

# ON MAPS OF THE THREE-SPHERE INTO THE PLANE

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## 1. INTRODUCTION

The following theorem deals with a special case of part of the Knaster conjecture [2].

**THEOREM.** *Let  $f: S^3 \rightarrow E^2$  be continuous, and let  $p, p_1, p_2$  be points of  $S^3$  which are vertices of an equilateral triangle in  $E^4$ . Then there exists a rotation  $r \in SO(4)$  such that  $f(rp) = f(rp_1) = f(rp_2)$ .*

This note consists of a proof of this theorem. Before giving the proof, let us fix the notation.  $E^n$  is Euclidean  $n$ -space,  $S^{n-1}$  the unit sphere of  $E^n$ ;  $SO(n)$  is the group of proper rotations of  $E^n$ , considered here as operating on  $S^{n-1}$ ; and  $P^n$  is real projective  $n$ -space. For  $x \in S^3$ , let  $G_x$  denote the subgroup of  $SO(4)$  consisting of rotations which leave  $x$  fixed. Let  $f_1: S^3 \rightarrow E^1$  be the map obtained by following  $f$  by the projection of  $E^2$  onto  $E^1$  which is defined by the rule  $(x_1, x_2) \rightarrow x_1$ . Without loss of generality, suppose that  $p$  is a point of  $S^3$  at which  $f_1$  attains its maximum value, and that this maximum is positive. It is an elementary matter to show that there exists a rotation  $a \in SO(4)$  satisfying

- (1)  $ap = p_1, \quad ap_1 = p_2, \quad a^3 = 1$  (where 1 denotes the identity element of  $SO(4)$ ),
- (2)  $a$  leaves some point, say  $z \in S^3$ , fixed.

Then  $G_p$  and  $G_z$  are conjugate subgroups of  $SO(4)$ , and they carry homologous, non-bounding, integral 3-cycles of  $SO(4)$ . The proof will now proceed as follows: we shall construct a map  $\psi: SO(4) \rightarrow S^3$ , under the assumption that the theorem is false. Then we shall see that  $\psi|_{G_p}$  and  $\psi|_{G_z}$  have different degrees. Since this is impossible, our proof by contradiction will then be complete.

## 2. CONSTRUCTION OF $\psi$

This construction is well known. Define the three maps

$$\phi: SO(4) \rightarrow E^6, \quad T: SO(4) \rightarrow SO(4), \quad T^1: E^6 \rightarrow E^6$$

by the conditions

$$\phi(r) = (f(rp), f(rp_1), f(rp_2)),$$

$$T(r) = r \cdot a,$$

$$T^1(x_1, \dots, x_6) = (x_3, x_4, x_5, x_6, x_1, x_2).$$

Then  $\phi \circ T = T^1 \circ \phi$ , since  $ap = p_1$ , and so forth. Let

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