

An Introduction to Heegaard Floer Homology

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1. Introduction

The aim of these notes is to give an introduction to Heegaard Floer homology for closed oriented 3-manifolds [31]. We will also discuss a related Floer homology invariant for knots in S^3 [29], [34].

Let Y be an oriented closed 3-manifold. The simplest version of Heegaard Floer homology associates to Y a finitely generated Abelian group $\widehat{HF}(Y)$. This homology is defined with the help of Heegaard diagrams and Lagrangian Floer homology. Variants of this construction give related invariants $HF^+(Y)$, $HF^-(Y)$, $HF^\infty(Y)$.

While its construction is very different, Heegaard Floer homology is closely related to Seiberg-Witten Floer homology [10, 15, 17], and instanton Floer homology [3, 4, 7]. In particular it grew out of our attempt to find a more topological description of Seiberg-Witten theory for three-manifolds.

2. Heegaard decompositions and diagrams

Let Y be a closed oriented three-manifold. In this section we describe decompositions of Y into more elementary pieces, called handlebodies.

A *genus g handlebody* U is diffeomorphic to a regular neighborhood of a bouquet of g circles in \mathbb{R}^3 ; see Figure 1. The boundary of U is an oriented surface of genus g . If we glue two such handlebodies together along their common boundary, we get a closed 3-manifold

$$Y = U_0 \cup_\Sigma U_1$$

oriented so that Σ is the oriented boundary of U_0 . This is called a Heegaard decomposition for Y .

2.1. Examples. The simplest example is the (genus 0) decomposition of S^3 into two balls. A similar example is given by taking a tubular neighborhood of the unknot in S^3 . Since the complement is also a solid torus, we get a genus 1 Heegaard decomposition of S^3 .

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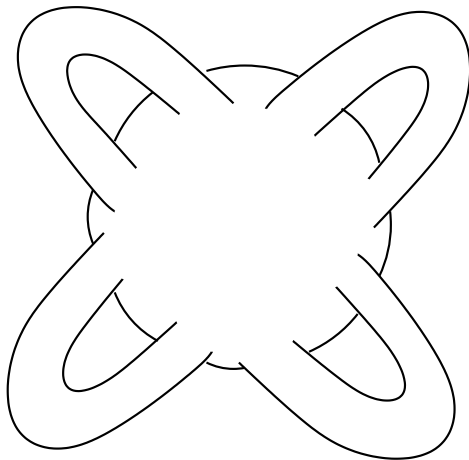


FIGURE 1. A handlebody of genus 4.

Other simple examples are given by lens spaces. Take

$$S^3 = \{(z, w) \in \mathbb{C}^2 \mid |z|^2 + |w|^2 = 1\}$$

Let $(p, q) = 1$, $1 \leq q < p$. The lens space $L(p, q)$ is given by dividing out S^3 by the free \mathbb{Z}/p action

$$f : (z, w) \longrightarrow (\alpha z, \alpha^q w),$$

where $\alpha = e^{2\pi i/p}$. Clearly $\pi_1(L(p, q)) = \mathbb{Z}/p$. Note also that the solid tori $U_0 = \{|z| \leq \frac{1}{2}\}$, $U_1 = \{|z| \geq \frac{1}{2}\}$ are preserved by the action, and their quotients are also solid tori. This gives a genus 1 Heegaard decomposition of $L(p, q)$.

2.2. Existence of Heegaard decompositions. While the small genus examples might suggest that 3-manifolds that admit Heegaard decompositions are special, in fact the opposite is true:

THEOREM 2.1. ([39]) *Let Y be an oriented closed three-dimensional manifold. Then Y admits a Heegaard decomposition.*

PROOF. Start with a triangulation of Y . The union of the vertices and the edges gives a graph in Y . Let U_0 be a small neighborhood of this graph. In other words replace each vertex by a ball, and each edge by a solid cylinder. By definition U_0 is a handlebody. It is easy to see that $Y - U_0$ is also a handlebody, given by a regular neighborhood of a graph on the centers of the triangles and tetrahedra in the triangulation. \square

2.3. Stabilizations. It follows from the above proof that the same three-manifold admits lots of different Heegaard decompositions. In particular, given a Heegaard decomposition $Y = U_0 \cup_{\Sigma} U_1$ of genus g , we can define another decomposition of genus $g + 1$ by choosing two points in Σ and connecting them by a small unknotted arc γ in U_1 . Let U'_0 be the union of U_0 and a small tubular neighborhood N of γ . Similarly let $U'_1 = U_1 - N$. The new decomposition

$$Y = U'_0 \cup_{\Sigma'} U'_1$$

is called the *stabilization* of $Y = U_0 \cup_{\Sigma} U_1$. Clearly $g(\Sigma') = g(\Sigma) + 1$. For an easy example note that the genus 1 decomposition of S^3 described earlier is the stabilization of the genus 0 decomposition.

According to a theorem of Singer [39], any two Heegaard decompositions can be connected by stabilizations (and destabilizations):

THEOREM 2.2. *Let (Y, U_0, U_1) and (Y, U'_0, U'_1) be two Heegaard decompositions of Y of genus g and g' respectively. Then for k large enough the $(k - g')$ -fold stabilization of the first decomposition is diffeomorphic to the $(k - g)$ -fold stabilization of the second decomposition.*

2.4. Heegaard diagrams. In view of Theorem 2.2, if we find an invariant for Heegaard decompositions with the property that it does not change under stabilization, then this is in fact a three-manifold invariant. For example the Casson invariant [1, 37] is defined in this way. However, for the definition of Heegaard Floer homology we need some additional information which is given by diagrams.

Let us start with a handlebody U of genus g .

DEFINITION 2.3. A set of attaching circles $(\gamma_1, \dots, \gamma_g)$ for U is a collection of closed embedded curves in $\Sigma_g = \partial U$ with the following properties

- The curves γ_i are disjoint from each other.
- $\Sigma_g - \gamma_1 - \dots - \gamma_g$ is connected.
- The curves γ_i bound disjoint embedded disks in U .

REMARK 2.4. The second property in the above definition is equivalent to the property that $([\gamma_1], \dots, [\gamma_g])$ are linearly independent in $H_1(\Sigma, \mathbb{Z})$.

DEFINITION 2.5. Let (Σ_g, U_0, U_1) be a genus g Heegaard decomposition for Y . A *compatible Heegaard diagram* is given by Σ_g together with a collection of curves $\alpha_1, \dots, \alpha_g, \beta_1, \dots, \beta_g$ with the property that $(\alpha_1, \dots, \alpha_g)$ is a set of attaching circles for U_0 and $(\beta_1, \dots, \beta_g)$ is a set of attaching circles for U_1 .

REMARK 2.6. A Heegaard decomposition of genus $g > 1$ admits lots of different compatible Heegaard diagrams.

In the opposite direction any diagram $(\Sigma_g, \alpha_1, \dots, \alpha_g, \beta_1, \dots, \beta_g)$ where the α and β curves satisfy the first two conditions in Definition 2.3 determines uniquely a Heegaard decomposition and therefore a 3-manifold.

2.5. Examples. It is helpful to look at a few examples. The genus 1 Heegaard decomposition of S^3 corresponds to a diagram $(\Sigma_1, \alpha, \beta)$ where α and β meet transversely in a unique point. $S^1 \times S^2$ corresponds to $(\Sigma_1, \alpha, \alpha)$.

The lens space $L(p, q)$ has a diagram $(\Sigma_1, \alpha, \beta)$ where α and β intersect at p points and in a standard basis $x, y \in H_1(\Sigma_1) = \mathbb{Z} \oplus \mathbb{Z}$, $[\alpha] = y$ and $[\beta] = px + qy$.

Another example is given in Figure 2. Here we think of S^2 as the plane together with the point at infinity. In the picture the two circles on the left are identified, or equivalently we glue a handle to S^2 along these circles. Similarly we identify the two circles on the right side of the picture. After this identification the two horizontal lines become closed circles α_1 and α_2 . As for the two β curves, β_1 lies in the plane and β_2 goes through both handles once.

DEFINITION 2.7. We can define a one-parameter family of Heegaard diagrams by changing the right side of Figure 2. For $n > 0$ instead of twisting around the