



Paradoxical Twins

Beyond an Introduction

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The Standard Twin Paradox

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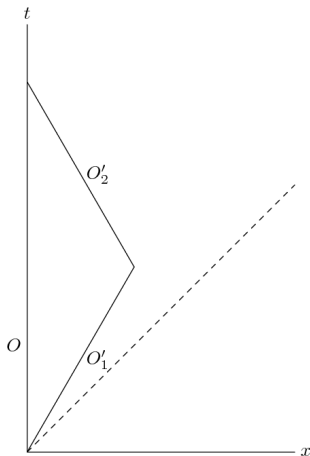
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We have two twins:

- 1) In the I.F. O .
- 2) In two different I.F.'s, O'_1 and O'_2 .

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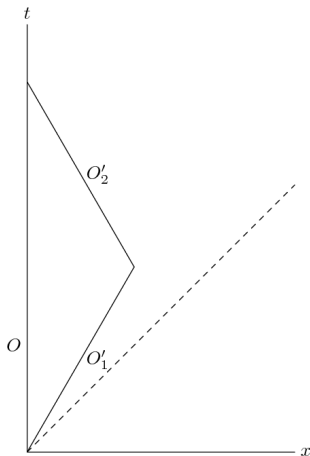
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Blind application of time
dilation leads to contradiction.

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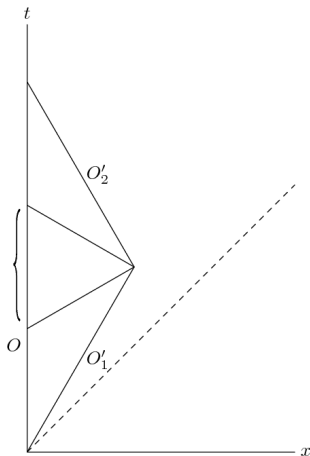
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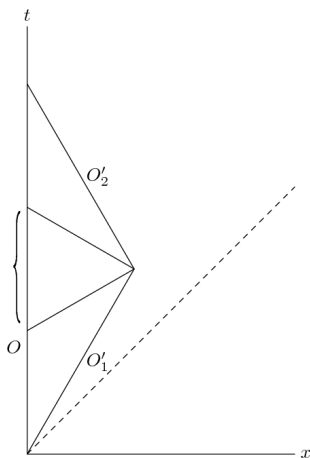


We have two twins:

- 1) In the I.F. O .
- 2) In two different I.F.'s, O'_1 and O'_2 .

Blind application of time
dilation leads to contradiction.

The Standard Twin Paradox



We have two twins:

- 1) In the I.F. O .
- 2) In two different I.F.'s, O'_1 and O'_2 .

Blind application of time dilation leads to contradiction.

Actually, O' does see O -clock run slowly, but there is also a sudden aging at the turn-around point. Using finite acceleration, we can account for this faster aging as a gravitational effect.

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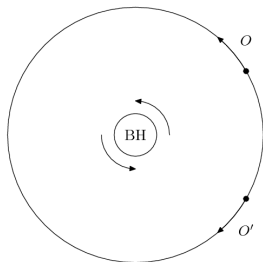
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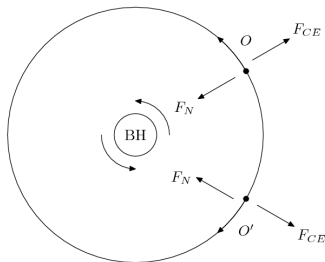
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- Can we have the twins both be inertial?
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- Radial equation:
$$-F_N + F_{CE}$$

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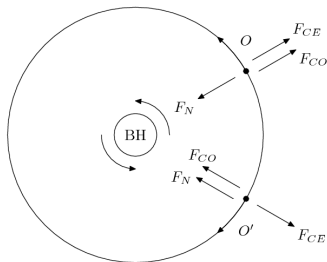
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- Can we have the twins both be inertial?
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- Radial equation:
$$-F_N + F_{CE} \pm F_{CO} = 0$$

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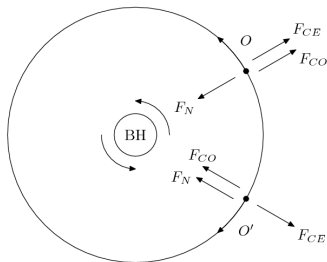
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- Coriolis force (F_{CO}) is a gravito-magnetic effect

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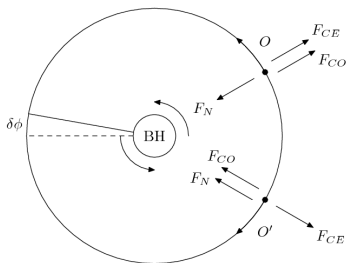
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- F_{CO} and F_{CE} depend differently on $\dot{\phi}$, so different orbital speeds are required.

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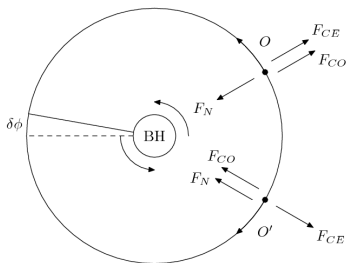
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 - Coriolis force (F_{CO}) is a gravito-magnetic effect
 - F_{CO} and F_{CE} depend differently on $\dot{\phi}$, so different orbital speeds are required.
- Since O' moves faster, she ages less!

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- Geodesics *locally* maximize proper time.

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- Geodesics *locally* maximize proper time.
- Geometry in a neighborhood of each twin is different, so there is a geometric asymmetry between the two twins.

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- Geodesics *locally* maximize proper time.
- Geometry in a neighborhood of each twin is different, so there is a geometric asymmetry between the two twins.
- It would be interesting to compute perceived aging directly in each twins' frame.

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- Can we do this without curvature?

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- Can we do this without curvature?
- Intrinsic curvature (geometry) \mapsto extrinsic curvature (topology).

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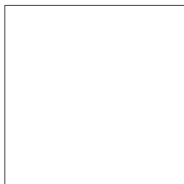
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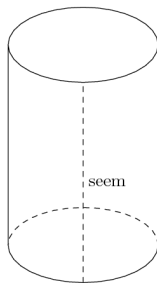
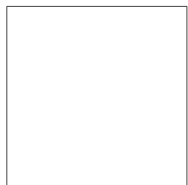
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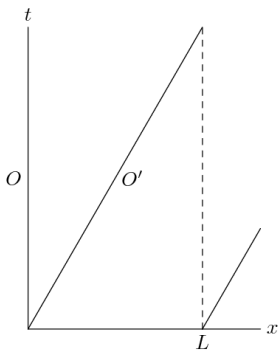
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Identify points that differ
by L .

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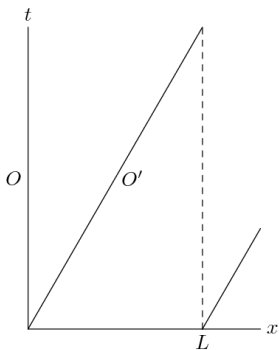
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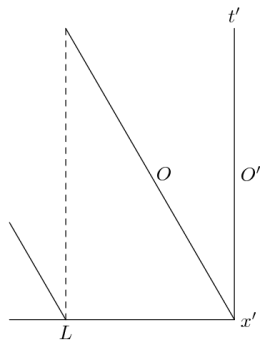
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Identify points that differ
by L .

Contradiction?

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Let's look at the boundary conditions:

$$\begin{pmatrix} t \\ x \end{pmatrix} \sim \begin{pmatrix} t \\ x + nL \end{pmatrix}$$

Periodic Boundary Conditions Examined

Let's look at the boundary conditions:

$$\begin{aligned}\begin{pmatrix} t \\ x \end{pmatrix} &\sim \begin{pmatrix} t \\ x + nL \end{pmatrix} \\ \Lambda \begin{pmatrix} t \\ x \end{pmatrix} &\sim \Lambda \begin{pmatrix} t \\ x \end{pmatrix} + \Lambda \begin{pmatrix} 0 \\ nL \end{pmatrix}\end{aligned}$$

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- The identification condition is not Lorentz invariant.

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- The identification condition is not Lorentz invariant.
- The naïve Minkowski diagram for O' is incorrect since it assumed the condition $(t', x') \sim (t', x' + nL)$.

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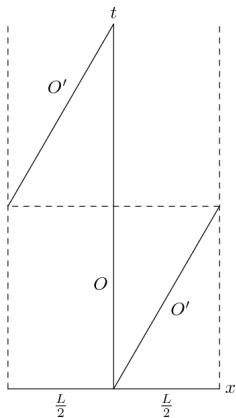
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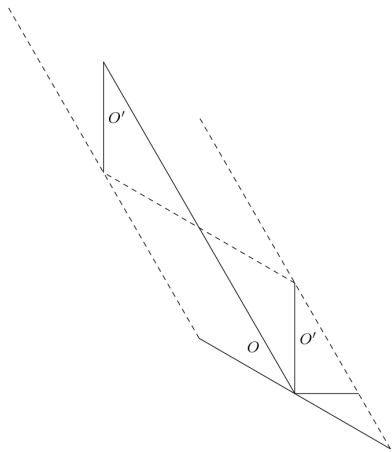
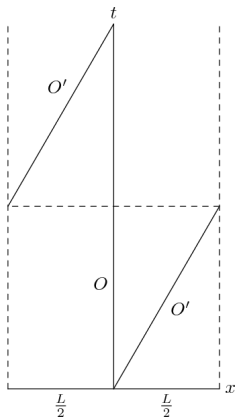
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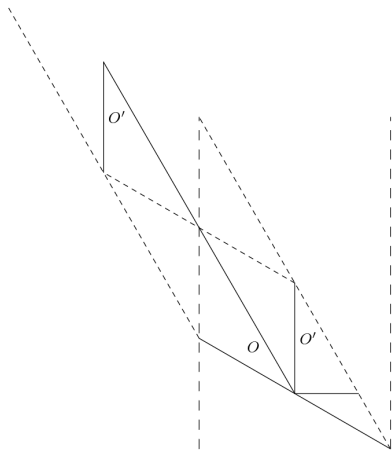
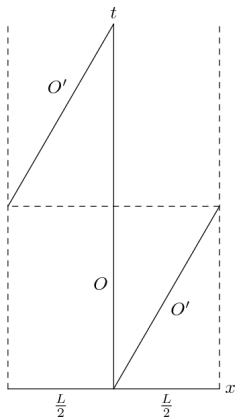
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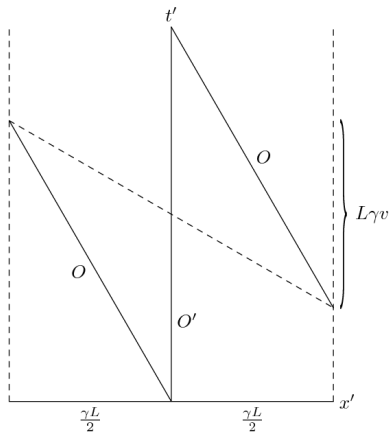
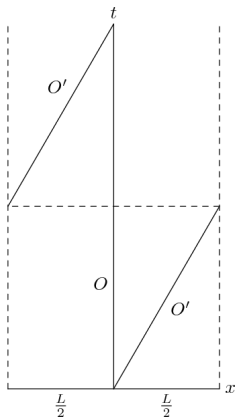
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O' sees O clock run slowly by γ .

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But there is an additional $v\gamma L = T\gamma v^2$.

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Thus the total aging of O as seen by O' is

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$$\hat{T} = (T' + T\gamma v^2) / \gamma$$

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Thus the total aging of O as seen by O' is

$$\begin{aligned}\hat{T} &= (T' + T\gamma v^2) / \gamma \\ &= \left(\frac{T}{\gamma} + T\gamma v^2 \right) / \gamma\end{aligned}$$

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Thus the total aging of O as seen by O' is

$$\begin{aligned}\hat{T} &= (T' + T\gamma v^2) / \gamma \\ &= \left(\frac{T}{\gamma} + T\gamma v^2 \right) / \gamma \\ &= T (\gamma^{-2} + (1 - \gamma^{-2}))\end{aligned}$$

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They agree!

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Each observer sees images of herself in both directions

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- O : all the same age t .

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Each observer sees images of herself in both directions

- O : all the same age t .
- O' : differ in age by $\pm Lv\gamma$.

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- The universe is anisotropic in O' .

Each observer sees images of herself in both directions

- O : all the same age t .
- O' : differ in age by $\pm Lv\gamma$.

Including light propagation:

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- O' frame is *not* a global inertial frame.
- Attempting such a frame results in unsynchronized clocks.
- The universe is larger (γL) for O' .
- The universe is anisotropic in O' .

Each observer sees images of herself in both directions

- O : all the same age t .
- O' : differ in age by $\pm Lv\gamma$.

Including light propagation:

- O : sees self in past by L .

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- O' frame is *not* a global inertial frame.
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Each observer sees images of herself in both directions

- O : all the same age t .
- O' : differ in age by $\pm Lv\gamma$.

Including light propagation:

- O : sees self in past by L .
- O' sees self in past by $\gamma L \pm Lv\gamma = L\gamma(1 \pm v) = L\sqrt{\frac{1 \pm v}{1 \mp v}}$

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- O' frame is *not* a global inertial frame.
- Attempting such a frame results in unsynchronized clocks.
- The universe is larger (γL) for O' .
- The universe is anisotropic in O' .

Each observer sees images of herself in both directions

- O : all the same age t .
- O' : differ in age by $\pm Lv\gamma$.

Including light propagation:

- O : sees self in past by L .
- O' sees self in past by $\gamma L \pm Lv\gamma = L\gamma(1 \pm v) = L\sqrt{\frac{1 \pm v}{1 \mp v}}$

Thus the universe is shorter in one direction than the other.

(Anisotropic) Light Propagation

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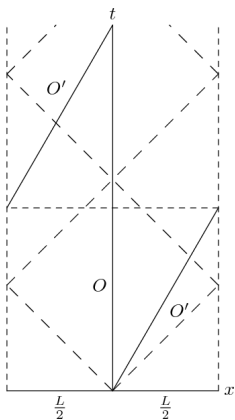
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- Minkowski space $\mathbb{R}^{1,1}$ is isotropic.

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- Minkowski space $\mathbb{R}^{1,1}$ is isotropic.
- The cylinder $\mathbb{R}^{1,1} / \sim = R \times S^1$ is not, since there is a direction which does not go on forever.

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- Minkowski space $\mathbb{R}^{1,1}$ is isotropic.
- The cylinder $\mathbb{R}^{1,1} / \sim = R \times S^1$ is not, since there is a direction which does not go on forever.
- However, it is still homogeneous.

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- Minkowski space $\mathbb{R}^{1,1}$ is isotropic.
- The cylinder $\mathbb{R}^{1,1} / \sim = R \times S^1$ is not, since there is a direction which does not go on forever.
- However, it is still homogeneous.
- We can make this more precise in group theory:

The Cylinder

The symmetry group of \mathbb{R}^2 is $ISO(2)$:

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The Cylinder

The symmetry group of \mathbb{R}^2 is $ISO(2)$:

$$M = \left(\begin{array}{c|c} R_\theta & T \\ \hline 0 & 1 \end{array} \right)$$

R_θ is a rotation matrix
 T is a translation vector.

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The Cylinder

The symmetry group of \mathbb{R}^2 is $ISO(2)$:

$$M = \left(\begin{array}{c|c} R_\theta & T \\ \hline 0 & 1 \end{array} \right) \quad \begin{array}{l} R_\theta \text{ is a rotation matrix} \\ T \text{ is a translation vector.} \end{array}$$

The action of M on a point is then

$$\begin{aligned} \begin{pmatrix} x' \\ y' \\ 1 \end{pmatrix} &= \begin{pmatrix} R_\theta & T \\ \hline 0 & 1 \end{pmatrix} \begin{pmatrix} x \\ y \\ 1 \end{pmatrix} \\ &= \begin{pmatrix} R_\theta \begin{pmatrix} x \\ y \end{pmatrix} + T \\ 1 \end{pmatrix} \end{aligned}$$

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Making a Cylinder

The cylinder is formed from the plane by identifying points that differ by the group operation $T_{L,0}$, that is:

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Making a Cylinder

The cylinder is formed from the plane by identifying points that differ by the group operation $T_{L,0}$, that is:

$$\begin{aligned} \begin{pmatrix} x \\ y \\ 1 \end{pmatrix} &\sim T_{L,0} \begin{pmatrix} x \\ y \\ 1 \end{pmatrix} \\ &= \left(\begin{array}{c|c} I_2 & L \\ \hline 0 & 1 \end{array} \right) \begin{pmatrix} x \\ y \\ 1 \end{pmatrix} \\ &= \begin{pmatrix} x + L \\ y \\ 1 \end{pmatrix} \end{aligned}$$

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What is the symmetry group of the cylinder?

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What is the symmetry group of the cylinder?
For what group operations is it true that:

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What is the symmetry group of the cylinder?

For what group operations is it true that:

$$\begin{array}{c} \mathbb{R}^2 \\ \downarrow g \\ \mathbb{R}^2 \end{array}$$

$$\begin{array}{c} x, Tx \\ \downarrow g \\ g(x), g(Tx) \end{array}$$

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What is the symmetry group of the cylinder?

For what group operations is it true that:

$$\begin{array}{ccc} \mathbb{R}^2 & \xrightarrow{\pi} & \mathbb{R} \times S^1 \\ \downarrow g & & \\ \mathbb{R}^2 & \xrightarrow{\pi} & \end{array} \quad \begin{array}{ccc} x, Tx & \xrightarrow{\pi} & y \\ \downarrow g & & \\ g(x), g(Tx) & \xrightarrow{\pi} & \end{array}$$

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For what group operations is it true that:

$$\begin{array}{ccc} \mathbb{R}^2 & \xrightarrow{\pi} & \mathbb{R} \times S^1 \\ \downarrow g & & \downarrow h \\ \mathbb{R}^2 & \xrightarrow{\pi} & \mathbb{R} \times S^1 \end{array}$$

$$\begin{array}{ccc} x, Tx & \xrightarrow{\pi} & y \\ \downarrow g & & \downarrow h \\ g(x), g(Tx) & \xrightarrow{\pi} & h(y) \end{array}$$

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$$\begin{array}{ccc} \mathbb{R}^2 & \xrightarrow{\pi} & \mathbb{R} \times S^1 \\ \downarrow g & & \downarrow h \\ \mathbb{R}^2 & \xrightarrow{\pi} & \mathbb{R} \times S^1 \end{array} \qquad \begin{array}{ccc} x, Tx & \xrightarrow{\pi} & y \\ \downarrow g & & \downarrow h \\ g(x), g(Tx) & \xrightarrow{\pi} & h(y) \end{array}$$

For the right equation to hold we must have

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For what group operations is it true that:

$$\begin{array}{ccc} \mathbb{R}^2 & \xrightarrow{\pi} & \mathbb{R} \times S^1 \\ \downarrow g & & \downarrow h \\ \mathbb{R}^2 & \xrightarrow{\pi} & \mathbb{R} \times S^1 \end{array} \qquad \begin{array}{ccc} x, Tx & \xrightarrow{\pi} & y \\ \downarrow g & & \downarrow h \\ g(x), g(Tx) & \xrightarrow{\pi} & h(y) \end{array}$$

For the right equation to hold we must have

$$Tg(x) = gT(x)$$

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What is the symmetry group of the cylinder?

For what group operations is it true that:

$$\begin{array}{ccc} \mathbb{R}^2 & \xrightarrow{\pi} & \mathbb{R} \times S^1 \\ \downarrow g & & \downarrow h \\ \mathbb{R}^2 & \xrightarrow{\pi} & \mathbb{R} \times S^1 \end{array} \qquad \begin{array}{ccc} x, Tx & \xrightarrow{\pi} & y \\ \downarrow g & & \downarrow h \\ g(x), g(Tx) & \xrightarrow{\pi} & h(y) \end{array}$$

For the right equation to hold we must have

$$Tg(x) = gT(x)$$

that is, g and T commute.

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So we want

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$$gT = Tg$$

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So we want

$$gT = Tg$$
$$\left(\begin{array}{c|c} R & v_x \\ \hline & v_y \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} I_2 & L \\ \hline & 0 \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} I_2 & L \\ \hline & 0 \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} R & v_x \\ \hline & v_y \\ \hline 0 & 1 \end{array} \right)$$

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So we want

$$gT = Tg$$
$$\left(\begin{array}{c|c} R & \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} I_2 & \begin{pmatrix} L \\ 0 \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} I_2 & \begin{pmatrix} L \\ 0 \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} R & \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right)$$
$$\left(\begin{array}{c|c} R & R \begin{pmatrix} L \\ 0 \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} R & \begin{pmatrix} L \\ 0 \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right)$$

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So we want

$$gT = Tg$$
$$\left(\begin{array}{c|c} R & \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} I_2 & \begin{pmatrix} L \\ 0 \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} I_2 & \begin{pmatrix} L \\ 0 \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} R & \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right)$$
$$\left(\begin{array}{c|c} R & R \begin{pmatrix} L \\ 0 \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} R & \begin{pmatrix} L \\ 0 \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right)$$

and thus

Cylinder Symmetry

So we want

$$gT = Tg$$
$$\left(\begin{array}{c|c} R & \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} I_2 & \begin{pmatrix} L \\ 0 \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} I_2 & \begin{pmatrix} L \\ 0 \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} R & \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right)$$
$$\left(\begin{array}{c|c} R & R \begin{pmatrix} L \\ 0 \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} R & \begin{pmatrix} L \\ 0 \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right)$$

and thus

$$R \begin{pmatrix} L \\ 0 \end{pmatrix} = \begin{pmatrix} L \\ 0 \end{pmatrix}$$

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$$\left(\begin{array}{c|c} R & \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} I_2 & \begin{pmatrix} L \\ 0 \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} I_2 & \begin{pmatrix} L \\ 0 \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} R & \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right)$$
$$\left(\begin{array}{c|c} R & R \begin{pmatrix} L \\ 0 \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} R & \begin{pmatrix} L \\ 0 \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right)$$

and thus

$$R \begin{pmatrix} L \\ 0 \end{pmatrix} = \begin{pmatrix} L \\ 0 \end{pmatrix}$$

and R is the identity and $g \in T(2)$ is a translation.

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$$\left(\begin{array}{c|c} R & \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} I_2 & \begin{pmatrix} L \\ 0 \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} I_2 & \begin{pmatrix} L \\ 0 \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) \left(\begin{array}{c|c} R & \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right)$$
$$\left(\begin{array}{c|c} R & R \begin{pmatrix} L \\ 0 \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right) = \left(\begin{array}{c|c} R & \begin{pmatrix} L \\ 0 \end{pmatrix} + \begin{pmatrix} v_x \\ v_y \end{pmatrix} \\ \hline 0 & 1 \end{array} \right)$$

and thus

$$R \begin{pmatrix} L \\ 0 \end{pmatrix} = \begin{pmatrix} L \\ 0 \end{pmatrix}$$

and R is the identity and $g \in T(2)$ is a translation.

Identifying two that differ by T gives $S^1 \times \mathbb{R} \simeq SO(2) \times T(1)$.

The SR Cylinder

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The Invariance group of $\mathbb{R}^{1,1}$ is the Poincaré group, $ISO(1, 1)$:

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The SR Cylinder

The Invariance group of $\mathbb{R}^{1,1}$ is the Poincaré group, $ISO(1, 1)$:

$$\left(\begin{array}{c|c} \Lambda & v_t \\ \hline 0 & 1 \end{array} \right),$$

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The Invariance group of $\mathbb{R}^{1,1}$ is the Poincaré group, $ISO(1, 1)$:

$$\left(\begin{array}{c|c} \Lambda & v_t \\ \hline 0 & 1 \end{array} \right),$$

We identify points that differ by

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The Invariance group of $\mathbb{R}^{1,1}$ is the Poincaré group, $ISO(1, 1)$:

$$\left(\begin{array}{c|c} \Lambda & v_t \\ \hline 0 & 1 \end{array} \right),$$

We identify points that differ by

$$T_{0,L} = \left(\begin{array}{c|c} I_2 & 0 \\ \hline 0 & L \end{array} \right),$$

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$$\left(\begin{array}{c|c} \Lambda & v_t \\ \hline 0 & 1 \end{array} \right),$$

We identify points that differ by

$$T_{0,L} = \left(\begin{array}{c|c} I_2 & 0 \\ \hline 0 & L \end{array} \right),$$

The commuting group operations must satisfy

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$$\left(\begin{array}{c|c} \Lambda & v_t \\ \hline 0 & 1 \end{array} \right),$$

We identify points that differ by

$$T_{0,L} = \left(\begin{array}{c|c} I_2 & 0 \\ \hline 0 & L \end{array} \right),$$

The commuting group operations must satisfy

$$\Lambda \begin{pmatrix} 0 \\ L \end{pmatrix} = \begin{pmatrix} 0 \\ L \end{pmatrix}$$

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The Invariance group of $\mathbb{R}^{1,1}$ is the Poincaré group, $ISO(1, 1)$:

$$\left(\begin{array}{c|c} \Lambda & v_t \\ \hline 0 & 1 \end{array} \right),$$

We identify points that differ by

$$T_{0,L} = \left(\begin{array}{c|c} I_2 & 0 \\ \hline 0 & L \end{array} \right),$$

The commuting group operations must satisfy

$$\Lambda \begin{pmatrix} 0 \\ L \end{pmatrix} = \begin{pmatrix} 0 \\ L \end{pmatrix}$$

And the symmetry group is translations again.

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Cylinder Frames

Up to translations of the origin, there is an unique privileged system of coordinates on $\mathbb{R}^1 \times S^1$ that respects the symmetry.

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Cylinder Frames

Up to translations of the origin, there is an unique privileged system of coordinates on $\mathbb{R}^1 \times S^1$ that respects the symmetry. Moreover the symmetries help us construct this frame.

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Up to translations of the origin, there is an unique privileged system of coordinates on $\mathbb{R}^1 \times S^1$ that respects the symmetry. Moreover the symmetries help us construct this frame.

So in any other coordinate system either

- The metric splits but the coordinates do not.
- The coordinates split but the metric does not.

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Up to translations of the origin, there is an unique privileged system of coordinates on $\mathbb{R}^1 \times S^1$ that respects the symmetry. Moreover the symmetries help us construct this frame.

So in any other coordinate system either

- The metric splits but the coordinates do not.
- The coordinates split but the metric does not.

The frame we constructed for O' kept the metric diagonal, but the coordinates didn't respect the symmetry.

Cylinder Frames

Let's construct a frame for O' that respects the symmetry.

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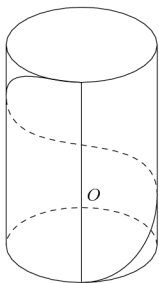
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Let's construct a frame for O' that respects the symmetry.



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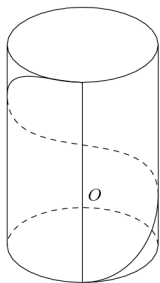
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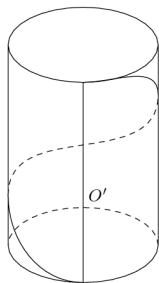
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Cylinder Frames

Let's construct a frame for O' that respects the symmetry.



twist
→



Cylinder Frames

Let's construct a frame for O' that respects the symmetry.



$$f : (t, [x]) \rightarrow (t, [x - vt])$$

where $[x]$ means the image of x in the cylinder.

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$$\begin{pmatrix} t \\ [x] \end{pmatrix} \mapsto \begin{pmatrix} t \\ [x - vt] \end{pmatrix}$$

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$$\begin{pmatrix} t \\ [x] \end{pmatrix} \mapsto \begin{pmatrix} t \\ [x - vt] \end{pmatrix}$$
$$f^{-1} = \begin{pmatrix} t' \\ [x' + vt'] \end{pmatrix}$$

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$$\begin{aligned} \begin{pmatrix} t \\ [x] \end{pmatrix} &\mapsto \begin{pmatrix} t \\ [x - vt] \end{pmatrix} \\ f^{-1} &= \begin{pmatrix} t' \\ [x' + vt'] \end{pmatrix} \\ Df^{-1} &= \begin{pmatrix} 1 & 0 \\ 1 & -v \end{pmatrix} \end{aligned}$$

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$$\begin{aligned} \begin{pmatrix} t \\ [x] \end{pmatrix} &\mapsto \begin{pmatrix} t \\ [x - vt] \end{pmatrix} \\ f^{-1} &= \begin{pmatrix} t' \\ [x' + vt'] \end{pmatrix} \\ Df^{-1} &= \begin{pmatrix} 1 & 0 \\ 1 & -v \end{pmatrix} \\ g' &= (Df^{-1})^t g Df^{-1} \end{aligned}$$

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$$\begin{aligned} \begin{pmatrix} t \\ [x] \end{pmatrix} &\mapsto \begin{pmatrix} t \\ [x - vt] \end{pmatrix} \\ f^{-1} &= \begin{pmatrix} t' \\ [x' + vt'] \end{pmatrix} \\ Df^{-1} &= \begin{pmatrix} 1 & 0 \\ 1 & -v \end{pmatrix} \\ g' &= (Df^{-1})^t g Df^{-1} \\ &= \begin{pmatrix} 1 & 1 \\ 0 & -v \end{pmatrix} \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix} \begin{pmatrix} 1 & 0 \\ 1 & -v \end{pmatrix} \end{aligned}$$

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$$\begin{aligned} \begin{pmatrix} t \\ [x] \end{pmatrix} &\mapsto \begin{pmatrix} t \\ [x - vt] \end{pmatrix} \\ f^{-1} &= \begin{pmatrix} t' \\ [x' + vt'] \end{pmatrix} \\ Df^{-1} &= \begin{pmatrix} 1 & 0 \\ 1 & -v \end{pmatrix} \\ g' &= (Df^{-1})^t g Df^{-1} \\ &= \begin{pmatrix} 1 & 1 \\ 0 & -v \end{pmatrix} \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix} \begin{pmatrix} 1 & 0 \\ 1 & -v \end{pmatrix} \\ &= \begin{pmatrix} -1 & -v \\ -v & 1 + v^2 \end{pmatrix} \end{aligned}$$

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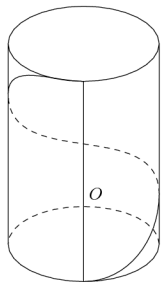
$$\begin{aligned} \begin{pmatrix} t \\ [x] \end{pmatrix} &\mapsto \begin{pmatrix} t \\ [x - vt] \end{pmatrix} \\ f^{-1} &= \begin{pmatrix} t' \\ [x' + vt'] \end{pmatrix} \\ Df^{-1} &= \begin{pmatrix} 1 & 0 \\ 1 & -v \end{pmatrix} \\ g' &= (Df^{-1})^t g Df^{-1} \\ &= \begin{pmatrix} 1 & 1 \\ 0 & -v \end{pmatrix} \begin{pmatrix} -1 & 0 \\ 0 & 1 \end{pmatrix} \begin{pmatrix} 1 & 0 \\ 1 & -v \end{pmatrix} \\ &= \begin{pmatrix} -1 & -v \\ -v & 1 + v^2 \end{pmatrix} \end{aligned}$$

Which is not diagonal.

Topological Invariant

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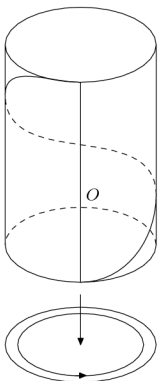
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- The number of times the path wraps around the cylinder is the *winding number*.

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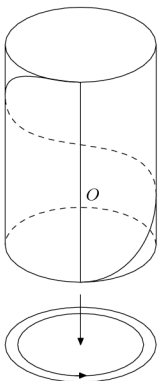
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- The number of times the path wraps around the cylinder is the *winding number*.
- This makes sense as long as we project points down in a manner *orthogonal* to the space surfaces.

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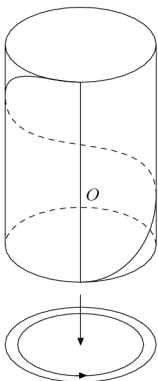
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- The number of times the path wraps around the cylinder is the *winding number*.
- This makes sense as long as we project points down in a manner *orthogonal* to the space surfaces.
- This invariant describes twin aging.

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- The twin paradox is possible without acceleration.

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- The twin paradox is possible without acceleration.
- Differential aging is always accompanied by another asymmetry.

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- The twin paradox is possible without acceleration.
- Differential aging is always accompanied by another asymmetry.
- The SR cylinder actually has more in common with GR.

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- The twin paradox is possible without acceleration.
- Differential aging is always accompanied by another asymmetry.
- The SR cylinder actually has more in common with GR.
- It possessed a preferred frame due to symmetry.

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