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The Cartan machinery is also applied to obtain explicit solutions of PDEs, via Darboux's method, the method of characteristics, and Cartan's method of equivalence. This text is suitable for a one-year graduate course in differential geometry. It has numerous exercises and examples throughout.

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Cartan for Beginners: Differential Geometry via Moving Frames and Exterior Differential Systems, Second Edition. p. 17, Def. 1.6.4, line 2 change  $\omega|_e$  to  $\omega_e$  p. 17, line -1 change  $Ad_{-1}$  to  $Ad(a^{-1})$  p. 18, Def. 1.6.9 right-hand side of displayed equation should read  $[\omega(X), \theta(Y)] - [\omega(Y), \theta(X)]$  (not +) p. 19, Proof of 1.6.10, last line the "uniqueness" referred to is in the Frobenius Theorem p. 20, Exercise 1.6.14.3 change "complete the proof of" to "prove" p. 20 ...

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Maurer-Cartan form. We give two examples of the geometry of curves in homogeneous spaces: classifying holomorphic mappings of the complex plane under fractional linear transformations in §1.7, and classifying curves in  $E^3$  under Euclidean motions (i.e., rotations and translations) in §1.8. We also include exercises on plane curves in other geometries.

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In the mathematical field of differential geometry, a Cartan connection is a flexible generalization of the notion of an affine connection. It may also be regarded as a specialization of the general concept of a principal connection, in which the geometry of the principal bundle is tied to the geometry of the base manifold using a solder form.

### **Cartan connection - Wikipedia**

geometry and partial differential equations. These ideas originated about a century ago in the works of several mathematicians, including Gaston Darboux, Edouard Goursat and, most importantly, Elie Cartan. Over the years these techniques have been refined and extended; major contributors to the subject are mentioned below, under "Further Reading".

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Elie Cartan pioneered the method of moving frames as a coordinate free way of studying differential geometry. A moving frame is a basis of vectors (tangent, movement, directional etc.) at each point of a curve, surface, or manifold. If the manifold is Riemannian (has a Riemannian metric), one considers orthonormal bases.

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