

§ Cosmology

Friedmann-Lemaitre-Robertson-Walker model

$$(M, g), \quad g = -dt^2 + a^2(t) \left(\frac{1}{1-kr^2} dr^2 + r^2 d\theta^2 + r^2 \sin^2 \theta d\varphi^2 \right)$$

$$\omega^0 = dt, \omega^1 = a(t)(1-kr^2)^{-\frac{1}{2}} dr, \omega^2 = a(t)r d\theta, \omega^3 = a(t)r \sin \theta d\varphi$$

$\{\omega^0, \omega^1, \omega^2, \omega^3\}$ is an orthonormal coframe

$$d\omega^i = \omega^j \wedge \omega_k^i$$

$$\Omega_i^j = d\omega_i^j - \omega_i^k \wedge \omega_k^j$$

$$R_{ij} = \sum_k R_{kij}^k, \quad R_{iji}^j = \Omega_i^j(E_i, E_j)$$

$$d\omega^1 = \dot{a}(1-kr^2)^{-\frac{1}{2}} dt \wedge dr = \omega^0 \wedge \omega_0^1 + \omega^2 \wedge \omega_2^1 + \omega^3 \wedge \omega_3^1$$

$$= dt \wedge \omega_0^1 + X \theta \wedge \omega_2^1 + X \phi \wedge \omega_3^1, \quad \therefore \omega_0^1 = \dot{a}(1-kr^2)^{-\frac{1}{2}} dr = \omega_1^0$$

$$d\omega^2 = \dot{a} r dt \wedge d\theta + a dr \wedge d\theta = \omega^0 \wedge \omega_0^2 + \omega^1 \wedge \omega_1^2 + \omega^3 \wedge \omega_3^2$$

$$= dt \wedge \omega_0^2 + (1-kr^2)^{-\frac{1}{2}} dr \wedge \omega_1^2 + \omega^3 \wedge \omega_3^2$$

$$\therefore \omega_0^2 = \dot{a} r dt, \quad \omega_1^2 = (1-kr^2)^{-\frac{1}{2}} dr = -\omega_2^1$$

$$d\omega^3 = \dot{a} r \sin \theta dt \wedge d\varphi + a \sin \theta dr \wedge d\varphi + ar \cos \theta d\theta \wedge d\varphi$$

$$= \omega^0 \wedge \omega_0^3 + \omega^1 \wedge \omega_1^3 + \omega^2 \wedge \omega_2^3$$

$$= dt \wedge \omega_0^3 + (1-kr^2)^{-\frac{1}{2}} dr \wedge \omega_1^3 + \omega^2 \wedge \omega_2^3$$

$$\therefore \omega_0^3 = \dot{a} r \sin \theta dt, \quad \omega_1^3 = -\omega_3^1 = (1-kr^2)^{-\frac{1}{2}} \sin \theta dr, \quad \omega_2^3 = -\omega_3^2 = \cos \theta d\varphi$$

$$\Omega_1^0 = d\omega_1^0 - (\dots), \quad (\dots) \text{中皆為 } 0$$

$$= d(\dot{a}(1-kr^2)^{-\frac{1}{2}} dr) = \ddot{a}(1-kr^2)^{-\frac{1}{2}} dt \wedge dr = \frac{\ddot{a}}{a} \omega^0 \wedge \omega^1 = \Omega_0^1$$

$$\Omega_2^0 = \Omega_0^2 = d\omega_0^2 - (\omega_2^1 \wedge \omega_1^0 + \omega_2^3 \wedge \omega_3^0) = \ddot{a} r dt \wedge d\theta = \frac{\ddot{a}}{a} \omega^0 \wedge \omega^2$$

Where $d\omega_2^0 = d(\dot{a}r d\theta) = \dot{a} dr \wedge d\theta + \ddot{a} r dt \wedge d\theta$

$$\omega_2^1 \wedge \omega_1^0 = -(1-kr^2)^{\frac{1}{2}} d\theta \wedge \dot{a}(1-kr^2)^{-\frac{1}{2}} dr = \dot{a} dr \wedge d\theta ,$$

$$\omega_2^3 \wedge \omega_3^0 = \cos d\varphi \wedge \dot{a} r \sin \theta d\varphi = 0$$

$$\Omega_3^0 = d\omega_3^0 - (\omega_3^1 \wedge \omega_1^0 + \omega_3^2 \wedge \omega_2^0)$$

$$= d(\dot{a} r \sin \theta d\varphi) - ((1-kr^2) \sin \theta d\varphi \wedge \dot{a}(1-kr^2)^{-\frac{1}{2}} dr + (-\cos \theta d\varphi) \wedge \dot{a} r d\theta)$$

$$= \ddot{a} r \sin \theta dt \wedge d\varphi + \dot{a} \sin \theta dr \wedge d\varphi + \dot{a} r \cos \theta d\theta \wedge d\varphi + \dot{a} \sin \theta d\varphi \wedge dr - \dot{a} r \cos \theta d\theta \wedge d\varphi$$

$$= \frac{\ddot{a}}{a} \omega^0 \wedge \omega^3$$

$$\Omega_1^2 = d\omega_1^2 - (\omega_1^0 \wedge \omega_0^2 + \omega_1^3 \wedge \omega_3^2)$$

$$= d((1-kr^2)^{\frac{1}{2}} d\theta) - (\dot{a}(1-kr^2)^{-\frac{1}{2}} dr \wedge \dot{a} r d\theta + (1-kr^2)^{\frac{1}{2}} \sin \theta d\varphi \wedge \cos \theta d\varphi)$$

$$= \frac{1}{2}(1-kr^2)^{-\frac{1}{2}} (-2kr) dr \wedge d\theta - (\dot{a})^2 r (1-kr^2)^{-\frac{1}{2}} dr \wedge d\theta$$

$$= \frac{k}{a^2} \omega^2 \wedge \omega^1 + \frac{(\dot{a})^2}{a^2} \omega^2 \wedge \omega^1 = \left(\frac{k}{a^2} + \frac{(\dot{a})^2}{a^2} \right) \omega^2 \wedge \omega^1$$

同理

$$\Omega_1^3 = -\Omega_3^1 = \left(\frac{k}{a^2} + \frac{(\dot{a})^2}{a^2} \right) \omega^3 \wedge \omega^1$$

$$\Omega_2^3 = -\Omega_3^2 = \left(\frac{k}{a^2} + \frac{(\dot{a})^2}{a^2} \right) \omega^3 \wedge \omega^2$$

$$R_{00} = R_{100}^1 + R_{200}^2 + R_{300}^3 = -(R_{010}^1 + R_{020}^2 + R_{030}^3) = -\frac{3\ddot{a}}{a}$$

Where $R_{010}^1 = \Omega_0^1(E_0, E_1) = \frac{\ddot{a}}{a}$, $R_{020}^2 = \Omega_0^2(E_0, E_2) = \frac{\ddot{a}}{a}$, $R_{030}^3 = \Omega_0^3(E_0, E_3) = \frac{\ddot{a}}{a}$

$$R_{11} = R_{011}^0 + R_{211}^2 + R_{311}^3 = -(R_{101}^0 + R_{121}^2 + R_{133}^1)$$

$$= \frac{\ddot{a}}{a} + \frac{2(\dot{a})^2}{a^2} + \frac{2k}{a^2}$$

$$R_{101}^0 = -\frac{\ddot{a}}{a}, \quad R_{121}^2 = \Omega_1^2(E_1, E_2) = -\left(\frac{k}{a^2} + \frac{(\dot{a})^2}{a^2}\right), \quad R_{131}^3 = \Omega_1^3(E_1, E_3) = -\left(\frac{k}{a^2} + \frac{(\dot{a})^2}{a^2}\right)$$

同理可求 $R_{22} = R_{33} = \dots = R_{11}$