^1$.

Now we need to check that they form an atlas.

1. Do they combine to cover all of $S^1$? Yes
2. Are the transition functions $C^p$ for some $p$? Consider the overlap $U_1 \cap U_2$.

The transition function $\phi_2 \circ \phi_1^{-1} : \phi_1 \circ \phi_2^{-1}(x_1) = \phi_1 \circ \phi_2^{-1}(x_2)$ is then $\phi_2 \circ \phi_1^{-1} : x_2(x_1) = x_1 + \pi$ which is $C^\infty$!

We can do something similar for the other overlap.