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Infinitesimal projective rigidity under Dehn filling

Michael Heusener and Joan Porti*

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Abstract

To a hyperbolic manifold one can associate a canonical projective structure and ask whether it can be deformed or not. In a cusped manifold, one can ask about the existence of deformations that are trivial on the boundary. We prove that if the canonical projective structure of a cusped manifold is infinitesimally projectively rigid relative to the boundary, then infinitely many Dehn fillings are projectively rigid. We analyze in more detail the figure eight knot and the Withehead link exteriors, for which we can give explicit infinite families of slopes with projectively rigid Dehn fillings.

MSC: 57M50; 53A20; 53C15

Keywords: Projective structures; variety of representations; infinitesimal deformations.

1 Introduction

A closed hyperbolic n -dimensional manifold inherits a canonical projective structure. This can be easily seen by considering the Klein model for the hyperbolic space. Projective structures on manifolds were studied by Benzécri in the 1960's [2]. Though the hyperbolic structure is rigid for $n > 2$ (cf. [26, 20]), it might be possible to deform the canonical projective structure. Kac and Vinberg [25] gave the first examples of such deformations. Koszul [17] and Goldman later generalized these examples. Johnson and Millson provide deformations of the canonical projective structure by means of bending along totally geodesic surfaces [14]. Examples of deformations for Coxeter orbifolds have been obtained by Choi [6] and Marquis [19].

In the sequel we will use the following notation:

1.1 Definition A closed hyperbolic manifold is called *projectively locally rigid* if the canonical projective structure induced by the hyperbolic metric cannot be deformed.

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Cooper, Long and Thistlethwaite have studied the deformability of 4500 hyperbolic manifolds from the Hodgson-Weeks census with rank 2 fundamental group [7], proving that at most 61 can be deformed. The goal of this paper is to provide infinite families of projectively locally rigid manifolds, by means of Dehn filling.

Let N be a closed hyperbolic 3-dimensional manifold. We will make use of the fact that geometric structures on N are controlled by their holonomy representation. Hence consider the holonomy representation of the closed hyperbolic 3-manifold N

$$\rho: \pi_1(N) \rightarrow PSO(3, 1) \subset PGL(4).$$

If not specified, the coefficients of matrix groups are real: $PGL(4) = PGL(4, \mathbf{R})$. The closed manifold N is projectively rigid if and only if all deformations of ρ in $PGL(4)$ are conjugate to a representation in $PSO(3, 1)$, because in this case Weil's rigidity implies that all deformations of ρ are contained in the $PGL(4)$ -orbit of ρ .

Existence or not of deformations is often studied at the infinitesimal level. We may consider the adjoint action on the Lie algebra $\mathfrak{so}(3, 1)$. Then Weil's infinitesimal rigidity [26] asserts that

$$H^1(\pi_1(N); \mathfrak{so}(3, 1)_{\text{Ad } \rho}) = 0.$$

The adjoint action extends to the Lie algebra $\mathfrak{sl}(4) := \mathfrak{sl}(4, \mathbf{R})$ and motivates the following definition.

1.2 Definition A closed hyperbolic three manifold N is called *infinitesimally projectively rigid* if

$$H^1(\pi_1(N); \mathfrak{sl}(4)_{\text{Ad } \rho}) = 0.$$

Infinitesimal rigidity implies local rigidity, but the examples of [8] and [7] show that the converse is not true.

We are working with aspherical manifolds, so computing the cohomology of a manifold or of its fundamental group does not make any difference.

For cusped manifolds one has a similar definition. Let M denote a compact three manifold with boundary a union of tori and whose interior is hyperbolic with finite volume.

1.3 Definition The manifold M is called *infinitesimally projectively rigid* if the inclusion $\partial M \subset M$ induces an injective homomorphism

$$0 \rightarrow H^1(M; \mathfrak{sl}(4)_{\text{Ad } \rho}) \rightarrow H^1(\partial M; \mathfrak{sl}(4)_{\text{Ad } \rho}).$$

The following theorem provides infinitely many examples of infinitesimally projectively rigid 3-dimensional manifolds.

1.4 Theorem *Let M be a compact orientable 3-manifold whose interior is hyperbolic with finite volume. If M is infinitesimally projectively rigid, then infinitely many Dehn fillings on M are infinitesimally projectively rigid.*

A hyperbolic Dehn filling on M induces a noncomplete structure on M , that can be viewed as a hyperbolic cone structure with cone angles 2π . In some cases this cone angle can be decreased to zero, yielding the complete structure on M . The methods of Theorem 1.4, give the following:

1.5 Theorem *Let M be compact orientable 3-manifold whose interior is hyperbolic with cusps. If a Dehn filling on M satisfies:*

- (i) *it is infinitesimally projectively rigid,*
- (ii) *the noncomplete induced structure on M can be joined to the complete one by a path of hyperbolic cone structures parametrized by cone angle from 2π to 0,*

then infinitely many Dehn fillings on M are infinitesimally projectively rigid.

By Hodgson and Kerckhoff estimation of the size of the Dehn filling space [13], in a cusped manifold the deformation of Theorem 1.5 exists for all but at most 60 Dehn fillings. Hence:

1.6 Corollary *Let M be a one cusped hyperbolic manifold of finite volume. If 61 Dehn fillings on M are either non-hyperbolic or infinitesimally projectively rigid, then infinitely many fillings are so.*

Those results are proved using the fact that the infinitesimally projectively rigid examples lie in a proper real analytic subset of the Thurston's hyperbolic Dehn filling space. This technique goes back to Kapovich, in the setting of deformations of lattices $PSO(3, 1)$ in $PSO(4, 1)$ [15]. Moreover, working with examples that lie in a curve of the or non hyperbolic and looking carefully at the infinitesimal deformations, we can obtain explicit examples of projectively rigid manifolds obtained by Dehn filling:

1.7 Proposition *For n sufficiently large, the homology sphere obtained by $1/n$ -Dehn filling on the figure eight knot is infinitesimally projectively rigid.*

In fact, for every $k \in \mathbf{Z}$, $k \neq 0$, there exists $n_k > 0$ such that if $n \geq n_k$ then the k/n -Dehn filling on the figure eight knot is infinitesimally projectively rigid.

Using that punctured torus bundles with tunnel number one are obtained by n -Dehn filling on the Whitehead link (cf. [1]), we shall prove:

1.8 Proposition *All but finitely many punctured torus bundles with tunnel number one are infinitesimally projectively rigid.*

All but finitely many twist knots are infinitesimally projectively rigid.

The real hyperbolic space \mathbf{H}^3 naturally embeds in the complex hyperbolic space $\mathbf{H}_{\mathbb{C}}^3$. We may study the corresponding deformation theory coming from viewing $PSO(3, 1) = \text{Isom}^+(\mathbf{H}^3)$ in $PSU(3, 1) = \text{Isom}_0(\mathbf{H}_{\mathbb{C}}^3)$, i.e. the identity component of complex hyperbolic isometries.

1.9 Definition We say that M is *infinitesimally $\mathbf{H}_{\mathbb{C}}^3$ -rigid* if

$$0 \rightarrow H^1(M; \mathfrak{su}(3, 1)_{\text{Ad } \rho}) \rightarrow H^1(\partial M; \mathfrak{su}(3, 1)_{\text{Ad } \rho}).$$

In particular, if $\partial M = \emptyset$, then we require $H^1(M; \mathfrak{su}(3, 1)_{\text{Ad } \rho}) = 0$. The study of deformations in $PGL(4)$ and $PSU(3, 1)$ are related, as we shall see in Subsection 3.3. In particular we have the following theorem of Cooper, Long and Thistlethwaite.

1.10 Theorem [8] *Let M^n be a real hyperbolic manifold of finite volume, $n \geq 3$. Then M^n is infinitesimally projectively rigid if and only if M^n is infinitesimally $\mathbf{H}_{\mathbb{C}}^n$ -rigid*

This equivalence is described by means of Lie algebras, and it is used along the paper, because some things are easier to understand in the complex hyperbolic setting instead of the projective one.

The article is organized as follows. In Section 2 we recall Thurston's construction of deformations of hyperbolic structures and the generalized Dehn filling coefficients. In Section 3 we introduce the main tools of infinitesimal deformations. The next two sections are devoted to cohomology computations, namely in Section 4 we compute invariant subspaces of the Lie algebras and in Section 5 we analyze the image in cohomology of the restriction to the torus boundary. The proof of Theorems 1.4 and 1.5 of the results is given on Section 6, by means of an analytic function on the deformation space: when this function does not vanish, then the corresponding Dehn filling is infinitesimally rigid. To prove Propositions 1.7 and 1.8, we require the notion of flexing slope, treated in Section 7, as well as explicit computations on the figure eight knot and the Whitehead link exteriors, made in Section 8.

2 Dehn filling and Thurston's slice

In this section we recall the deformation space introduced by Thurston in his proof of hyperbolic Dehn filling theorem [24].

Along the paper, M denotes a compact manifold with boundary a union of $k > 0$ tori and hyperbolic interior:

$$\partial M = \partial_1 M \sqcup \cdots \sqcup \partial_k M,$$

where each $\partial_i M \cong T^2$.

The deformation space of hyperbolic structures is described by the *Thurston slice*. Given $\lambda_i, \mu_i \in \pi_1(\partial M)$ a pair of simple closed curves that generate the fundamental group on each component ∂M_i , Thurston introduced a parameter

$$u = (u_1, \dots, u_k) \in U \subset \mathbf{C}^k,$$

defined on U a neighborhood of 0. The neighborhood U parametrizes the deformations of the complete holonomy of the interior of M . Two structures parametrized by u and $u' \in U$ are equivalent (the developing maps differ by composing with an isometry of \mathbf{H}^3) if and only if

$$(u_1, \dots, u_k) = (\pm u'_1, \dots, \pm u'_k). \quad (1)$$

This is a consequence of the fact that (1) is a criterion for having the same character, and the fact that deformations are parametrized by conjugacy classes of holonomy [5].

2.1 Theorem (Thurston's slice) *There exists an open neighborhood $0 \in U \subset \mathbf{C}^k$, an analytic family of representations $\{\rho_u\}_{u \in U}$, of $\pi_1(M)$ in $PSL_2(\mathbf{C})$ and analytic functions $v_i = v_i(u)$, $i = 1, \dots, k$ so that:*

- (i) *The parameters u_i and v_i are the complex length of $\rho_u(\mu_i)$ and $\rho_u(\lambda_i)$ respectively.*
- (ii) *The function $\tau_i(u) = v_i(u)/u_i$ is analytic. Moreover $v_i = \tau_i(0)u_i + (|u|^3)$, where $\tau_i(0) \in \mathbf{C}$ is the cusp shape and has nonzero imaginary part.*
- (iii) *The structure with holonomy ρ_u is complete on the i -th cusp if and only if $u_i = 0$.*
- (iv) *When $u_i \neq 0$, the equation*

$$p_i u_i + q_i v_i = 2\pi \mathbf{i} \quad (2)$$

has a unique solution for $(p_i, q_i) \in \mathbf{R}^2$. The representation ρ_u is the holonomy of a incomplete hyperbolic structure with generalized Dehn filling coefficients (p_i, q_i) on the i -th cusp.

See [3, App. B] for a proof, for instance.

In his proof of hyperbolic Dehn filling, Thurston shows that there is a diffeomorphism between U and a neighborhood of ∞ in $(\mathbf{R}^2 \cup \{\infty\})^k$ that maps componentwise 0 to ∞ and $u_i \neq 0$ to $(p_i, q_i) \in \mathbf{R}^2$ satisfying $p_i u_i + q_i v_i = 2\pi \mathbf{i}$.

The geometric interpretation of generalized Dehn filling coefficients is the following one:

- (i) When $p_i, q_i \in \mathbf{Z}$ are coprime, then the completion for ρ_u is precisely the Dehn filling with slope $p_i\mu_i + q_i\lambda_i$.
- (ii) When $p_i/q_i = p'_i/q'_i \in \mathbf{Q} \cup \infty$ with $p'_i, q'_i \in \mathbf{Z}$ coprime, then the completion for ρ_u is a cone manifold, obtained by Dehn filling with slope $p'_i\mu_i + q'_i\lambda_i$ where the core of the torus is a singular geodesic with cone angle $2\pi p'_i/p_i$.
- (iii) When $p_i/q_i \in \mathbf{R} \setminus \mathbf{Q}$, then the metric completion is the one point compactification.

A particular case that we will use later is when $u_i = \alpha_i \mathbf{i}$ for some $\alpha_i \in \mathbf{R}$, $\alpha_i > 0$. Then $p_i = 2\pi/\alpha_i$ and $q_i = 0$, and $\rho_{(\mathbf{i}\alpha_1, \dots, \mathbf{i}\alpha_k)}$ is the holonomy of a hyperbolic cone manifold with cone angles $(\alpha_1, \dots, \alpha_k)$.

The real analytic structure will be crucial in our arguments. When viewed in $PSL_2(\mathbf{C})$, ρ_u is complex analytic, but we will work with the real analytic structure, which is the same as for $PSO(3, 1)$. In particular the following lemma will be usefull.

2.2 Lemma *For each $i = 1, \dots, k$, if $\tau_i(u) = v_i(u)/u_i$, then the map*

$$\begin{aligned} U \subset \mathbf{C}^k &\rightarrow \mathbf{R}^2 \\ u &\mapsto \frac{1}{|p_i + q_i\tau_i|^2}(p_i, q_i) \end{aligned}$$

is real analytic.

Proof. Using Equation (2), we obtain:

$$p_i = -2\pi \frac{\operatorname{Re}(u_i\tau_i)}{|u_i|^2 \operatorname{Im}(\tau_i)}, \quad q_i = 2\pi \frac{\operatorname{Re}(u_i)}{|u_i|^2 \operatorname{Im}(\tau_i)}, \quad p_i + q_i\tau_i = \frac{2\pi\mathbf{i}}{u_i}.$$

The lemma is an straightforward consequence from these equalities and the fact that the imaginary part of $\tau_i(0)$ does not vanish. \square

3 Infinitesimal deformations

The matrix of the Lorentzian inner product is denoted by

$$J = \begin{pmatrix} 1 & & & \\ & 1 & & \\ & & 1 & \\ & & & -1 \end{pmatrix}.$$

So that

$$O(3, 1) = \{A \in GL(4) \mid A^t J A = J\},$$

and the connected component of the identity of its projectivization $PSO(3, 1)$ is the group of orientation preserving isometries of \mathbf{H}^3 . Its Lie algebra is

$$\mathfrak{so}(3, 1) = \{a \in \mathfrak{sl}(4) \mid a^t J = -Ja\}.$$

Following Johnson and Millson [14], along the paper we shall use the decomposition of $\mathfrak{sl}(4)$ as direct sum of $PSO(3, 1)$ -modules via the adjoint action:

$$\mathfrak{sl}(4) = \mathfrak{so}(3, 1) \oplus \mathfrak{v}, \quad (3)$$

where

$$\mathfrak{v} = \{a \in \mathfrak{sl}(4) \mid a^t J = Ja\}.$$

Notice that \mathfrak{v} is not a Lie algebra, but just a $PSO(3, 1)$ -module.

Hence given a representation $\rho: \pi_1(M) \rightarrow PSO(3, 1)$ we obtain a *canonical splitting* in homology:

$$H^*(M; \mathfrak{sl}(4)_{\text{Ad } \rho}) = H^*(M; \mathfrak{so}(3, 1)_{\text{Ad } \rho}) \oplus H^*(M; \mathfrak{v}_{\text{Ad } \rho}).$$

In the remaining of the section, we shall recall the known results about the cohomology group $H^1(M; \mathfrak{so}(3, 1)_{\text{Ad } \rho})$ (Subsection 3.1) and provide some properties of $H^*(M; \mathfrak{v}_{\text{Ad } \rho})$.

3.1 Infinitesimal deformations in real hyperbolic space

Infinitesimal deformations in $\text{Isom}^+(\mathbf{H}) = PSO(3, 1)$ are well understood, and described by $H^1(M; \mathfrak{so}(3, 1)_{\text{Ad } \rho})$. We summarize here the main results:

3.1 Proposition *Let M be a finite volume hyperbolic 3-manifold with k cusps and let U be as in Theorem 2.1. For all $u \in U$:*

(i) *The inclusion $\partial M \subset M$ induces a monomorphism*

$$0 \rightarrow H^1(M; \mathfrak{so}(3, 1)_{\text{Ad } \rho_u}) \rightarrow H^1(\partial M; \mathfrak{so}(3, 1)_{\text{Ad } \rho_u}).$$

(ii) *If we choose one essential simple closed curve $\mu_i \subset \partial_i M$ for each boundary component, then the inclusion of the union $\mu = \mu_1 \cup \dots \cup \mu_k \subset M$ induces a monomorphism*

$$0 \rightarrow H^1(M; \mathfrak{so}(3, 1)_{\text{Ad } \rho_u}) \rightarrow H^1(\mu; \mathfrak{so}(3, 1)_{\text{Ad } \rho_u}).$$

(iii) $\dim H^1(M; \mathfrak{so}(3, 1)_{\text{Ad } \rho_u}) = 2k$.

(iv) $\dim H^1(M, \mu; \mathfrak{so}(3, 1)_{\text{Ad } \rho_u}) = 2k$.

This proposition can be seen as the algebraic part of Thurston's hyperbolic Dehn filling theorem. When $\partial M = \emptyset$ it is due to Weil [26], and when $\partial M \neq \emptyset$, it is Garland rigidity [10]. See [16] or [10] for a proof.

3.2 Killing form, cup product and Kronecker pairing in \mathfrak{v}

The *Killing form* on any Lie algebra \mathfrak{g} is defined as:

$$B(X, Y) = \text{trace}(ad_X \circ ad_Y) \quad \forall X, Y \in \mathfrak{g},$$

where $ad_X \in \text{End}(\mathfrak{g})$ denotes the endomorphism given by $ad_X(Y) = [X, Y]$. If $\mathfrak{g} = \mathfrak{sl}(4)$, then $B(X, Y) = 8 \text{tr}(X \cdot Y)$.

Both the form B on $\mathfrak{sl}(4)$ and its restriction to $\mathfrak{so}(3, 1)$ are nondegenerate. Moreover \mathfrak{v} is the orthogonal complement to $\mathfrak{so}(3, 1)$:

$$\mathfrak{sl}(4) = \mathfrak{so}(3, 1) \perp \mathfrak{v}.$$

Therefore B restricted to \mathfrak{v} is nondegenerate

A *cup product* on cohomology is defined by using B :

$$H^p(M; \mathfrak{v}) \otimes H^q(M, \partial M; \mathfrak{v}) \xrightarrow{\cup} H^{p+q}(M, \partial M; \mathfrak{v} \otimes \mathfrak{v}) \xrightarrow{B_*} H^{p+q}(M, \partial M; \mathbf{R}) \quad (4)$$

where the first arrow is the usual cup product, and B_* denotes the map induced by $B: \mathfrak{v} \otimes \mathfrak{v} \rightarrow \mathbf{R}$. Since we do not use any other cup product, this one will be simply denoted by \cup . This cup product induces *Poincaré duality* since B is non degenerated, cf. [14]. As B is symmetric, this cup product is symmetric or antisymmetric depending on whether the product of dimensions pq is even or odd, as the usual cup product.

The Killing form is also used to define a *Kronecker pairing* between homology and cohomology. Consider $C_*(\widetilde{M})$ the group of chains of the universal covering, with the action of $\pi_1(M)$. The chain group is the tensor product $\mathfrak{v} \otimes_{\pi_1 M} C_*(\widetilde{M})$, so that a cycle is an element $\sum v_i \otimes c_i$, $c_i \in C_*(\widetilde{M})$ and $v_i \in \mathfrak{v}$. Moreover the cochain group is the set of morphisms $\text{Hom}_{\pi_1 M}(C_*(\widetilde{M}); \mathfrak{v})$, and a cocycle is a morphism of $\pi_1 M$ -modules, $\theta: C_*(\widetilde{M}) \rightarrow \mathfrak{v}$. Then the Kronecker pairing is given by:

$$\begin{array}{ccc} H^p(M; \mathfrak{v}) & \times & H_p(M; \mathfrak{v}) & \rightarrow & \mathbf{R} \\ [\theta] & & [\sum_i v_i \otimes c_i] & \mapsto & \sum_i B(\theta(c_i), v_i). \end{array} \quad (5)$$

This pairing gives duality between homology and cohomology.

3.3 Complex hyperbolic space

Consider $\mathbf{C}^{3,1}$ i.e. \mathbf{C}^4 with the hermitian product

$$\langle w, z \rangle = w_1 \bar{z}_1 + w_2 \bar{z}_2 + w_3 \bar{z}_3 - w_4 \bar{z}_4 = w^t J \bar{z} = z^* w$$

where $z^* = \bar{z}^t J$. Its projectivization $\mathbf{P}^{3,1} := \mathbf{P}(\mathbf{C}^{3,1})$ gives rise to complex hyperbolic space $\mathbf{H}_{\mathbf{C}}^3$. More precisely, $\mathbf{H}_{\mathbf{C}}^3 = \{[v] \in \mathbf{P}^{3,1} \mid \langle v, v \rangle < 0\}$ cf. [11, 9]. Here and in the sequel $[v]$ denotes the line generated by the non zero vector $v \in \mathbf{C}^{3,1}$.

Let

$$SU(3, 1) = \{A \in SL(4, \mathbf{C}) \mid \bar{A}^t J A = J\}.$$

The group of holomorphic isometries of complex hyperbolic space is its projectivization $PSU(3, 1) = PU(3, 1)$, with Lie algebra:

$$\mathfrak{su}(3, 1) = \{a \in \mathfrak{sl}(4, \mathbf{C}) \mid \bar{a}^t J = -J a\}.$$

The key point is that, as $SO(3, 1)$ -module, this Lie algebra has a decomposition:

$$\mathfrak{su}(3, 1) = \mathfrak{so}(3, 1) \perp \mathfrak{iv}. \quad (6)$$

Thus:

3.2 Remark The subspace $\mathfrak{v} = \{a \in \mathfrak{sl}(4) \mid a^t J = J a\}$ can be seen as the imaginary part of infinitesimal deformations in complex hyperbolic space.

Proof of Theorem 1.10. Equation (6) holds true in any dimension, and, since it is an isomorphism of $PSO(n, 1)$ -modules, it gives an isomorphism in cohomology:

$$\begin{aligned} H^1(M; \mathfrak{sl}(n+1)) &= H^1(M; \mathfrak{so}(n, 1)) \oplus H^1(M; \mathfrak{v}) \cong \\ &H^1(M; \mathfrak{so}(n, 1)) \oplus H^1(M; \mathfrak{iv}) = H^1(M; \mathfrak{su}(n, 1)). \end{aligned}$$

Using this isomorphism, the proof follows. \square

We will use Remark 3.2 and Equation (6) to understand the computations for the cohomology with coefficients in \mathfrak{v} in a Riemannian setting.

In order to understand the Killing form on $\mathfrak{su}(3, 1)$ we follow the exposition of Goldman [11, 4.1.3]. Let

$$v_+ = \begin{pmatrix} 0 \\ 0 \\ 1 \\ 1 \end{pmatrix} \quad \text{and} \quad v_- = \begin{pmatrix} 0 \\ 0 \\ -1 \\ 1 \end{pmatrix}$$

be two null vectors in $\mathbf{C}^{3,1}$ representing two distinct boundary points of $\mathbf{H}_{\mathbf{C}}^3$. Then the element

$$\eta := -\frac{1}{2}(v_+ v_-^* - v_- v_+^*) = \begin{pmatrix} 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 \\ 0 & 0 & 1 & 0 \end{pmatrix}$$

is the infinitesimal generator of a 1-parameter subgroup of isometries fixing the points $[v_{\pm}] \in \partial\mathbf{H}_{\mathbf{C}}^3$ and translating along the geodesic between $[v_+]$ and $[v_-]$.

Decompose the Lie algebra $\mathfrak{su}(3, 1)$ into eigenspaces

$$\mathfrak{g}_k = \text{Ker}(\text{ad}_\eta - k\mathbf{I})$$

of ad_η . The eigenspace \mathfrak{g}_k is nonzero only for $k \in \{0, \pm 1, \pm 2\}$. More explicitly we have:

$$\mathfrak{g}_0 = \left\{ \begin{pmatrix} a & 0 & 0 \\ 0 & -\frac{\text{tr}(a)}{2} & t \\ 0 & t & -\frac{\text{tr}(a)}{2} \end{pmatrix} \middle| a \in \mathfrak{u}(2), t \in \mathbf{R} \right\},$$

$\mathfrak{g}_{\pm 1} = \{vv_\pm^* - v_\pm v^* \mid v \in V(v_\pm)^\perp\}$ and $\mathfrak{g}_{\pm 2} = \{isv_\pm v_\pm^* \mid s \in \mathbf{R}\}$ where $V(v_\pm)$ denotes the vector space generated by v_+ and v_- . Note that $V(v_\pm)$ the positive two-dimensional complex subspace of $\mathbf{C}^{3,1}$ given by $z_3 = z_4 = 0$. As usual we have $[\mathfrak{g}_k, \mathfrak{g}_l] \subset \mathfrak{g}_{k+l}$ with the convention that $\mathfrak{g}_{k+l} = 0$ if $|k+l| > 2$. This tells us immediately that \mathfrak{g}_k is orthogonal with respect to the Killing form to \mathfrak{g}_l for all $k \neq -l$.

Now let $G_\pm \subset PSU(3, 1)$ denote the stabilizer of the point $[v_\pm] \in \partial\mathbf{H}_\mathbf{C}^3$. The Lie algebra \mathfrak{g}_\pm of G_\pm is given by

$$\mathfrak{g}_\pm = \mathfrak{g}_0 \oplus \mathfrak{g}_{\pm 1} \oplus \mathfrak{g}_{\pm 2}.$$

Note also that $\mathfrak{h}_\pm = \mathfrak{g}_{\pm 1} \oplus \mathfrak{g}_{\pm 2}$ is the Lie algebra of parabolic transformations fixing the point $[v_\pm]$.

As a consequence of this discussion we obtain the following lemma.

3.3 Lemma *The Killing form of $\mathfrak{su}(3, 1)$ restricted to \mathfrak{g}_\pm is degenerated. More precisely, the radical $\text{rad}(\mathfrak{g}_\pm) = \mathfrak{g}_\pm \cap \mathfrak{g}_\pm^\perp = \mathfrak{h}_\pm$ consist exactly the infinitesimal parabolic transformations.*

Proof. Let us consider the sign $+$ the other case is analogous. We have

$$\mathfrak{g}_0^\perp = \mathfrak{h}_+ \oplus \mathfrak{h}_-, \quad \mathfrak{g}_1^\perp = \mathfrak{g}_0 \oplus \mathfrak{h}_+ \oplus \mathfrak{g}_{-2} \text{ and } \mathfrak{g}_2^\perp = \mathfrak{g}_0 \oplus \mathfrak{h}_+ \oplus \mathfrak{g}_{-1}.$$

This follows since \mathfrak{g}_k is orthogonal with respect to the Killing form to \mathfrak{g}_l for all $k \neq -l$. Hence $\mathfrak{g}_+ \cap \mathfrak{g}_+^\perp = \mathfrak{g}_+ \cap \mathfrak{g}_0^\perp \cap \mathfrak{g}_1^\perp \cap \mathfrak{g}_2^\perp = \mathfrak{h}_+ = \mathfrak{g}_1 \oplus \mathfrak{g}_2$. \square

4 Invariant subspaces in complex hyperbolic geometry

In this section we shall compute subspaces of the module \mathfrak{v} that are invariant by certain elements of $PSO(3, 1)$. This will be used later when computing cohomology. For a set of hyperbolic isometries $\Gamma \subset PSO(3, 1)$, we shall compute the invariant subspace in \mathfrak{v} :

$$\mathfrak{v}^\Gamma = \{v \in \mathfrak{v} \mid \text{Ad}_\gamma(v) = v, \forall \gamma \in \Gamma\}.$$

For our computations, we will view elements in \mathfrak{v} as lying in \mathfrak{iv} , namely as infinitesimal isometries of $\mathbf{H}_{\mathbb{C}}^3$. We also use the following lemma (see [4, III.9.3] for a proof).

4.1 Lemma *For $\gamma \in PSU(3, 1)$, $\mathfrak{su}(3, 1)^\gamma = \text{Ker}(\text{Ad}_\gamma - \mathbf{1})$ is the Lie algebra of the centralizer of γ (i.e. the Lie subgroup of elements in $PSU(3, 1)$ that commute with γ).*

Alternatively, the computation of invariant subspaces could also be made with the analogue of Lemma 4.1 for $GL(4)$ or just by explicit computation of the adjoint action on \mathfrak{v} .

The centralizer of an element is obtained by means of the stabilizer of an invariant object in $\mathbf{H}_{\mathbb{C}}^3 \cup \partial\mathbf{H}_{\mathbb{C}}^3$. This explains the organization of this section, one subsection for each object.

4.1 Geodesics.

Consider the Riemannian geodesic γ in $\mathbf{H}_{\mathbb{C}}^3$ between $[v_+]$ and $[v_-]$. Let $\mathfrak{g}_0 \subset \mathfrak{su}(3, 1)$ denote the Lie algebra of the subgroup $G_0 \subset PSU(3, 1)$ which fixes the endpoints of the geodesic γ (see [11, 4.1.3]).

4.2 Lemma *Let $A \in PSO(3, 1)$ be a hyperbolic element of complex length $l + \mathbf{i}\alpha$, $l \neq 0$.*

(i) *If $\alpha \notin \pi\mathbf{Z}$, then $\dim \mathfrak{v}^A = 1$.*

(ii) *If $\alpha \in \pi\mathbf{Z}$, then $\dim \mathfrak{v}^A = 3$.*

Proof. We let γ denote the axis of A . After conjugation we might assume that γ is the geodesic between $[v_+]$ and $[v_-]$ and hence

$$A = \begin{pmatrix} \cos \alpha & -\sin \alpha & 0 & 0 \\ \sin \alpha & \cos \alpha & 0 & 0 \\ 0 & 0 & \cosh l & \sinh l \\ 0 & 0 & \sinh l & \cosh l \end{pmatrix}.$$

If $\alpha = \pi$, then A commutes with the whole stabilizer G_0 . Moreover, the subgroup of $PSO(3, 1)$ preserving γ is isomorphic to $P(O(2) \times O(1, 1))$. Thus

$$\begin{aligned} \dim \mathfrak{v}^A &= \dim(\mathfrak{g}_0) - \dim(\mathfrak{so}(2) \oplus \mathfrak{so}(1, 1)) \\ &= 5 - 2 = 3. \end{aligned}$$

If $\alpha \neq \pi$, then the Lie algebra of the centralizer of A in $\mathfrak{su}(3, 1)$ is three-dimensional and therefore

$$\dim \mathfrak{v}^A = 3 - 2 = 1.$$

□

4.2 Complex hyperbolic lines

Complex hyperbolic space is the projectivization of the subset of the time-like vectors of $\mathbf{C}^{3,1}$. A *complex hyperbolic line* is defined as the intersection of $\mathbf{H}_{\mathbf{C}}^3$ with a complex projective line. The group $SU(3,1)$ acts transitively on the complex planes that contain time-like vectors. Hence all complex hyperbolic lines are all isomorphic to $\mathbf{H}_{\mathbf{C}}^1$, and a standard model for a complex hyperbolic line is the image of the plane given by $x_1 = x_2 = 0$.

The intersection of a complex hyperbolic line with $\partial\mathbf{H}_{\mathbf{C}}^3$ is a smooth circle called a *chain*. Two distinct boundary points of $\mathbf{H}_{\mathbf{C}}^3$ are contained in a unique chain and the Riemannian geodesic between the two boundary points is contained in the corresponding complex hyperbolic line.

The identity component of the stabilizer of a chain is given by $P(U(2) \times U(1,1)) \subset PSU(3,1)$.

4.3 Lemma *Let $A \in PSO(3,1)$ be an elliptic element of rotation angle $\alpha \in (0, 2\pi)$.*

(i) *If $\alpha = \pi$, then $\dim \mathfrak{v}^A = 5$.*

(ii) *If $\alpha \neq \pi$, then $\dim \mathfrak{v}^A = 3$.*

Proof. The fixed point set of A is a complex line, whose stabilizer is $P(U(2) \times U(1,1))$.

If $\alpha = \pi$ then A commutes with all elements in this stabilizer. As the stabilizer of a geodesic in $PSO(3,1)$ is two dimensional ($SO(2) \times \mathbf{R}$) we obtain:

$$\begin{aligned} \dim \mathfrak{v}^A &= \dim((\mathfrak{u}(1,1) \oplus \mathfrak{u}(2)) - 1 - \dim(\mathfrak{so}(2) \oplus \mathbf{R})) \\ &= \dim \mathfrak{u}(1,1) + \dim \mathfrak{u}(2) - 3 = 4 + 4 - 3 = 5. \end{aligned}$$

When $\alpha \neq \pi$, then the centralizer of A is the projectivization of

$$\left\{ \begin{pmatrix} \zeta C & 0 \\ 0 & B \end{pmatrix} \mid C \in SO(2), \zeta \in U(1), B \in U(1,1) \right\}$$

and therefore

$$\begin{aligned} \dim \mathfrak{v}^A &= \dim(\mathfrak{u}(1,1) \oplus \mathfrak{so}(2)) - 2 \\ &= 4 + 1 - 2 = 3. \end{aligned}$$

□

4.3 Parabolics and Heisenberg geometry

In the sequel we will use the notation of Section 3.3, i.e we will fix two light-like vectors $v_{\pm} \in \mathbf{C}^{3,1}$ representing two distinct boundary points $[v_{\pm}] \in \partial\mathbf{H}_{\mathbf{C}}^3$. Moreover we will use the root-space decomposition of $\mathfrak{su}(3,1)$. The Heisenberg group \mathcal{H}_- is the group of parabolic transformations fixing the point $[v_-]$, i.e. $\exp: \mathfrak{g}_{-1} \oplus \mathfrak{g}_{-2} \rightarrow \mathcal{H}_-$ is given by

$$\begin{aligned} & \exp(v_- v^* - v v_-^* + \mathbf{i} t v_- v_-^*) \\ &= I_4 + v_- v^* - v v_-^* - (\|v\|^2/2 - \mathbf{i}t)v_- v_-^* \\ &= \begin{pmatrix} 1 & 0 & z_1 & z_1 \\ 0 & 1 & z_2 & z_2 \\ -\bar{z}_1 & -\bar{z}_2 & 1 - \|v\|^2/2 + \mathbf{i}t & -\|v\|^2/2 + \mathbf{i}t \\ \bar{z}_1 & \bar{z}_2 & \|v\|^2/2 - \mathbf{i}t & 1 + \|v\|^2/2 - \mathbf{i}t \end{pmatrix} \\ &=: H(z_1, z_2, t) \end{aligned} \quad (7)$$

where $v = (z_1, z_2, 0, 0)^t \in v_{\pm}^{\perp} \cap v_{\pm}^{\perp}$ is a space-like vector and hence $\langle v, v \rangle = \|v\|^2 = |z_1|^2 + |z_2|^2 \geq 0$.

Following the exposition in Goldman's book [11, 4.2], the boundary at infinity of $\mathbf{H}_{\mathbf{C}}^3$ minus the point $[v_-]$ can be identified with a *Heisenberg space*, i.e. a space equipped with a simply transitive left action of the Heisenberg group \mathcal{H}_- . Hence by looking at the orbit of $[v_+]$ we have a bijection $\mathcal{H}_- \rightarrow \partial\mathbf{H}_{\mathbf{C}}^3 \setminus \{[v_-]\}$ given by

$$H(z_1, z_2, t) \mapsto H(z_1, z_2, t)[v_+] = \begin{bmatrix} 2z_1 \\ 2z_2 \\ 1 - \|z\|^2 + 2\mathbf{i}t \\ 1 + \|z\|^2 - 2\mathbf{i}t \end{bmatrix}$$

where $\|z\|^2 = |z_1|^2 + |z_2|^2$.

In the sequel we shall represent points of \mathcal{H}_- by triples of points (z_1, z_2, t) where $z_1, z_2 \in \mathbf{C}$, $t \in \mathbf{R}$ with multiplication

$$\begin{aligned} (\omega_1, \omega_2, s) \cdot (z_1, z_2, t) &= (\omega_1 + z_1, \omega_2 + z_2, s + t + \text{Im}(\omega_1 \bar{z}_1 + \omega_2 \bar{z}_2)) \\ &\quad \forall (\omega_1, \omega_2, s), (z_1, z_2, t) \in \mathcal{H} \end{aligned} \quad (8)$$

Therefore, \mathcal{H}_- is a nilpotent 5-dimensional real Lie group, which is a non-trivial central extension

$$0 \rightarrow \mathbf{R} \rightarrow \mathcal{H}_- \rightarrow \mathbf{C}^2 \rightarrow 0.$$

The center are the elements of the form $(0, 0, t)$, $t \in \mathbf{R}$.

In the sequel we will make use of the *Siegel domain model* \mathfrak{H}^3 of $\mathbf{H}_{\mathbf{C}}^3$. Here

$$\mathfrak{H}^3 = \left\{ w = \begin{pmatrix} w_1 \\ w_2 \\ w_3 \end{pmatrix} \in \mathbf{C}^3 \mid |w_1|^2 + |w_2|^2 < 2\Re(w_3) \right\}$$

is obtained in the following way: we choose the point $[v_-] \in \partial\mathbf{H}_{\mathbf{C}}^3$ and we denote by $H \subset \mathbf{P}^{3,1}$ the projective hyperplane tangent to $\partial\mathbf{H}_{\mathbf{C}}^3$ at $[v_-]$. More precisely, H is the projectivization of $v_-^\perp \subset \mathbf{C}^{3,1}$ given by the equation $z_3 + z_4 = 0$. The corresponding affine embedding $\mathbf{C}^3 \rightarrow \mathbf{CP}^3 \setminus H$ is given by

$$\begin{pmatrix} w_1 \\ w_2 \\ w_3 \end{pmatrix} \mapsto \begin{bmatrix} w_1 \\ w_2 \\ 1/2 - w_3 \\ 1/2 + w_3 \end{bmatrix}.$$

It is easy to see that $\mathbf{H}_{\mathbf{C}}^3$ correspond to the Siegel domain $\mathfrak{H}^3 \subset \mathbf{C}^3$. In this model the whole stabilizer G_- of the point $[v_-]$ at infinity is the semidirect product:

$$G_- = \mathcal{H}_- \rtimes (U(2) \times \mathbf{R}).$$

Here $U(2)$ acts linearly on the factor \mathbf{C}^2 , and trivially on the factor \mathbf{R} . Moreover \mathbf{R} acts as follows:

$$(I_2, \lambda)(z_1, z_2, t)(I_2, -\lambda) = (e^{-\lambda}z_1, e^{-\lambda}z_2, e^{-2\lambda}t), \quad \forall \lambda \in \mathbf{R}, \quad \forall (z_1, z_2, t) \in \mathcal{H}.$$

In this construction, the subgroup of real parabolic transformations corresponds to $\mathbf{R}^2 \times \{0\} \subset \mathcal{H}_-$.

4.4 Lemma (i) *If A is a nontrivial parabolic element of $PSO(3, 1)$, then $\dim \mathfrak{v}^A = 3$.*

(ii) *If $\Gamma < PSO(3, 1)$ is a rank 2 parabolic subgroup, then $\dim \mathfrak{v}^\Gamma = 1$.*

Proof. Using the representation in the Heisenberg group \mathcal{H}_- , we may assume that up to conjugation A is $(1, 0, 0) \in \mathcal{H}_-$. Note that the centralizer of A is contained in G_- . This follows from the fact that A has a unique fixed point on $\overline{\mathbf{H}_{\mathbf{C}}^3}$ and every element which commutes with A has to fix this point.

Now a direct calculation gives that the centralizer of A in G_- is 5-dimensional and given by

$$\left\{ (s, z, t) \begin{pmatrix} 1 & 0 \\ 0 & a \end{pmatrix} \in G_- \mid s, t \in \mathbf{R}, z \in \mathbf{C} \text{ and } a \in U(1) \right\}.$$

Thus $\dim(\mathfrak{su}(3, 1)^A) = 5$, and since $\dim(\mathfrak{so}(3, 1))^A = 2$ (the tangent space to the real parabolic group itself), the first assertion follows.

For the last assertion, we view Γ as a rank 2 subgroup of the Heisenberg group

$$\Gamma < \mathbf{R}^2 \times \{0\} < \mathcal{H}_-.$$

Its centralizer is contained in G_- and is precisely the subgroup of elements with real coordinates:

$$\mathbf{R}^3 \cong \{(s_1, s_2, t) \in \mathcal{H}_- \mid s_1, s_2, t \in \mathbf{R}\} < \mathcal{H}_-.$$

As the subgroup of real parabolic transformations $\mathbf{R}^2 \times \{0\}$ is the centralizer in of Γ in $PSO(3,1)$, it follows that $\mathfrak{v}^\Gamma = \{(0,0)\} \times \mathbf{R}$ is one dimensional. \square

5 Cohomology of the torus

In this section, we analyze the cohomology of the boundary ∂M and the image of the map induced by inclusion $\partial M \subset M$, which is a Lagrangian subspace.

5.1 A Lagrangian subspace

As in Section 2, let ρ_u denote a representation contained in Thurston's slice, where $u = (u_1, \dots, u_k) \in U \subset \mathbf{C}^k$ is a point in the deformation space. The subspace invariant by the image of the peripheral subgroup of the i -th component is denoted by $\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}$, and its orthogonal complement by

$$(\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))})^\perp = \{v \in \mathfrak{v} \mid B(v, w) = 0, \forall w \in \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}\}.$$

5.1 Lemma (i) For $u_i \neq 0$, the radical of $\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}$ is trivial, i.e.

$$(\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))})^\perp \cap \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))} = 0.$$

(ii) For every $u \in U$, the invariant subspace $\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}$ has dimension one.

Proof.

When $u_i \neq 0$, $\rho_u(\pi_1(\partial_i M))$ consists of loxodromic and/or elliptic elements that preserve a geodesic, and we want to apply Lemma 4.2 (i). For this, we need an element $\gamma \in \pi_1(\partial_i M)$ such that $\rho_u(\gamma)$ satisfies the hypothesis of Lemma 4.2 (i). If the real part of u_i does not vanish and the imaginary part of u_i is not contained in $\mathbf{Z}\pi$ then we choose μ_i . If the real part of u_i vanishes, by Theorem 2.1 the real part of v_i does not, and the condition on the complex length applies to either λ_i or $\lambda_i \mu_i$, that have respective complex lengths v_i and $u_i + v_i$. The same argument applies when the imaginary part of u_i is zero.

By Lemma 4.2 (i) and its proof, $\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}$ is the one dimensional subspace generated by (a conjugate of)

$$\begin{pmatrix} 1 & & & \\ & 1 & & \\ & & -1 & \\ & & & -1 \end{pmatrix},$$

and both assertions of the lemma are clear when $u_i \neq 0$.

When $u_i = 0$, assertion (ii) is Lemma 4.4 (ii). \square

Note that the cup product on $H^1(\partial M; \mathfrak{v})$ is the orthogonal sum of the cup products on the groups $H^1(\partial_i M; \mathfrak{v})$. More precisely, if we denote by $res_i: H^1(\partial M; \mathfrak{v}) \rightarrow H^1(\partial_i M; \mathfrak{v})$ the restriction induced by the inclusion $\partial_i M \hookrightarrow \partial M$ then for $z_1, z_2 \in H^1(\partial M; \mathfrak{v})$ we have

$$z_1 \cup z_2 = \sum_{i=1}^k res_i(z_1) \cup res_i(z_2). \quad (9)$$

5.2 Lemma *Let $u = (u_1, \dots, u_k) \in U$.*

(i) *When $u_i \neq 0$, there is a natural isomorphism*

$$H^*(\partial_i M; \mathfrak{v}_{Ad \rho_u}) \cong H^*(\partial_i M; \mathbf{R}) \otimes \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}.$$

(ii) *For $u \in U$, $\dim H^1(\partial M; \mathfrak{v}_{Ad \rho_u}) = 2k$, and the image*

$$\text{Im}(H^1(M; \mathfrak{v}_{Ad \rho_u}) \rightarrow H^1(\partial M; \mathfrak{v}_{Ad \rho_u}))$$

is a Lagrangian subspace of $H^1(\partial M; \mathfrak{v}_{Ad \rho_u})$ for the cup product (in particular it has dimension k).

Proof. To prove assertion (i), we use the decomposition of Lemma 5.1:

$$\mathfrak{v} = (\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))})^\perp \oplus \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))},$$

which is a direct sum of $\pi_1(\partial M)$ -modules, and therefore it induces a direct sum in cohomology. Since $(\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))})^\perp$ has no invariant subspaces,

$$H^0(\partial_i M, (\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))})^\perp) = 0.$$

In addition, the Killing form restricted to $(\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))})^\perp$ is non-degenerate, thus by duality and by vanishing of the Euler characteristic

$$H^*(\partial_i M, (\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))})^\perp) = 0.$$

Hence

$$H^*(\partial_i M; \mathfrak{v}) = H^*(\partial_i M; \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}) \cong H^*(\partial_i M; \mathbf{R}) \otimes \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}.$$

The proof of assertion (ii) is a standard application of duality, that we reproduce for completeness (cf. [12]). We are interested in the following part of the exact cohomology sequence of the pair $(M, \partial M)$:

$$H^1(M; \mathfrak{v}) \xrightarrow{j^*} H^1(\partial M; \mathfrak{v}) \xrightarrow{\Delta} H^2(M, \partial M; \mathfrak{v}).$$

The maps j^* and Δ are dual to each other and it follows that $\dim \text{Im}(j^*) = 1/2 \dim H^1(\partial M; \mathfrak{v}) = k$. Moreover for $z_1 \in H^1(M; \mathfrak{v})$ and $z_2 \in H^1(\partial M; \mathfrak{v})$ we have

$$\langle j^*(z_1) \cup z_2, [\partial M] \rangle = \langle z_1 \cup \Delta(z_2), [M, \partial M] \rangle$$

where $[M, \partial M] \in H_3(M, \partial M; \mathbf{R})$ and $[\partial M] \in H_2(\partial M; \mathbf{R})$ denote the respective fundamental classes.

Now $\Delta \circ j^* = 0$ implies that $\text{Im}(j^*)$ is isotropic and hence Lagrangian since $\dim \text{Im}(j^*) = k$. \square

5.3 Corollary *Let M be a cusped manifold, then $\dim H^1(M; \mathfrak{v}_{\text{Ad } \rho_u}) \geq k$, $\forall u \in U \subset \mathbf{C}^k$.*

Moreover M is infinitesimally projectively rigid iff $\dim H^1(M; \mathfrak{v}_{\text{Ad } \rho_0}) = k$.

Proof. Follows directly from Lemma 5.2 and from the decomposition $\mathfrak{sl}(4) = \mathfrak{so}(3, 1) \oplus \mathfrak{v}(3)$. \square

5.2 Parabolic representations

Let λ and μ be two generators of \mathbf{Z}^2 and

$$\varrho: \mathbf{Z}^2 \rightarrow PSO(3, 1)$$

a representation into a parabolic group. Up to conjugation we suppose that the boundary point $[v_-]$ is the fixed point of the parabolic group. Viewing the parabolic group as translations of \mathbf{R}^2 , $\varrho(\lambda)$ is a translation of vector v_λ , and $\varrho(\mu)$ of vector v_μ . Assume that the representation has rank 2, (i.e. v_λ and v_μ are linearly independent). Then:

5.4 Lemma *If the angle φ between v_λ and v_μ is not in $\frac{\pi}{3}\mathbf{Z}$ then the map induced by restrictions*

$$H^1(\mathbf{Z}^2; \mathfrak{v}_{\text{Ad } \varrho}) \xrightarrow{i_\lambda^* \oplus i_\mu^*} H^1(\lambda; \mathfrak{v}_{\text{Ad } \varrho}) \oplus H^1(\mu; \mathfrak{v}_{\text{Ad } \varrho})$$

is injective. Moreover, $\text{rank}(i_\lambda^) = \text{rank}(i_\mu^*) = 1$.*

Proof. We follow the notation from Subsection 4.3. We may assume that $v_\lambda = (1, 0)$, $v_\mu = (a \cos \varphi, a \sin \varphi) \in \mathbf{R}^2$, $a \sin \varphi \neq 0$. In the Heisenberg model \mathcal{H}_- , $\varrho(\lambda) = (1, 0, 0)$ and $\varrho(\mu) = (a \cos \varphi, a \sin \varphi, 0)$. For $\theta \in \mathbf{R}$, we define a representation $\varrho_\theta: \mathbf{Z} \oplus \mathbf{Z} \rightarrow G_-$ by

$$\varrho_\theta(\lambda) = \varrho(\lambda) \text{ and } \varrho_\theta(\mu) = \varrho(\mu) \begin{pmatrix} 1 & 0 \\ 0 & e^{i\theta} \end{pmatrix}.$$

Notice that $\varrho_\theta(\lambda)$ and $\varrho_\theta(\mu)$ commute, because $\begin{pmatrix} 1 & 0 \\ 0 & e^{i\theta} \end{pmatrix}$ fixes $(1, 0)$.

Differentiating at $\theta = 0$, we obtain an infinitesimal deformation i.e. a cocycle $d_\mu: \mathbf{Z}^2 \rightarrow \mathfrak{g}_- = \mathfrak{g}_0 \oplus \mathfrak{g}_{-1} \oplus \mathfrak{g}_{-2}$ given by

$$d_\mu(\gamma) = \left. \frac{d\varrho_\theta(\gamma)}{d\theta} \right|_{\theta=0} \varrho_0(\gamma)^{-1}.$$

The cocycle $d_\mu: \mathbf{Z}^2 \rightarrow \mathfrak{g}_-$ is trivial when restricted to λ . More precisely we obtain

$$d_\mu(\lambda) = 0 \text{ and } d_\mu(\mu) = \begin{pmatrix} 0 & 0 \\ 0 & \mathbf{i} \end{pmatrix}.$$

Notice that the derivative of the canonical embedding $U(2) \rightarrow PSU(3, 1)$ determinate by,

$$A \mapsto \begin{pmatrix} A & 0 \\ 0 & I_2 \end{pmatrix}$$

is the map $\mathfrak{u}(2) \rightarrow \mathfrak{su}(3, 1)$ given by

$$a \mapsto \begin{pmatrix} a & 0 \\ 0 & 0 \end{pmatrix} - \frac{\text{tr } a}{4} I_4$$

and that

$$\begin{pmatrix} 0 & 0 \\ 0 & \mathbf{i} \end{pmatrix} \mapsto \frac{\mathbf{i}}{4} \begin{pmatrix} -1 & & & \\ & 3 & & \\ & & -1 & \\ & & & -1 \end{pmatrix} \in \mathfrak{iv}.$$

Hence we obtain a cocycle $z_\mu: \mathbf{Z}^2 \rightarrow \mathfrak{v}$ given by $z_\mu(\lambda) = 0$ and $z_\mu(\mu) = a_\lambda$ where

$$a_\lambda := \begin{pmatrix} -1 & & & \\ & 3 & & \\ & & -1 & \\ & & & -1 \end{pmatrix} \in \mathfrak{v}.$$

In the same way we obtain a second cocycle $z_\lambda: \mathbf{Z}^2 \rightarrow \mathfrak{v}$ given by $z_\lambda(\lambda) = a_\mu$ and $z_\lambda(\mu) = 0$ where

$$a_\mu = \begin{pmatrix} 1 - 2 \cos(2\varphi) & 2 \sin(2\varphi) & & \\ 2 \sin(2\varphi) & 1 + 2 \cos(2\varphi) & & \\ & & -1 & \\ & & & -1 \end{pmatrix} \in \mathfrak{v}.$$

Here φ is the angle between v_μ and v_λ . The matrix a_μ is the analogue of a_λ , as $\mathbf{i}a_\mu$ is an infinitesimal rotation in the direction perpendicular to v_μ , and of course it is invariant by $\varrho(\mu)$ (it can be obtained by conjugating a_λ by a rotation of angle φ).

We claim that the cocycle z_μ is cohomologically nontrivial when restricted to μ , i.e. nontrivial in $H^1(\mu; \mathfrak{v}_{\text{Ad } \varrho})$. This proves that z_μ is a

nontrivial cocycle, $\text{rank}(i_\mu^*) \geq 1$ and $\text{rank}(i_\lambda^*) \leq 1$. By the symmetry of the generators it follows that z_λ is a nontrivial cocycle, $\text{rank}(i_\mu^*) \leq 1$ and $\text{rank}(i_\lambda^*) \geq 1$. Moreover, since $i_\mu^*(z_\lambda) = 0 = i_\lambda^*(z_\mu)$ it follows that the image of $i_\mu^* \oplus i_\lambda^*$ is 2-dimensional and the assertion of the lemma follows.

To prove the claim, we will use the cup product

$$H^1(\mu; \mathfrak{v}_{\text{Ad } \varrho}) \times H^0(\mu; \mathfrak{v}_{\text{Ad } \varrho}) \rightarrow H^1(\mu; \mathbf{R}) \cong \mathbf{R}$$

associated to the Killing form defined in (4). Recall that $a_\mu \in H^0(\mu; \mathfrak{v}_{\text{Ad } \varrho}) = \mathfrak{v}^{\varrho(\mu)}$ is invariant under the action of μ . The cup product $i_\mu^*(z_\mu) \cup a_\mu$ is represented by the homomorphism $H_1(\mu; \mathbf{R}) \rightarrow \mathbf{R}$ given by

$$\begin{aligned} (i_\mu^*(z_\mu) \cup a_\mu)(\mu) &= B(a_\lambda, a_\mu) = 8 \text{tr}(a_\lambda \cdot a_\mu) \\ &= 32(1 + 2 \cos(2\varphi)) = 128 \left(\cos^2(\varphi) - \frac{1}{4} \right). \end{aligned}$$

This is nonzero by the hypothesis about the angle φ between v_λ and v_μ , hence $i_\mu^*(z_\mu) \cup a_\mu$ is not homologous to zero. \square

Notice that in the proof of Lemma 5.4, instead of the cup product we could have considered the Kronecker pairing between homology and cohomology, and we would have ended up checking the non-vanishing of the same evaluation of the Killing form $B(a_\lambda, a_\mu)$.

Before the next lemma, we still need a claim about symplectic forms on vector spaces.

5.5 Claim Let (V, ω) be a 2-dimensional symplectic subspace. Suppose that $f, g: V \rightarrow \mathbf{R}$ are linear forms which form a basis of the dual space V^* , i.e. $f \oplus g: V \rightarrow \mathbf{R}^2$ is an isomorphism.

Then there exists a constant $c \in \mathbf{R}$, $c \neq 0$, such that, for every $x, y \in V$

$$\omega(x, y) = c(f(x)g(y) - g(x)f(y)).$$

Proof. The proof of this claim is clear since each non degenerated alternating bilinear form on a 2-dimensional vector space is a determinant form, which is unique up to multiplication with a non zero constant. \square

5.6 Lemma *If a subspace $L \subset H^1(\partial M; \mathfrak{v}_{\text{Ad } \rho_0})$ is Lagrangian for the cup product, then there exist simple closed curves $\mu_1 \in \pi_1(\partial_1 M)$, \dots , $\mu_k \in \pi_1(\partial_k M)$ so that the image of L injects in $H^1(\mu_1; \mathfrak{v}_{\text{Ad } \rho_0}) \oplus \dots \oplus H^1(\mu_k; \mathfrak{v}_{\text{Ad } \rho_0})$. Moreover, injectivity fails if we consider only $k - 1$ curves.*

Proof. Along this proof, the action on \mathfrak{v} is the adjoint of the holonomy of the complete structure, so $\text{Ad } \rho$ is omitted from notation. For $j = 1, \dots, k$,

let $res_j: H^1(\partial M; \mathfrak{v}) \rightarrow H^1(\partial_j M; \mathfrak{v})$ denote the map induced by restriction, which is also the projection to the j -th factor of the isomorphism

$$H^1(\partial M; \mathfrak{v}) \cong H^1(\partial_1 M; \mathfrak{v}) \perp \cdots \perp H^1(\partial_k M; \mathfrak{v}).$$

Recall that this is an orthogonal sum for the cup product (9).

We prove the lemma by induction on k . When $k = 1$, it suffices to chose two curves μ_1 and λ_1 in $\partial_1 M$ that satisfy the hypothesis of Lemma 5.4. Hence

$$i_{\mu_1}^* \oplus i_{\lambda_1}^*: H^1(\partial_1 M; \mathfrak{v}) \rightarrow H^1(\mu_1; \mathfrak{v}) \oplus H^1(\lambda_1; \mathfrak{v})$$

is injective. Then for at least one of the curves, say μ_1 , $i_{\mu_1}^*(L) \neq 0$.

For the induction step, we chose the corresponding curves on the k -th component μ_k and λ_k , so that

$$i_{\mu_k}^* \oplus i_{\lambda_k}^*: H^1(\partial_k M; \mathfrak{v}) \rightarrow H^1(\mu_k; \mathfrak{v}) \oplus H^1(\lambda_k; \mathfrak{v})$$

is injective, and assume that $i_{\mu_k}^*(L) \neq 0$.

Let $L' \subset H^1(\partial_1 M; \mathfrak{v}) \perp \cdots \perp H^1(\partial_{k-1} M; \mathfrak{v})$ be the projection to the first $k-1$ factors of the kernel of $i_{\mu_k}^*$ restricted to L ; i.e.

$$L' = (res_1 \oplus \cdots \oplus res_{k-1})(\ker i_{\mu_k}^*|_L)$$

We first check that L' is isotropic. Given $x, y \in L'$, there exist $x_k, y_k \in H^1(\partial_k M; \mathfrak{v})$ such that $(x, x_k), (y, y_k) \in L$ and $i_{\mu_k}^*(x_k) = i_{\mu_k}^*(y_k) = 0$. Thus, by Claim 5.5 and equation (9):

$$0 = (x, x_k) \cup (y, y_k) = x \cup y + c_k(i_{\mu_k}^*(x_k)i_{\lambda_k}^*(y_k) - i_{\lambda_k}^*(x_k)i_{\mu_k}^*(y_k)) = x \cup y.$$

Finally we claim that the dimension of L' is $k-1$. Since $\dim((\ker(i_{\mu_k}^*|_L)) = k-1$, we need to check that $res_1 \oplus \cdots \oplus res_{k-1}$ restricted to $\ker(i_{\mu_k}^*|_L)$ is injective. Let $x \in \ker(res_1) \cap \cdots \cap \ker(res_{k-1}) \cap \ker(i_{\mu_k}^*|_L)$, we want to check that $x = 0$. Notice that $x \in H^1(\partial_k M; \mathfrak{v}) \cap L \cap \ker(i_{\mu_k}^*)$. Choose $y \in L$ such that $i_{\mu_k}^*(y) \neq 0$, this is possible because $i_{\mu_k}^*(L) \neq 0$. Then, using that $x \in H^1(\partial_k M; \mathfrak{v})$, Claim 5.5 and Equation (9),

$$0 = x \cup y = c_k(i_{\mu_k}^*(x)i_{\lambda_k}^*(y) - i_{\lambda_k}^*(x)i_{\mu_k}^*(y)) = -c_k i_{\lambda_k}^*(x)i_{\mu_k}^*(y)$$

for some $c_k \neq 0$. Since $i_{\mu_k}^*(y) \neq 0$, $i_{\lambda_k}^*(x) = 0$. Therefore $x = 0$. \square

6 The function on the deformation space

Recall that M denotes a compact manifold with boundary a union of $k > 0$ tori and hyperbolic interior. The goal of this section is to give a sufficient cohomological condition which guarantees that infinitely many fillings on M are infinitesimally rigid. For this we need several tools for constructing a function on the deformation space. The first one is given by the following lemma. All statements are up to taking a smaller neighborhood of 0, $U \subset \mathbf{C}^k$.

6.1 Lemma As in Section 2, let $U \subset \mathbf{C}^k$ be an open neighborhood of 0 which parametrizes the deformations of the complete holonomy of the interior of M .

1. There exists a nonvanishing element $a_u^i \in \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}$ that varies analytically in U .
2. There exists a family of cohomology classes $\{z_u^1, \dots, z_u^k\}$ that define a basis for the image of $H^1(M; \mathfrak{v}_{\text{Ad } \rho_u}) \rightarrow H^1(\partial M; \mathfrak{v}_{\text{Ad } \rho_u})$ and that varies analytically in u .

6.2 Remark To vary analytically depends on the construction we take for cohomology, but we always think of an analytic map on a finite dimensional space of cocycles, either in simplicial cohomology (fixing a triangulation and varying the bundle) or in group cohomology (fixing a generating set for the fundamental group).

Proof. The first assertion follows directly from Lemma 5.1 (ii).

For the second part we will use Lemma 5.2 (ii). The rank of $H^1(M; \mathfrak{v}_{\text{Ad } \rho_u}) \rightarrow H^1(\partial M; \mathfrak{v}_{\text{Ad } \rho_u})$ is k . Hence it suffices to take a basis when $u = 0$, $\{z_0^1, \dots, z_0^k\}$ and then make it vary in the kernel of $H^1(\partial M; \mathfrak{v}_{\text{Ad } \rho_u}) \rightarrow H^2(M, \partial M; \mathfrak{v}_{\text{Ad } \rho_u})$, which is an analytic family of k -dimensional vector spaces. \square

For $i = 1, \dots, k$ we consider the following 1-cycle in the i -th torus $\partial_i M$ of the boundary

$$a_u^i \otimes \frac{1}{|p_i + q_i \tau_i|^2} (p_i \mu_i + q_i \lambda_i)$$

in simplicial homology. This twisted cycle is the image of the untwisted cycle

$$\frac{p_i \mu_i + q_i \lambda_i}{|p_i + q_i \tau_i|^2} \in H_1(\partial_i M, \mathbf{R})$$

by the natural map

$$H_1(\partial_i M, \mathbf{R}) \xrightarrow{a_u^i \otimes \cdot} H_1(\partial_i M, \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}) \rightarrow H_1(\partial_i M, \mathfrak{v})$$

that consists in tensorizing by a_u^i and composing with the map induced by the inclusion of coefficients $\mathfrak{v}^{\rho_u(\pi_1(\partial_i M))} \rightarrow \mathfrak{v}$.

Let $\langle \cdot, \cdot \rangle$ denote the Kronecker pairing between homology and cohomology. We define

$$f(u) = \det \left(\left(\langle z_u^i, a_u^j \otimes \frac{p_j \mu_j + q_j \lambda_j}{|p_j + q_j \tau_j|^2} \rangle \right)_{ij} \right)$$

where p_i and q_i are the generalized Dehn filling coefficients corresponding to $u \in U$ (see Section 2). If we view z_u as a map on simplicial chains taking values on \mathfrak{v} , and B denotes the Killing form, then

$$f(u) = \det \left(B \left(z_u^i \left(\frac{p_j \mu_j + q_j \lambda_j}{|p_j + q_j \tau_j|^2} \right), a_u^j \right) \right).$$

6.3 Remark The function f depends on several non-canonical choices. But we are only interested in the zero locus of f and this set does not depend on the different cocycles involved in the definition of f . Notice also that Lemma 2.2 implies that f is analytic and $f(0) = 0$.

In the sequel let $u_{(\mathbf{p}, \mathbf{q})}$ denote the parameter of the structure whose completion gives the Dehn filling with coefficients $(p_1, q_1), \dots, (p_k, q_k)$ where (p_i, q_i) are pairs of coprime integers.

6.4 Lemma *If*

- (i) $f(u_{(\mathbf{p}, \mathbf{q})}) \neq 0$ and
- (ii) $\dim H^1(M, \mathfrak{v}_{\text{Ad } \rho_{u_{(\mathbf{p}, \mathbf{q})}}}) = k$,

then $H^1(M_{(\mathbf{p}, \mathbf{q})}, \mathfrak{v}_{\text{Ad } \rho_{u_{(\mathbf{p}, \mathbf{q})}}}) = 0$.

Proof. In this proof the representation $\rho_{u_{(\mathbf{p}, \mathbf{q})}}$ is fixed and we remove $\text{Ad } \rho_u$ from notation.

Hypothesis (i) and (ii) imply that

$$\{a_u^1 \otimes (p_1 \mu_1 + q_1 \lambda_1), \dots, a_u^k \otimes (p_k \mu_k + q_k \lambda_k)\}$$

is a basis for $H_1(M; \mathfrak{v})$. Hence for $\gamma := \gamma_1 \cup \dots \cup \gamma_k$, $\gamma_i = p_i \mu_i + q_i \lambda_i$, the following composition gives an isomorphism in homology:

$$\bigoplus_{i=1}^k H_1(\gamma_i; \mathbf{R}) \rightarrow \bigoplus_{i=1}^k H_1(\gamma_i; \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}) \rightarrow H_1(\gamma; \mathfrak{v}) \rightarrow H_1(M; \mathfrak{v}).$$

Equivalently, we have an isomorphism in cohomology:

$$H^1(M; \mathfrak{v}) \rightarrow H^1(\gamma; \mathfrak{v}) \rightarrow \bigoplus_{i=1}^k H^1(\gamma_i; \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}) \rightarrow \bigoplus_{i=1}^k H^1(\gamma_i; \mathbf{R}). \quad (10)$$

Let N denote a tubular neighborhood of the filling geodesics, so that $N = N_1 \cup \dots \cup N_k$ is the union of k solid tori, $N \cup M$ is the closed manifold $M_{(\mathbf{p}, \mathbf{q})}$ and $N \cap M = \partial M$. We check that the inclusions induce an isomorphism

$$H^i(M; \mathfrak{v}) \oplus H^i(N; \mathfrak{v}) \rightarrow H^i(\partial M; \mathfrak{v})$$

for $i = 0$ and $i = 1$. Then by Mayer-Vietoris, $H^1(M_{(\mathbf{p}, \mathbf{q})}, \mathfrak{v}) = 0$ follows.

When $i = 0$, $H^0(M; \mathfrak{v}) \cong \mathfrak{v}^{\text{Ad } \rho_u(\pi_1 M)} = 0$, and the required isomorphism comes from the fact that $\pi_1(N_j)$ and $\pi_1(\partial_j M)$ have the same image under ρ_u and hence the same invariant subspace.

When $i = 1$, we notice that by Lemma 5.2

$$H^1(\partial_i M, \mathfrak{v}) = H^1(\partial_i M, \mathbf{R}) \otimes \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))},$$

and $\dim \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))} = 1$, by Lemma 5.1. Similarly,

$$H^1(N_i, \mathfrak{v}) = H^1(N_i, \mathbf{R}) \otimes \mathfrak{v}^{\rho_u(\pi_1(\partial_i M))}.$$

Then the proof follows from isomorphism (10) and the natural isomorphism induced by inclusions:

$$H^1(\partial_i M; \mathbf{R}) \cong H^1(N_i; \mathbf{R}) \oplus H^1(\gamma_i; \mathbf{R}).$$

□

By analyticity we get:

6.5 Corollary *If the generic dimension of $H^1(M; \mathfrak{v}_{\text{Ad} \rho_u})$ is k and if f is non-constant in a neighborhood of 0, then infinitely many Dehn filling are infinitesimally rigid.*

Proof. The dimension of $H^1(M; \mathfrak{v}_{\text{Ad} \rho_u})$ is bounded below by k and lower semicontinuous on $u \in U$ (it is larger on a proper analytic subset). Hence the set of $u \in U$ where $\dim H^1(M; \mathfrak{v}_{\text{Ad} \rho_u}) \neq k$ or $f(u) = 0$ is a proper analytic subset of U , and it misses infinitely many Dehn fillings by [21, Lemme 4.4]. □

For a collection of simple closed curves $\mu = \{\mu_1, \dots, \mu_k\}$, one on each $\partial_i M$ and non nullhomotopic, let $\rho_{i\alpha}$ denote the holonomy of the corresponding hyperbolic cone structure with cone angle α and meridians μ .

6.6 Proposition *Assume that there exists a collection of simple closed curves as above $\mu \subset \pi_1(\partial M)$ and some $\varepsilon > 0$ so that, $\forall 0 < \alpha < \varepsilon$,*

$$\dim H^1(M, \mu; \mathfrak{v}_{\text{Ad} \rho_{\alpha i}}) = 3k.$$

Then infinitely many Dehn fillings are infinitesimally rigid.

Proof. Our goal is to prove the proposition by applying Corollary 6.5. Since $\rho_{\alpha i}(\mu_j)$ is a rotation of angle $0 < \alpha < \pi$, by Lemma 4.2 $\dim H^0(\mu_j; \mathfrak{v}_{\text{Ad} \rho_{\alpha i}}) = \dim \mathfrak{v}^{\text{Ad} \rho_{\alpha i}(\mu_j)} = 3$, and therefore $\dim H^0(\mu; \mathfrak{v}_{\text{Ad} \rho_{\alpha i}}) = 3k$.

Then the long exact sequence of the pair (M, μ) starts as follows:

$$0 \rightarrow H^0(\mu, \mathfrak{v}_{\text{Ad} \rho_{\alpha i}}) \rightarrow H^1(M, \mu, \mathfrak{v}_{\text{Ad} \rho_{\alpha i}}) \rightarrow H^1(M, \mathfrak{v}_{\text{Ad} \rho_{\alpha i}}) \rightarrow \dots$$

Since $\dim H^0(\mu; \mathfrak{v}_{\text{Ad} \rho_{\alpha i}}) = \dim H^1(M, \mu, \mathfrak{v}_{\text{Ad} \rho_{\alpha i}})$, we have an inclusion

$$0 \rightarrow H^1(M; \mathfrak{v}_{\text{Ad} \rho_{\alpha i}}) \rightarrow H^1(\mu; \mathfrak{v}_{\text{Ad} \rho_{\alpha i}}).$$

The inclusion of μ in M factors through ∂M , hence by Lemma 5.2, it follows that

$$\dim H^1(M; \mathfrak{v}_{\text{Ad} \rho_{\alpha i}}) = k,$$

which is the first condition for applying Corollary 6.5, by lower semicontinuity of the dimension of H^1 .

Moreover, using Lemma 5.2 (i), it follows that

$$H^1(M; \mathfrak{v}_{Ad\rho_{\alpha i}}) \cong \bigoplus_{j=1}^k H^1(\mu_j; \mathbf{R}) \otimes \mathfrak{v}^{\rho_{\alpha i}(\pi_1(\partial_j M))}.$$

This implies that one can choose a basis $\{z_u^1, \dots, z_u^k\}$ for $H^1(M; \mathfrak{v}_{Ad\rho_{\alpha i}})$, where $z_u^j = \hat{\mu}_j \otimes a_{\alpha \mathbf{i}}^j$ and $\hat{\mu}_j \in H^1(\mu_j; \mathbf{Z})$ is the dual of the fundamental class in $H_1(\mu_j; \mathbf{Z})$. Thus, since $p_j = 2\pi/\alpha$ and $q_j = 0$, we get

$$f(\alpha \mathbf{i}) = \frac{\alpha^k}{(2\pi)^k} B(a_{\alpha \mathbf{i}}^1, a_{\alpha \mathbf{i}}^1) \cdots B(a_{\alpha \mathbf{i}}^k, a_{\alpha \mathbf{i}}^k) \neq 0,$$

as the Killing form on $\mathfrak{v}^{\rho_{\alpha i}(\pi_1(\partial_j M))}$ is nondegenerate. \square

Proof of Theorem 1.4. As M is infinitesimally projectively rigid, by Lemma 5.6 we can choose a set of slopes $\mu = \mu_1 \cup \cdots \cup \mu_k$, so that

$$0 \rightarrow H^1(M; \mathfrak{v}_{Ad\rho_0}) \rightarrow H^1(\mu; \mathfrak{v}_{Ad\rho_0})$$

is exact. By the long exact sequence of the pair (M, μ) , since $\dim \mathfrak{v}^{Ad\rho_0(\mu_j)} = 3$, this is equivalent to saying that $\dim H^1(M, \mu; \mathfrak{v}_{Ad\rho_0}) = 3k$. By analyticity and lower semicontinuity of the dimension of the cohomology, the hypothesis of Proposition 6.6 holds true. \square

Proof of Theorem 1.5. Let $M_{(\mathbf{p}, \mathbf{q})}$ be infinitesimally projectively rigid. Then $u_{(\mathbf{p}, \mathbf{q})} \in U$ denotes the parameter in the Thurston slice corresponding to the holonomy of the structure on M induced by the Dehn filling.

As in the proof of Lemma 6.4, a Mayer-Vietoris argument gives that

$$\dim H^1(M; \mathfrak{v}_{Ad\rho_{u_{(\mathbf{p}, \mathbf{q})}}}) = k.$$

Moreover, if the parameter $u_{(\mathbf{p}, \mathbf{q})}$ is contained in the domain of definition of f then $f(u_{(\mathbf{p}, \mathbf{q})}) \neq 0$. A priori the domain of definition of f could be a smaller neighborhood of the origin: the problem is that the cohomology classes $z_u^1, \dots, z_u^k \in \text{Im}(H^1(M; \mathfrak{v}_{Ad\rho}) \rightarrow H^1(\partial M; Ad\rho))$ could be linearly dependent or even not be defined outside a small neighborhood of 0. To fix that, we use the path of hyperbolic cone structures, that gives a segment in U , that we parametrize by the cone angle $\alpha \in [0, 2\pi]$. Let $u_\alpha \in U$ denote the parameter of the deformation space and $\gamma_1, \dots, \gamma_k$ the boundary slopes. By compactness, the segment $[0, 2\pi]$ is covered by intervals (α_i, α_{i+1}) where there exists cohomology classes $z_\alpha^1, \dots, z_\alpha^k \in \text{Im}(H^1(M; \mathfrak{v}_{Ad\rho}) \rightarrow H^1(\partial M; Ad\rho))$ that vary analytically on α and are linearly independent for each $\alpha \in (\alpha_i, \alpha_{i+1})$, by Lemma 6.1. On each interval

we may use the cohomology classes to construct functions similar to f , i.e. as the determinant of the matrix of Kronecher pairings between z_α^i and the homology class represented by $a_\alpha^j \otimes \frac{\alpha}{2\pi} \gamma_j$. This finite sequence of paths and the usual analyticity argument gives that in a neighborhood of 0, $f \neq 0$ and the generic dimension of the cohomology is the expected one. Hence we may apply Corollary 6.5. \square

7 Flexing slopes

7.1 Definition Let M^3 be a cusped hyperbolic manifold of finite volume which is infinitesimally projectively rigid. Let γ be a slope of $\partial_1 M$, We say that γ is a *flexing slope* if the map

$$i_\gamma^*: H^1(M; \mathfrak{v}_{\text{Ad } \rho_0}) \rightarrow H^1(\gamma; \mathfrak{v}_{\text{Ad } \rho_0})$$

is nontrivial.

7.2 Proposition Let M^3 be a cusped hyperbolic manifold of finite volume which is infinitesimally projectively rigid and let $\mu, \lambda \in \partial_1 M$ be a pair of simple closed curves generating the fundamental group of $\partial_1 M$. Let $(p_n, q_n) \in \mathbf{Z}^2$ be a sequence of coprime integers lying on a line $a p_n + b q_n = c$. If $\gamma = -b\mu + a\lambda$ is a flexing slope, then $M_{(p_n, q_n), \infty, \dots, \infty}^3$ is infinitesimally rigid for n large enough.

Proof. After changing the basis in homology, the curves μ and λ are chosen such that $a = 1$, $b = 0$, i.e. $\lambda = (0, 1)$ is the flexing slope. We also may assume $(p_n, q_n) = (c, n)$.

Let us consider the path

$$s \mapsto \begin{cases} (c, \frac{1}{s}) & \text{if } s \neq 0 \\ \infty & \text{if } s = 0 \end{cases}$$

in the parameter space. Denote by $u(s)$ the corresponding point in the deformation space.

7.3 Lemma The path $u(s)$ is a real analytic on $s \in (-\varepsilon, \varepsilon)$.

Proof. Setting $\tau(u) = v(u)/u$, from $p u + q v = u(c + \frac{1}{s}\tau(u)) = 2\pi\mathbf{i}$ we can write

$$u(s c + \tau(u)) = s 2\pi\mathbf{i}.$$

Since $\tau(0) \neq 0$ and τ is analytic on u , this allows to define u as analytic function on s , by applying the analytic version of the implicit function theorem. \square

Let $\theta_u \in \text{Im}(H^1(M; \mathfrak{v}_{Ad\rho_u}) \rightarrow H^1(\partial_1 M; \mathfrak{v}_{Ad\rho_u}))$ be an analytic family of cohomology classes, so that $i_\lambda^*(\theta_0) \neq 0$. This is always possible since i_λ^* factors through $H^1(\partial_1 M; \mathfrak{v}_{Ad\rho_u})$.

The two cohomology classes $z_\mu, z_\lambda \in H^1(\partial_1 M; \mathfrak{v}_{Ad\rho_0})$ as defined in the proof of Lemma 5.4 satisfy $i_\mu^*(z_\lambda) = i_\lambda^*(z_\mu) = 0$, $i_\mu^*(z_\mu) \neq 0$, and $i_\lambda^*(z_\lambda) \neq 0$. Hence we may assume that

$$\theta_0 = z_\lambda + \beta z_\mu, \quad \text{for some } \beta \in \mathbf{R}.$$

Let also $a_{u(s)} \in \mathfrak{v}^{Ad\rho_{u(s)}(\pi_1(\partial_1 M))}$ be an analytic family of invariant elements, with $a_0 \neq 0$. As in Lemma 6.1, we want to see that for $s > 0$, the following function does not vanish:

$$\begin{aligned} f(s) &:= \left\langle \theta_{u(s)}, a_{u(s)} \otimes \frac{c\mu + \frac{1}{s}\lambda}{|c + \frac{1}{s}\tau|^2} \right\rangle \\ &= \frac{s}{|sc + \tau|^2} \langle \theta_{u(s)}(sc\mu + \lambda), a_{u(s)} \rangle. \end{aligned}$$

Notice that it follows from the proof of Lemma 5.1 that for small s , $s \neq 0$, the restriction of the Killing form on the subspace $\mathfrak{v}^{Ad\rho_{u(s)}(\pi_1(\partial_1 M))}$ is positive definite i.e. $B(a_{u(s)}, a_{u(s)}) > 0$ for sufficiently small $s \neq 0$.

7.4 Lemma *If $\|a_{u(s)}\| = B(a_{u(s)}, a_{u(s)})^{1/2}$, then*

$$\lim_{s \rightarrow 0} \frac{B(\theta_{u(s)}(\lambda), a_{u(s)})}{\|a_{u(s)}\|} = 16 \quad \text{and} \quad \lim_{s \rightarrow 0} \frac{B(\theta_{u(s)}(\mu), a_{u(s)})}{\|a_{u(s)}\|} = 16\beta.$$

Assuming the lemma we obtain

$$\frac{f(s)}{s \|a_{u(s)}\|} = \frac{1}{|sc + \tau|^2} \left(\frac{B(\theta_{u(s)}(\lambda), a_{u(s)})}{\|a_{u(s)}\|} + sc \frac{B(\theta_{u(s)}(\mu), a_{u(s)})}{\|a_{u(s)}\|} \right)$$

and hence

$$\lim_{s \rightarrow 0} \frac{f(s)}{s \|a_{u(s)}\|} = \frac{16}{|\tau_0|^2}.$$

Hence $f(s) \neq 0$ for $s \neq 0$. Moreover, since the dimension of $H^1(M; \mathfrak{v}_{Ad\rho_u})$ is lower semicontinuous, it still satisfies $\dim(H^1(M; \mathfrak{v}_{Ad\rho_{u(s)}})) = k$. By analyticity those conditions are satisfied for all but finitely many s , hence we may apply Lemma 6.4.

This concludes the proof of Proposition 7.2 assuming Lemma 7.4. \square

Before proving Lemma 7.4, we still need a further computation. Let $w_0 \in \mathfrak{su}(3, 1)$ denote the following element of $\mathfrak{u}(1)$:

$$w_0 = \frac{\mathbf{i}}{2} V_0 \quad \text{where } V_0 = \begin{pmatrix} 1 & & & \\ & 1 & & \\ & & -1 & \\ & & & -1 \end{pmatrix}.$$

Note that w_0 is contained in $\mathfrak{g}_0 \subset \mathfrak{su}(3,1)$ which is the Lie algebra of the stabilizer of $[v_{\pm}] \in \partial_{\infty} \mathbf{H}_{\mathbf{C}}^3$.

7.5 Lemma *The invariant element $a_u \in \mathfrak{v}^{\rho_u(\pi_1(\partial M))}$ can be chosen such that:*

$$a_u = p(u) + 4 \left(\sinh^2 \frac{u}{2} \right) V_0$$

where $p(u)$ is an infinitesimal parabolic transformation.

Proof. Since w_0 is invariant by the stabilizer G_0 for $u \neq 0$, a_u can be obtained by conjugating w_0 , and then by normalizing the result so that the limit exists if u tends to 0.

Recall that in the Heisenberg model the subgroup of real parabolic representations corresponds to $\mathbf{R}^2 \times \{0\} \subset \mathcal{H}_- \subset G_- = \mathcal{H}_- \rtimes (U(2) \times \mathbf{R})$. Note also that w_0 is the image of $\mathbf{i}I_2$ under the canonical inclusion $\mathfrak{u}(2) \hookrightarrow \mathfrak{su}(3,1)$.

Suppose that $(x, y, 0) \in \mathbf{R}^2 \times \{0\}$ is the second fixed point of $\rho_u(\pi_1 \partial M)$. In the notation of $PSL_2(\mathbf{C})$ we have

$$\rho_u(\mu) = \pm \begin{pmatrix} e^{u/2} & 1 \\ 0 & e^{-u/2} \end{pmatrix},$$

hence

$$x + \mathbf{i}y = \frac{-1}{2 \sinh(u/2)}.$$

Using the formalism of G_- , the conjugate of w_0 we are looking for is:

$$\begin{aligned} \text{Ad}_{(x,y,0)} \begin{pmatrix} \mathbf{i} & 0 \\ 0 & \mathbf{i} \end{pmatrix} &= \frac{d}{dt}(x, y, 0) \begin{pmatrix} e^{it} & 0 \\ 0 & e^{it} \end{pmatrix} (-x, -y, 0) \Big|_{t=0} \\ &= \frac{d}{dt}(x, y, 0) (-xe^{it}, -ye^{it}, 0) \begin{pmatrix} e^{it} & 0 \\ 0 & e^{it} \end{pmatrix} \Big|_{t=0} \\ &= \frac{d}{dt}(x(1 - e^{it}), y(1 - e^{it}), (x^2 + y^2) \sin(t)) \begin{pmatrix} e^{it} & 0 \\ 0 & e^{it} \end{pmatrix} \Big|_{t=0} \\ &= (-\mathbf{i}x, -\mathbf{i}y, (x^2 + y^2)) + \begin{pmatrix} \mathbf{i} & 0 \\ 0 & \mathbf{i} \end{pmatrix}. \end{aligned}$$

Under the inclusion $\mathfrak{g}_- \hookrightarrow \mathfrak{su}(3,1)$ this element is written as

$$\begin{pmatrix} \frac{\mathbf{i}}{2} & & & \\ & \frac{\mathbf{i}}{2} & & \\ & & -\frac{\mathbf{i}}{2} & \\ & & & -\frac{\mathbf{i}}{2} \end{pmatrix} - \mathbf{i} \begin{pmatrix} 0 & 0 & x & y \\ 0 & 0 & x & y \\ -x & x & 0 & 0 \\ -y & y & 0 & 0 \end{pmatrix} + \mathbf{i}(x^2 + y^2) \begin{pmatrix} 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 1 & -1 \\ 0 & 0 & 1 & -1 \end{pmatrix}.$$

Hence $\text{Ad}_{(x,y,0)}(w_0) = w_0 + \text{Parabolic}$.

Now $x^2 + y^2 = \frac{1}{4 \sinh^2(u/2)}$ and in order to obtain an invariant which converges when $u \rightarrow 0$ we take

$$a_u = -i4 \left(\sinh^2 \frac{u}{2} \right) Ad_{(x,y,0)}(w_0) = 4 \left(\sinh^2 \frac{u}{2} \right) V_0 + \text{Parabolic}$$

and the lemma is clear. \square

Proof of Lemma 7.4. Using Lemmas 7.5 and 3.3 we obtain:

$$\begin{aligned} B(a_u, a_u)^{1/2} &= 4 \sinh^2 \frac{u}{2} B(V_0, V_0)^{1/2} = 8 \sinh^2 \frac{u}{2}; \\ B(\theta_{u(s)}(\lambda), a_{u(s)}) &= B(\theta_{u(s)}(\lambda), V_0) 4 \sinh^2 \frac{u}{2}. \end{aligned}$$

Hence

$$\frac{B(\theta_{u(s)}(\lambda), a_{u(s)})}{\|a_{u(s)}\|} = \frac{1}{2} B(\theta_{u(s)}(\lambda), V_0) \rightarrow \frac{1}{2} B(\theta_{u(0)}(\lambda), V_0) \text{ as } s \rightarrow 0,$$

and

$$B(\theta_{u(0)}(\lambda), V_0) = B(z_\lambda(\lambda), V_0) = B(a_\mu, W_0) = 32.$$

A similar computation holds for $\theta_{u(s)}(\mu)$. \square

8 Examples

In this section we compute two examples, the figure eight knot and the Whitehead link exteriors. We start introducing some notation. Let $\mathbf{x} \in \mathbf{R}^4$ be a column vector. As in Section 3.3 we will use the following notation: $\mathbf{x}^* = \mathbf{x}^t J$. The for all $\mathbf{x}, \mathbf{y} \in \mathbf{R}^4$ we have that $\mathbf{x}\mathbf{y}^* + \mathbf{y}\mathbf{x}^* \in \mathfrak{v}$. In the sequel we will make use of the following basis $\{v_1, \dots, v_9\}$ of \mathfrak{v} :

$$v_i = \mathbf{e}_i \mathbf{e}_i^* + \mathbf{e}_4 \mathbf{e}_4^* \quad \text{for } i = 1, \dots, 3,$$

and

$$\begin{aligned} v_4 &= \mathbf{e}_1 \mathbf{e}_2^* + \mathbf{e}_2 \mathbf{e}_1^*, & v_5 &= \mathbf{e}_1 \mathbf{e}_3^* + \mathbf{e}_3 \mathbf{e}_1^*, & v_6 &= \mathbf{e}_1 \mathbf{e}_4^* + \mathbf{e}_4 \mathbf{e}_1^*, \\ v_7 &= \mathbf{e}_2 \mathbf{e}_3^* + \mathbf{e}_3 \mathbf{e}_2^*, & v_8 &= \mathbf{e}_2 \mathbf{e}_4^* + \mathbf{e}_4 \mathbf{e}_2^*, & v_9 &= \mathbf{e}_3 \mathbf{e}_4^* + \mathbf{e}_4 \mathbf{e}_3^*. \end{aligned}$$

8.1 The figure eight knot

In this section we explain the computations to show that the figure eight knot exterior is infinitesimally projectively rigid.

Let Γ be the fundamental group of the figure eight knot exterior. We fix a presentation of Γ :

$$\Gamma = \langle x, y \mid xy^{-1}x^{-1}yxy^{-1}xyx^{-1}y^{-1} \rangle.$$

where x and y represent meridians.

By Corollary 5.3, it suffices to show that $\dim H^1(\Gamma, \mathfrak{v}_{Ad\rho_0}) = 1$.

We start with a holonomy representation of the complete structure in $SL_2(\mathbf{C})$ [23]:

$$x \mapsto \begin{pmatrix} 1 & 1 \\ 0 & 1 \end{pmatrix} \quad y \mapsto \begin{pmatrix} 1 & 0 \\ \frac{1-i\sqrt{3}}{2} & 1 \end{pmatrix},$$

Using for instance the construction described in [7], the representation in $PSO(3,1)$ is given by:

$$\rho_0(x) = \begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & -1 & 1 \\ 0 & 1 & 1/2 & 1/2 \\ 0 & 1 & -1/2 & 3/2 \end{pmatrix} \quad \rho_0(y) = \begin{pmatrix} 1 & 0 & \sqrt{3}/2 & \sqrt{3}/2 \\ 0 & 1 & 1/2 & 1/2 \\ -\sqrt{3}/2 & -1/2 & 1/2 & -1/2 \\ \sqrt{3}/2 & 1/2 & 1/2 & 3/2 \end{pmatrix}$$

Notice that the holonomy of x and y have a fixed point in the light cone, which are respectively:

$$v_+ = \begin{pmatrix} 0 \\ 0 \\ 1 \\ 1 \end{pmatrix} \quad \text{and} \quad v_- = \begin{pmatrix} 0 \\ 0 \\ -1 \\ 1 \end{pmatrix}.$$

With respect to the basis $\{v_1, \dots, v_9\}$ for \mathfrak{v} the adjoint representation is given by:

$$\text{Ad } \rho_0(x) = \begin{pmatrix} 1 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 1 & 2 & 2 & 0 & 0 & 0 & -2 & 2 & -2 \\ \frac{1}{4} & \frac{5}{4} & \frac{1}{2} & 0 & 0 & 0 & 1 & 1 & \frac{1}{2} \\ 0 & 0 & 0 & 1 & -1 & -1 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 & \frac{1}{2} & -\frac{1}{2} & 0 & 0 & 0 \\ 0 & 0 & 0 & -1 & \frac{1}{2} & \frac{3}{2} & 0 & 0 & 0 \\ \frac{1}{2} & \frac{3}{2} & 0 & 0 & 0 & 0 & -\frac{1}{2} & \frac{3}{2} & 0 \\ \frac{3}{2} & \frac{5}{2} & 2 & 0 & 0 & 0 & -\frac{3}{2} & \frac{5}{2} & -2 \\ \frac{3}{4} & \frac{7}{4} & \frac{1}{2} & 0 & 0 & 0 & 0 & 2 & \frac{1}{2} \end{pmatrix}$$

and

$$\text{Ad } \rho_0(y) = \begin{pmatrix} \frac{7}{4} & \frac{3}{4} & \frac{3}{2} & 0 & \sqrt{3} & -\sqrt{3} & 0 & 0 & \frac{3}{2} \\ \frac{1}{4} & \frac{5}{4} & \frac{1}{2} & 0 & 0 & 0 & 1 & 1 & \frac{1}{2} \\ 1 & \frac{1}{2} & \frac{1}{2} & \frac{\sqrt{3}}{2} & -\frac{\sqrt{3}}{2} & -\frac{\sqrt{3}}{2} & -\frac{1}{2} & \frac{1}{2} & -\frac{1}{2} \\ \frac{\sqrt{3}}{4} & \frac{\sqrt{3}}{4} & \frac{\sqrt{3}}{2} & 1 & 1/2 & -1/2 & \frac{\sqrt{3}}{2} & \frac{\sqrt{3}}{2} & \frac{\sqrt{3}}{2} \\ -\frac{3\sqrt{3}}{4} & -\frac{\sqrt{3}}{4} & 0 & -\frac{1}{2} & -\frac{1}{4} & \frac{5}{4} & -\frac{\sqrt{3}}{4} & -\frac{\sqrt{3}}{4} & 0 \\ -\frac{5\sqrt{3}}{4} & -\frac{3\sqrt{3}}{4} & -\sqrt{3} & -\frac{1}{2} & -\frac{5}{4} & \frac{9}{4} & -\frac{\sqrt{3}}{4} & -\frac{\sqrt{3}}{4} & -\sqrt{3} \\ -\frac{1}{4} & -\frac{3}{4} & 0 & -\frac{\sqrt{3}}{2} & -\frac{\sqrt{3}}{4} & \frac{\sqrt{3}}{4} & \frac{1}{4} & -\frac{3}{4} & 0 \\ \frac{3}{4} & \frac{5}{4} & 1 & \frac{\sqrt{3}}{2} & \frac{\sqrt{3}}{4} & -\frac{\sqrt{3}}{4} & \frac{3}{4} & \frac{7}{4} & 1 \\ -\frac{3}{2} & -1 & -\frac{1}{2} & -\frac{\sqrt{3}}{2} & 0 & \sqrt{3} & 0 & -1 & \frac{1}{2} \end{pmatrix}.$$

The cohomology group $H^1(\Gamma; \mathfrak{v})$ is computed as the quotient Z^1/B^1 , where Z^1 is the space of cocycles and B^1 the space of coboundaries:

$$\begin{aligned} Z^1 &= \{d : \Gamma \rightarrow \mathfrak{v} \mid d(\gamma_1\gamma_2) = d(\gamma_1) + \text{Ad}\rho_0(\gamma_1)d(\gamma_2), \forall \gamma_1, \gamma_2 \in \Gamma\}, \\ B^1 &= \{d \in Z^1 \mid d(\gamma) = (\text{Ad}\rho_0(\gamma) - 1)a, \forall \gamma \in \Gamma, \text{ for some } a \in \mathfrak{v}\}. \end{aligned}$$

Since \mathfrak{v} has no element globally invariant by Γ , $\dim B^1 = \dim \mathfrak{v} = 9$. We claim that $\dim Z^1 = 10$. To compute this dimension, we use the isomorphism of \mathbf{R} -vector spaces:

$$\begin{aligned} Z^1 &\leftrightarrow \{(a, b) \in \mathfrak{v}^2 \mid \frac{\partial w}{\partial x} \cdot a + \frac{\partial w}{\partial y} \cdot b = 0\}, \\ d &\leftrightarrow (d(x), d(y)) \end{aligned},$$

where $w = xy^{-1}x^{-1}yxy^{-1}xyx^{-1}y^{-1}$ is the relation in the presentation of Γ , and $\frac{\partial w}{\partial x}$, $\frac{\partial w}{\partial y}$ stand for the Fox derivatives [18]:

$$\begin{aligned} \frac{\partial w}{\partial x} &= 1 - xy^{-1}x^{-1} + xy^{-1}x^{-1}y + yxy^{-1}x^{-1} - y. \\ \frac{\partial w}{\partial y} &= -xy^{-1} + xy^{-1}x^{-1} - yxy^{-1}x^{-1} + yxy^{-1} - 1. \end{aligned}$$

Thus, Z^1 is isomorphic to the kernel of the linear map from $\mathfrak{v} \times \mathfrak{v}$ to \mathfrak{v} with matrix:

$$\left(\text{Ad } \rho_0\left(\frac{\partial w}{\partial x}\right), \text{Ad } \rho_0\left(\frac{\partial w}{\partial y}\right) \right). \quad (11)$$

One can check that this matrix has rank 8, by means of an elementary but tedious computation. Hence $\dim Z^1 = 10$, as claimed.

To prove Proposition 1.7 we need to show:

8.1 Remark The longitude is a flexing slope.

With this remark, Proposition 1.7 is just an application of Proposition 7.2. To prove that the longitude is a flexing slope, we need to analyze more carefully the previous computation.

By looking at the kernel of matrix (11), we choose one cocycle d determined by:

$$d(x) = \begin{pmatrix} 0 & 0 & 0 & 0 \\ 0 & 0 & -3 & -1 \\ 0 & -3 & 0 & 0 \\ 0 & 1 & 0 & 0 \end{pmatrix} \quad \text{and} \quad d(y) = 0.$$

Let $l = yx^{-1}y^{-1}x^2y^{-1}x^{-1}y$ be the longitude that commutes with x . Then, by Fox calculus,

$$d(l) = \begin{pmatrix} 60 & -4\sqrt{3} & 60\sqrt{3} & -68\sqrt{3} \\ -4\sqrt{3} & -4 & -12 & 12 \\ 60\sqrt{3} & -12 & 178 & -206 \\ 68\sqrt{3} & -12 & 206 & -234 \end{pmatrix}.$$

To see that d restricted to l is nontrivial, following the proof of Lemma 5.4, we must find an invariant element $a \in \mathfrak{v}^{\text{Ad } \rho_0(l)}$ such that $B(d(l), a) \neq 0$. Since:

$$\rho_0(l) = \begin{pmatrix} 1 & 0 & -2\sqrt{3} & 2\sqrt{3} \\ 0 & 1 & 0 & 0 \\ 2\sqrt{3} & 0 & -5 & 6 \\ 2\sqrt{3} & 0 & -6 & 7 \end{pmatrix},$$

following again the proof of Lemma 5.4, we choose

$$a = \begin{pmatrix} -1 & & & \\ & 3 & & \\ & & -1 & \\ & & & -1 \end{pmatrix},$$

and we have that $B(d(l), a) = -16 \neq 0$.

8.2 The Whitehead link

A similar computation as for the figure eight knot tells us that the Whitehead link $L = K_1 \sqcup K_2$ is infinitesimally projectively rigid. Let $\Gamma = \pi_1(M)$ denote the fundamental group of the Whitehead link exterior M . We will work with the presentation:

$$\Gamma = \langle x, y \mid xy^{-1}x^{-1}yx^{-1}y^{-1}xyx^{-1}yxy^{-1}xyx^{-1}y^{-1} \rangle$$

where x is a meridian for K_1 and y is a meridian for K_2 . The holonomy representation $\rho: \Gamma \rightarrow SL_2(\mathbf{C})$ is given by

$$x \mapsto \begin{pmatrix} 1 & 1 \\ 0 & 1 \end{pmatrix} \quad y \mapsto \begin{pmatrix} 1 & 0 \\ -1 - \mathbf{i} & 1 \end{pmatrix}$$

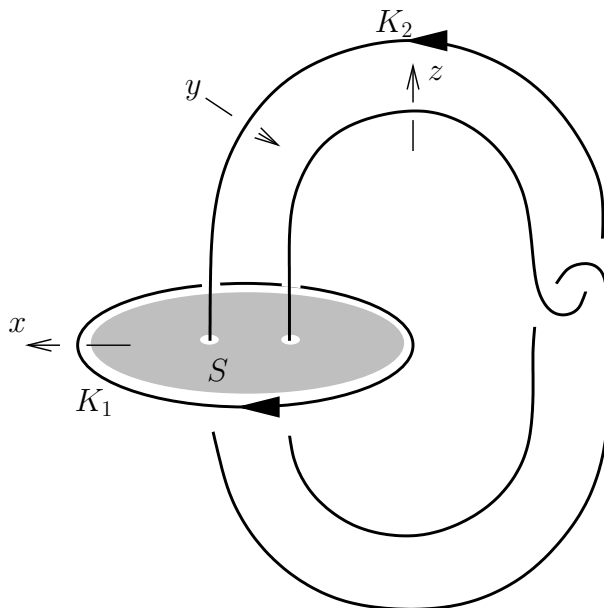


Figure 1: The thrice punctured sphere S in the Whitehead link.

(see [22] for details). A computation analogous to the one of the previous subsection shows that $\dim H^1(M; \mathfrak{v}_{Ad\rho}) = 2$.

Once we know the dimension of the deformation space, we have a geometric tool to understand the deformations: let S denote the thrice puncture sphere illustrated in Figure 1. By symmetry of the components of the link, there are two of them. The surface S intersects one boundary torus in a longitude $l_x = yx^{-1}y^{-1}xy^{-1}x^{-1}yx$, and the other one in two meridians y and $z = x^{-1}y^{-1}xyx^{-1}yx$, with opposite orientation. The restriction of the holonomy onto $\pi_1(S)$ is conjugate to a representation into $SL_2(\mathbf{R})$. Hence S a totally geodesic thrice puncture sphere in the link complement.

8.2 Lemma *Let $\partial_1 M$ denote the boundary component of K_1 . Every slope on $\partial_1 M$ different from the longitude l_x is a flexing slope.*

Proof. We consider the bending along S . If we restrict this bending to $\partial_1 M$, it is itself a bending along the longitude l_x , and it happens to be precisely the deformation constructed in the proof of Lemma 5.4. Thus, except for the longitude itself, this deformation is nontrivial when restricted to any slope of the torus, because the cusp shape of the Whitehead link lies in the Gaussian integers $\mathbf{Z}[\mathbf{i}]$, thus the angle of any slope with the longitude l_x can never be $\pi/3$, and we can apply Lemma 5.4. \square

Proof of Proposition 1.8. Lemma 8.2 and Proposition 7.2 imply that for almost all n the $(n, 1)$ -Dehn fillings are infinitesimally projectively rigid.

According to [1] those fillings are precisely the punctured torus bundles with tunnel number one.

Twists knots are obtained by $(1, n)$ -Dehn fillings, but we cannot apply Proposition 7.2, because the longitude is not a flexing slope. However, the path $(p, q) = (1, s)$ for $s \in \mathbf{R}$ and $s \geq 1$ is contained in the whole deformation space (cf. [1]). Hence, since the coefficients $(1, 1)$ correspond to the figure eight knot exterior, with an argument similar to Theorem 1.5, the $(1, n)$ -Dehn fillings are infinitesimally rigid for all but finitely many n . \square

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