27. Riemannian Manifolds Admitting Some Geodesic

By Tetsunori KUROGI Fukui University

(Comm. by Kenjiro SHODA, M. J. A., Feb. 12, 1974)

1. Introduction. Let M be a compact Riemannian manifold and f an isometry of M. Then a geodesic α on M is called f-invariant geodesic if $f\alpha = \alpha$. It is not known much about isometry invariant geodesic. In this paper we see what kind of Riemannian manifold admits an isometry invariant geodesic. Our results are following;

Theorem A (K. Grove). Let M be a compact connected, simply connected and oriented Riemannian manifold of odd dimension and f an orientation preserving isometry of M. Then there exists an f-invariant geodesic.

Theorem B. Let M be a compact connected, simply connected and oriented Riemannian manifold of 2k-dimension and f an orientation preserving isometry of M. Then there exists an f-invariant geodesic for k=1 and also well for k>1 if $\lambda_k(f)=even$ where $\lambda_k(f)$ is the trace of an induced homomorphism $f_k: H_k(M, Q) \to H_k(M, Q)$ where Q is the field of rational numbers.

Corollary. Let M be a manifold of Theorem B. Then M admits an f-invariant geodesic for any orientation preserving isometry f of M if $H_k(M, Q) = 0$.

The author wishes to thank the referee for his kindly suggestions.

2. Fixed points of isometry. Let M be a compact manifold and f be an isometry of M. Then the induced homomorphism by f of the *i*-th homology group of M over coefficient Q is denoted by $f_i: H_i(M, Q) \to H_i(M, Q)$ and the trace of f_i by $\lambda_i(f)$.

Lemma 1. Let M be an n-dimensional orientable Riemannian manifold and f an orientation preserving isometry, then we have $\lambda_i(f) = \lambda_{n-i}(f)$ $(i=1 \sim n)$.

Proof. We have only to use the Poincaré duality. q.e.d.

Lemma 2. Let M be an odd dimensional orientable Riemannian manifold and f an orientation preserving isometry of M, then f has no isolated fixed points.

Proof. Let x be a fixed point of f and $f_*: T_x(M) \to T_x(M)$ be an induced homomorphism by f. Then f_* is an element of SO(n) and so f_* has a following representation with respect to a suitable basis;