Recall that the time derivature
$$\frac{\partial}{\partial t}g(t)$$
 is
defined as
 $\left(\frac{\partial}{\partial t}g\right)(x,y) = \frac{\partial}{\partial t}g(x,y)$
time-derivature of the smooth
function $g(x,y)$.
In local coordinates,
 $g(t) = \partial_{ij}(t) dx^{i} \otimes dx^{j}$
 $= \partial_{t}g(t) = g_{ij}(t) dx^{i} \otimes dx^{j}$.
So the time derivature of the metric δ the time
derivature of its components functions with a fixed
basis.
Alimitarly $\left(\frac{\partial}{\partial t}\nabla\right)(x,y) = \frac{\partial}{\partial t}\nabla_{x}y$.
now ∇ is NOT tensorial, but $\frac{\partial}{\partial t}\nabla$ is a tensor
as

$$= f \mathfrak{I}_{X} A = f (\mathfrak{I}_{X}) (\mathfrak{X})$$
$$= \mathfrak{I}_{Y} \mathfrak{I}_{X} \mathfrak{I}_{Y} = \mathfrak{I}_{Y} \mathfrak{I}$$

Your any smooth family of metrics it is desirable to compute the variations of all the appociated quantities. We summarize them below for the case when $\partial_{t} g_{ij} = he_{ij}$, $h \in \Gamma(\mathcal{P}^{*}M \otimes_{S} \mathcal{P}^{*}M)$. $\frac{demma:}{demma:} = -\frac{(3^{ij}g_{jk} = 5^{i}_{k} = 0 \quad (9^{ij}g_{jk} = -9^{ij}g_{jk})}{2}$ • $\partial_{\xi} \Gamma_{ij}^{\kappa} = \frac{1}{a} \partial_{\xi}^{\kappa e} (\nabla_{i} h_{je} + \nabla_{j} h_{ie} - \nabla_{e} h_{ij})$ • $\partial_t R_{ijk} = \frac{1}{2} \partial_t P \int \nabla_i \nabla_j h_{kp} + \nabla_i \nabla_k h_{jp} (-\nabla_i \nabla_p h_{jk} - \nabla_j \nabla_i h_{kp})$ $= \nabla_{i} \nabla_{k} h_{i} p + \nabla_{j} \nabla_{p} h_{i} k$

$$= \frac{1}{2} g^{2} p \sum \nabla_{i} \nabla_{k} h_{i} p + \nabla_{j} \nabla_{p} h_{i} \kappa - \nabla_{i} \nabla_{p} h_{j} \kappa$$

$$- \nabla_{j} \nabla_{k} h_{i} p - R_{ij} \kappa h_{q} p - R_{ij} h_{kq} \sum$$

•
$$\partial_t R_{j\kappa} = \frac{1}{2} g^{PQ} \left(\nabla_q \nabla_j h_{\kappa p} + \nabla_q \nabla_{\kappa} h_{V p} - \nabla_q \nabla_p h_{j\kappa} - \nabla_j \nabla_{\kappa} h_{Q p} \right)$$

•
$$\partial_e R = -\Delta(trh) + \nabla^P \nabla^V hpq - \langle h, Rc \rangle$$

•
$$\partial t \int Ruolg = \int \left(\frac{R(mh)}{a} - Lh_1Rc\right) vol$$

M.

Along the <u>RE</u> we have following improvements $\partial_t R = \Delta R + 21Rc1^2 - proof below.$ $\partial_t R_{jk} = \Delta R_{jk} + 2g^{Pot}g^{ns}R_{pjkn}R_{qs}$ $- 2gPot R_{jp}R_{qk}.$

$$proof: - \partial t R_{jk} = \Delta R_{jk} + \nabla_{j} \nabla_{k} R - g^{P} U (\nabla_{q} \nabla_{j} R_{k} p) + \nabla_{q} \nabla_{k} R_{j} p)$$

$$= \Delta R_{jk} + \nabla_{j} \nabla_{k} R - g^{P} (\nabla_{j} \nabla_{q} R_{k} p - R_{q} i \kappa m R_{m} p) - R_{q} j p m R_{k} m$$

$$+ \nabla_{k} \nabla_{q} R_{j} p - R_{q} \kappa_{j} m R_{m} p$$

$$- R_{q} \kappa p m R_{j} m)$$

$$= \Delta R_{jk} + \nabla_{j} \nabla_{k} R - (\frac{1}{2} \nabla_{j} \nabla_{k} R + \frac{1}{2} \nabla_{k} \nabla_{j} R)$$

$$- R_{p} \kappa m R_{p} m + R_{j} m R_{k} m$$

$$- R_{p} \kappa m R_{p} m + R_{k} m R_{j} m)$$

= RHS.

Proof for
$$2 + R$$
.
We have $2 + R = -\Delta(tr(-2Re)) + div(div(-2Re))$
 $- \langle -2Re, Re \rangle$
 $= 2\Delta R - \Delta R + 2|Re|^2$ (we use twice contracted
 $= \Delta R + 2|Ric|^2$.

Proof for the evolution of vol.
First vecall that in local coordinates, the volume
form

$$Volg = \int defg_{ij} dx^{i} \wedge \dots \wedge dx^{n}$$

 $b det efg_{ij} = g(\frac{\partial}{\partial x_{i}}, \frac{\partial}{\partial x_{i}})$

Re call that $A^{-1} = \frac{1}{olet A} adj A \quad \text{for a square matrix} A$ where adj A = adjugate matrix = transpose of the cojector matrixThe partial derivature of det A wr.t. (i,j)-th costry is $\frac{2}{2a_{ij}} det (A) = (-1)^{i+j} det A_{ij}$ $= (adj A)_{ji} = det A (A^{-1})_{ji}$ so $\frac{2}{2t} \sqrt{detg_{ij}} = \frac{1}{2\sqrt{detg_{ii}}} = \frac{2}{2t} det g = \frac{1}{2\sqrt{detg}} = \frac{2detg}{2t} = \frac{2detg}{2t}$

$$= \frac{1}{2} \det g \left(g^{-1}\right)_{ji} h_{ij}$$
$$= \frac{1}{2} \det g g^{ij} h_{ij}$$
$$S. \quad \partial_t vol = (trh)_{vol}.$$

The proofs for the evolutions of Rm, Ric, R and I for general variations can be done using the local coordinate expressions of these quantities and noticing that they are all components of a tensor (I is not but Ott is) and hence use can simplify our calculations by working is normal coordinates at a point.

We did this in detail in the class.

- X