
Compliments to Bad Spaces

Oleg Viro

December 5, 2007

Human factor

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Differential Spaces

Finite Topological
Spaces

The ways that mathematical theories find to the core of mainstream mathematical curriculums are strongly influenced by accidental circumstances.

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Individuals shape Mathematics.

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The shapes are not perfect.

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differentiable manifolds and finite topological spaces.

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I am going to emphasize **opportunities**

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Take fresher examples:
differentiable manifolds and finite topological spaces.

I am going to emphasize **opportunities**,
but need to motivate the positive things by some criticism.

The opportunities are not lost yet.

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The modern definition of differentiable manifold was given in the book by O. Veblen and J.H.C. Whitehead [The foundations of differential geometry](#). Cambridge tracts in mathematics and mathematical physics.

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Inspired by H.Weyl's book on Riemann surfaces *Die Idee der Riemannschen Fläche* published in 1913.

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The traditional definition of smooth structures is quite long

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The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures

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The traditional definition of smooth structures is quite long and different from definitions of similar and closely related structures studied in algebraic geometry and topology.

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Smooth structures are traditionally defined only on manifolds.

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a subset \mapsto a subspace,

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a quotient set \mapsto a quotient space, etc.

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The image of a differential manifold under a differentiable map may be not a manifold,

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Smooth structures are traditionally defined only on manifolds. This deprives us of flexibility that we enjoy in general topology, where any set-theoretic construction has a topological counter-part:

a subset \mapsto a subspace,

a quotient set \mapsto a quotient space, etc.

The image of a differential manifold under a differentiable map may be not a manifold, and hence not eligible to bear any trace of a differential structure.

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Terminology related to differentiable manifolds does not let us speak on bad spaces.

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Is this *good*?

Is this *acceptable*?

Even if *you hate pathology*

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Terminology related to differentiable manifolds does not let us speak on bad spaces.

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Even if *you hate pathology*, do you know beforehand what is *pathologically bad* in Mathematics?

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smooth structure on a Cantor set?

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smooth structure on a *Cantor set*? , a *fractal set*?

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Why?

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Why? Was it not a *right time* for this?

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smooth structure on a *Cantor set*? , a *fractal set*?

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Why? Was it not a *right time* for this?

Were there not *right people*?

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Let X be a set and r be a natural number or ∞ .

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Let X be a set and r be a natural number or ∞ .

A *differential structure* of class C^r on X

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Let X be a set and r be a natural number or ∞ .

A *differential structure* of class C^r on X

not differentiable, but differential,
for nobody is going to differentiate it!

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Let X be a set and r be a natural number or ∞ .

A *differential structure* of class C^r on X is an algebra $C^r(X)$ of functions $X \rightarrow \mathbb{R}$ such that:

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A **differential structure** of class C^r on X is an algebra $C^r(X)$ of functions $X \rightarrow \mathbb{R}$ such that:

1. *Composition of functions belonging to $C^r(X)$ with C^r -differentiable function belongs to $C^r(X)$.*

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In other words, $(g \circ f : X \rightarrow \mathbb{R}) \in C^r(X)$

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In other words, $(g \circ f : X \rightarrow \mathbb{R}) \in C^r(X)$

if $f : X \rightarrow U$ is defined by $f_1, \dots, f_n \in C^r(X)$,
 $U \subset \mathbb{R}^n$ is an open set,

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In other words, $(g \circ f : X \rightarrow \mathbb{R}) \in C^r(X)$

if $f : X \rightarrow U$ is defined by $f_1, \dots, f_n \in C^r(X)$,

$U \subset \mathbb{R}^n$ is an open set,

and $g : U \rightarrow \mathbb{R}$ is a C^r -map.

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Finite Topological Spaces

Let X be a set and r be a natural number or ∞ .

A **differential structure** of class C^r on X is an algebra $C^r(X)$ of functions $X \rightarrow \mathbb{R}$ such that:

1. *Composition of functions belonging to $C^r(X)$ with C^r -differentiable function belongs to $C^r(X)$.*

In other words, $(g \circ f : X \rightarrow \mathbb{R}) \in C^r(X)$

if $f : X \rightarrow U$ is defined by $f_1, \dots, f_n \in C^r(X)$,

$U \subset \mathbb{R}^n$ is an open set,

and $g : U \rightarrow \mathbb{R}$ is a C^r -map.

2. *$f \in C^r(X)$ if near each point of X it coincides with a function belonging to $C^r(X)$.*

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and $g : U \rightarrow \mathbb{R}$ is a C^r -map.

2. *$f \in C^r(X)$ if near each point of X it coincides with a function belonging to $C^r(X)$.*

In other words, $f \in C^r(X)$ if for each $a \in X$ there exist $g, h \in C^r(X)$ such that $h(a) > 0$ and $f(x) = g(x)$ for each x with $h(x) > 0$.

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Finite Topological Spaces

A pair consisting of a set X and a differential structure of class C^r on X is called a *differential space of class C^r*

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Finite Topological Spaces

A pair consisting of a set X and a differential structure of class C^r on X is called a *differential space of class C^r* , or just a *C^r -space*.

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Examples

1. Any smooth manifold X with algebra $C^r(X)$ of C^r -differentiable functions.

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Examples

1. Any smooth manifold X with algebra $C^r(X)$ of C^r -differentiable functions.
2. *Discrete space*. Any X and all functions $X \rightarrow \mathbb{R}$.

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1. Any smooth manifold X with algebra $C^r(X)$ of C^r -differentiable functions.
2. *Discrete space*. Any X and all functions $X \rightarrow \mathbb{R}$.
3. *Indiscrete space*. Any X and all **constant** functions $X \rightarrow \mathbb{R}$.

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Examples

1. Any smooth manifold X with algebra $C^r(X)$ of C^r -differentiable functions.
2. *Discrete space*. Any X and all functions $X \rightarrow \mathbb{R}$.
3. *Indiscrete space*. Any X and all **constant** functions $X \rightarrow \mathbb{R}$.
4. *Topological space*. A topological space X with all **continuous** functions $X \rightarrow \mathbb{R}$.

Differentiable maps

Let X and Y be C^r -spaces.

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Finite Topological Spaces

Let X and Y be C^r -spaces.

$f : X \rightarrow Y$ is called **a C^r -map**

if $f \circ \phi \in C^r(X)$ for any $\phi \in C^r(Y)$.

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A C^r -map $f : X \rightarrow Y$ induces $f^* : C^r(Y) \rightarrow C^r(X)$.

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C^r -spaces and C^r -maps constitute a **category**.

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C^r -spaces and C^r -maps constitute a **category**.

Isomorphisms of the category are called C^r -diffeomorphisms.

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Finite Topological Spaces

For any set \mathcal{F} of real valued functions on a set X , there exists a minimal C^r -structure on X containing \mathcal{F} .

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For example, coordinate projections $\mathbb{R}^n \rightarrow \mathbb{R}$ generate the standard differential structure on \mathbb{R}^n .

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The C^r -structure generated by a C^s -structure \mathcal{C} with $s < r$ coincides with \mathcal{C} .

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The C^r -structure generated by a C^s -structure \mathcal{C} with $s < r$ coincides with \mathcal{C} .

For example, a C^0 -structure

which is nothing but a topological structure.

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For example, a C^0 -structure is a C^r -structure for any r . On the other hand, when *decreasing* r , we have to *add* new functions.

A C^r -structure \mathcal{A} generated as a C^r -structure by a C^s -structure \mathcal{B} with $s > r$ is called a *relaxation* of \mathcal{B} .

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A C^r -structure \mathcal{A} generated as a C^r -structure by a C^s -structure \mathcal{B} with $s > r$ is called a *relaxation* of \mathcal{B} .

Then \mathcal{B} is called a *refinement* of \mathcal{A} .

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Let X be a differential space and $A \subset X$.

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Finite Topological Spaces

Let X be a differential space and $A \subset X$.

Restrictions to A of functions differentiable on X

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Finite Topological Spaces

Let X be a differential space and $A \subset X$.

Restrictions to A of functions differentiable on X do **not necessarily** constitute a differential structure on A .

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For example, if $X = \mathbb{R}$ and $A = \mathbb{R}_{>0} = \{x \mid x > 0\}$,

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Finite Topological Spaces

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Restrictions to A of functions differentiable on X do not necessarily constitute a differential structure on A .

For example, if $X = \mathbb{R}$ and $A = \mathbb{R}_{>0} = \{x \mid x > 0\}$, the function $A \rightarrow \mathbb{R} : x \mapsto \frac{1}{x}$ is not a restriction of any function continuous on \mathbb{R} ,

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Restrictions to A of functions differentiable on X generate a differential structure.

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Restrictions to A of functions differentiable on X generate a differential structure. This structure is said to be *induced* on A by the structure of X .

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Restrictions to A of functions differentiable on X generate a differential structure. This structure is said to be *induced* on A by the structure of X , and A equipped with this structure is called a *(differential) subspace* of X .

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Restrictions to A of functions differentiable on X generate a differential structure. This structure is said to be *induced* on A by the structure of X , and A equipped with this structure is called a *(differential) subspace* of X .

Whitney Problem: Describe the differential structure induced on a closed $X \subset \mathbb{R}^n$.

Embeddings

Let X and Y be differential spaces (of class C^r).

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Let X and Y be differential spaces (of class C^r).

A map $f : X \rightarrow Y$ is called a *differential embedding* if it defines a diffeomorphism $X \rightarrow f(X)$.

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For a differential space X , functions f_1, \dots, f_n define a differential embedding $f : X \rightarrow \mathbb{R}^n : x \mapsto (f_1(x), \dots, f_n(x))$

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Example

Consider the set \mathcal{C} of all differentiable functions $\mathbb{R} \rightarrow \mathbb{R}$ with derivative vanishing at 0 .

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Example

Consider the set \mathcal{C} of all differentiable functions $\mathbb{R} \rightarrow \mathbb{R}$ with derivative vanishing at 0 . *This is a differential structure.*

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Finite Topological Spaces

Consider the set \mathcal{C} of all differentiable functions $\mathbb{R} \rightarrow \mathbb{R}$ with derivative vanishing at 0 . *This is a differential structure.*

How does the space $(\mathbb{R}, \mathcal{C})$ look like?

Is it embeddable to \mathbb{R}^2 ?

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We **need** functions $u, v : \mathbb{R} \rightarrow \mathbb{R}$ with $u'(0) = v'(0) = 0$ such that any differential function $f : \mathbb{R} \rightarrow \mathbb{R}$ with $f'(0) = 0$ was a composition $F \circ (u \times v)$ for some differentiable $F : \mathbb{R}^2 \rightarrow \mathbb{R}$.

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A parametrization of semicubical parabola:

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Finite Topological Spaces

Multiplication. Let X and Y be C^r -spaces.

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Multiplication. Let X and Y be C^r -spaces.
The canonical way to define C^r -structure in $X \times Y$

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Finite Topological Spaces

Multiplication. Let X and Y be C^r -spaces.

The canonical way to define C^r -structure in $X \times Y$ is to generate it by

$$\{f \circ pr_X \mid f \in C^r(X)\} \cup \{g \circ pr_Y \mid g \in C^r(Y)\}.$$

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The C^r -structure in the quotient set X/\sim canonically defined by $C^r(X)$

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Factorization. Let X be a C^r -space and

\sim be an equivalence relation in X .

The C^r -structure in the quotient set X/\sim

canonically defined by $C^r(X)$

consists of $f : X/\sim \rightarrow \mathbb{R}$ such that

$$(f \circ pr : X \rightarrow \mathbb{R}) \in C^r(X).$$

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1. What differential space is obtained by identification of the end points of $[0, 1]$?

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Finite Topological Spaces

1. What differential space is obtained by identification of the end points of $[0, 1]$? Is it embeddable to \mathbb{R}^2 ?

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1. What differential space is obtained by identification of the end points of $[0, 1]$? Is it embeddable to \mathbb{R}^2 ?

If so, how does the the image look like?

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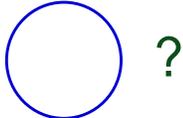
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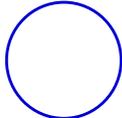
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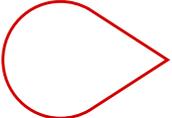
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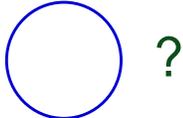
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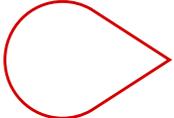
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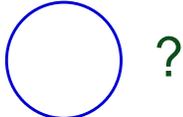
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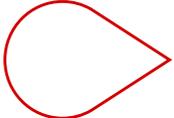
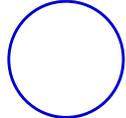
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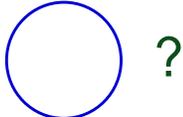
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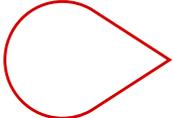
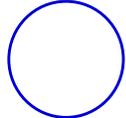
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No, like this:  ! Or that:  ! **But not this:**  !

2. What if we take $[0, 1.5]$ and identify each $x \in [0, 0.5]$ with $x + 1$?

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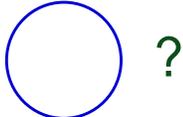
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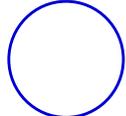
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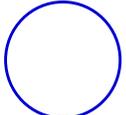
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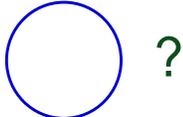
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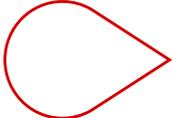
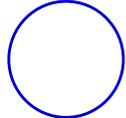
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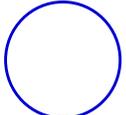
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New factorization:

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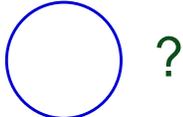
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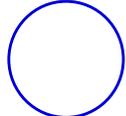
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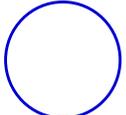
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New factorization:

Identifying end points of $[0, 1]$, identify also **tangent vectors!**

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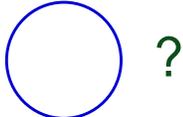
- **Examples of quotient spaces**

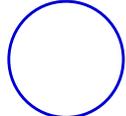
- Tangent vectors and dimensions

- Metric spaces

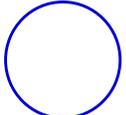
Finite Topological Spaces

1. What differential space is obtained by identification of the end points of $[0, 1]$? Is it embeddable to \mathbb{R}^2 ?

If so, how does the the image look like? Like this:  ?

No, like this:  ! Or that:  ! **But not this:**  !

2. What if we take $[0, 1.5]$ and identify each $x \in [0, 0.5]$ with $x + 1$?

Then we get really a space diffeomorphic to  .

New factorization:

Identifying end points of $[0, 1]$, identify also **tangent vectors!**

That is consider functions $f : [0, 1] \rightarrow \mathbb{R}$ with $f(0) = f(1)$ and $f'(0) = f'(1)$.

Examples of quotient spaces

- Human factor

Differential Spaces

- Differentiable

Manifolds

- What is wrong
- Political correctness in Mathematics

- Differential Structures

- Differential Spaces

- Differentiable maps

- Generating, refining, relaxing

- Subspaces

- Embeddings

- Example

- Constructing new differential spaces

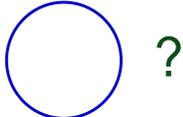
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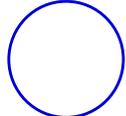
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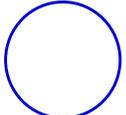
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The resulting space:  .

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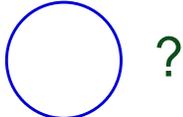
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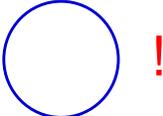
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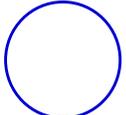
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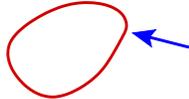
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The resulting space:  . Smooth, but with **jump of curvature.**

Tangent vectors and dimensions

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Differential Spaces

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Finite Topological Spaces

It is easier to define **cotangent** vectors.

Tangent vectors and dimensions

- Human factor

Differential Spaces

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Tangent vectors and dimensions

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Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $C^r(X)$.

Tangent vectors and dimensions

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Let X be a differential space and $p \in X$. Functions vanishing at p form a maximal ideal m_p of \mathbb{R} -algebra $C^r(X)$. The cotangent space $T_p^*(X)$ is m_p/m_p^2 .

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Tangent vectors and dimensions

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Tangent vectors and dimensions

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Other traditional definition of tangent vectors (via an equivalence of smooth paths)

Tangent vectors and dimensions

- Human factor

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Other traditional definition of tangent vectors (via an equivalence of smooth paths) gives another result

Tangent vectors and dimensions

- Human factor

Differential Spaces

- Differentiable

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- Examples of quotient spaces

- **Tangent vectors and dimensions**

- Metric spaces

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It can be defined as the space of **differentiations** of differentiable functions on X at p . As usual.

Other traditional definition of tangent vectors (via an equivalence of smooth paths) gives another result and does not give a vector space.

Tangent vectors and dimensions

- Human factor

Differential Spaces

- Differentiable

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Tangent vectors and dimensions

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$\dim T_p^*(X)$ may differ from the topological dimension of X at p . For example, $\dim T_0([0, 1]/(0 \sim 1)) = 2$.

Tangent vectors and dimensions

- Human factor

Differential Spaces

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$\dim T_p^*(X)$ may **differ** from the topological dimension of X at p . For example, $\dim T_0([0, 1]/(0 \sim 1)) = 2$.

Theorem: If $C^r(X)$ is the set of all continuous functions on a topological space X , then $\dim T_p^*(X) = 0$.

Tangent vectors and dimensions

- Human factor

Differential Spaces

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The quotient space $D^2/\partial D^2$ of disk D^2 is homeomorphic to sphere S^2 .

Tangent vectors and dimensions

- Human factor

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Tangent vectors and dimensions

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The quotient space $D^2/\partial D^2$ of disk D^2 is homeomorphic to sphere S^2 . What is $\dim_{\partial D^2/\partial D^2}(D^2/\partial D^2)$? **Infinity!**

Metric spaces

- Human factor

Differential Spaces

- Differentiable Manifolds
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- **Metric spaces**

Finite Topological Spaces

Each metric space is a differential space.

Metric spaces

- Human factor

Differential Spaces

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Finite Topological Spaces

Each metric space is a differential space.

A metric gives rise to many functions:

Metric spaces

- Human factor

Differential Spaces

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Finite Topological Spaces

Each metric space is a differential space.

A metric gives rise to many functions: distances from points.

Metric spaces

- Human factor

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Finite Topological Spaces

Each metric space is a differential space.

A metric gives rise to many functions: distances from points.
However on a Riemannian manifold they are not differentiable.

Metric spaces

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Finite Topological Spaces

Each metric space is a differential space.

A metric gives rise to many functions: distances from points. However on a Riemannian manifold they are not differentiable.

In a sufficiently small neighborhood of a point, distances from other points form **local coordinate system**.

Metric spaces

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Differential Spaces

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Let X be a metric space. A function $f : X \rightarrow \mathbb{R}$ is **differentiable** at $p \in X$ if for any neighborhood U of p there exist points $q_1, \dots, q_n \in U$ and real numbers a_1, \dots, a_n such that

$$\frac{|f(x) - f(p) - \sum a_i(\text{dist}(q_i, x) - \text{dist}(q_i, p))|}{\text{dist}(x, p)} \rightarrow 0$$

as $x \rightarrow p$.

Metric spaces

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Is this definition good?

Metric spaces

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$$\frac{|f(x) - f(p) - \sum a_i(\text{dist}(q_i, x) - \text{dist}(q_i, p))|}{\text{dist}(x, p)} \rightarrow 0$$

as $x \rightarrow p$. Is this definition good? At least, it recovers the smooth structure of a Riemannian manifold.

- Human factor

Differential Spaces

Finite Topological Spaces

- Hesitation of finite spaces
- Fundamental group
- Space of faces
- Homotopy
- Digital plane and Jordan Theorem
- Arbitrary finite space
- Baricentric subdivision

Finite Topological Spaces

Hesitation of finite spaces

- Human factor

Differential Spaces

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Topology seems to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces.

Hesitation of finite spaces

- Human factor

Differential Spaces

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Topology seems to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces. Finite **sets**, finite dimensional **vector spaces**, finite **fields**, finite **projective spaces**, etc. are appreciated by their host theories.

Hesitation of finite spaces

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Differential Spaces

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Who is guilty?

Hesitation of finite spaces

- Human factor

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Topology seems to be the only fields in Mathematics that hesitates of its own finite objects, finite topological spaces. Finite sets, finite dimensional vector spaces, finite fields, finite projective spaces, etc. are appreciated by their host theories.

Who is guilty? Interest towards Analysis?

Hesitation of finite spaces

- Human factor

Differential Spaces

Finite Topological Spaces

- **Hesitation of finite spaces**
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An average mathematician is well aware at best about two kinds of finite topological spaces:

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They are not that bad!

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At early days of topology, they were the main objects of the *Combinatorial Topology*.

Fundamental group

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What is the **minimal number of points** in a topological space with **nontrivial** fundamental group?

Fundamental group

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What is the **minimal number of points** in a topological space with **nontrivial** fundamental group?

What is the group?

Fundamental group

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What is the **minimal number of points** in a topological space with **nontrivial** fundamental group?

What is the group?

What is the next group?

Space of faces

- Human factor

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Let P be a compact polyhedron.

Space of faces

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Let P be a **compact polyhedron** represented as the union of closed convex polyhedra any two of which meet in a common face.

Space of faces

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Let P be a **compact polyhedron** represented as the union of closed convex polyhedra any two of which meet in a common face.

P is partitioned to open faces of these convex polyhedrons.

Space of faces

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Let P be a **compact polyhedron** represented as the union of closed convex polyhedra any two of which meet in a common face.

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Q **knows everything on P** .

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Q **knows everything on P** .

Especially if the partition was a triangulation.

Space of faces

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Q **knows everything on** P . Each point of Q represents a face of P .

Space of faces

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Space of faces

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The closure of a point $x \in Q$ consists of points corresponding to the faces of the corresponding face of P .

Space of faces

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Each point in a finite space has minimal neighborhood.

Space of faces

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Each point in a finite space has minimal neighborhood, **the intersection of all of its neighborhoods.**

Space of faces

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In Q the **minimal neighborhood** of a point corresponds to the **star** of corresponding face.

Space of faces

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The star $St(\sigma)$ of a face σ is the union of all faces Σ such that $\partial\Sigma \supset \sigma$.

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In Q the minimal neighborhood of a point corresponds to the star of corresponding face. Faces in P are partially ordered by adjacency: $\Sigma > \sigma$ iff $\text{Cl}(\Sigma) \supset \sigma$.

Space of faces

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This **partial order** defines and is defined by the **topology** of Q .

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P can be recovered from Q .

Homotopy

- Human factor

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Let P be a triangulated polyhedron

Homotopy

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Let P be a triangulated polyhedron,
 Q the space of its simplices

Homotopy

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Let P be a triangulated polyhedron,

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Let P be a triangulated polyhedron,
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 $pr : P \rightarrow Q$ the natural projection.

Homotopy

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Let P be a triangulated polyhedron,

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For topological spaces X and Y denote by $\pi(X, Y)$ the set of homotopy classes of maps $X \rightarrow Y$.

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Theorem. *For any topological space X , composition with pr defines a bijection $\pi(X, P) \rightarrow \pi(X, Q)$.*

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Corollary. *Any compact polyhedron is weak homotopy equivalent to a finite topological space.*

Digital plane and Jordan Theorem

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Digital plane and Jordan Theorem

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Digital line \mathcal{D} is the quotient space of \mathbb{R} by partition to points of \mathbb{Z} and open intervals $(n, n + 1)$.

Digital plane and Jordan Theorem

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Digital plane and Jordan Theorem

- Human factor

Differential Spaces

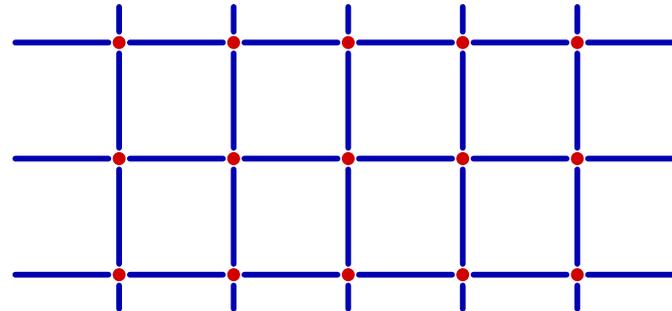
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Digital plane and Jordan Theorem

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Differential Spaces

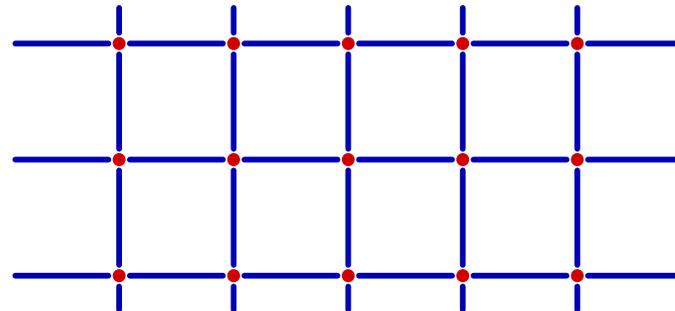
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Digital plane is \mathcal{D}^2 . It is the quotient space of \mathbb{R}^2 by the partition formed by integer points, open unit intervals connecting them, and open unit squares.



Digital circle of length d is the quotient space of the circle $S^1 \subset \mathbb{C}$ by the partition formed by complex roots of unity of degree d and open arcs connecting the roots next to each other.

Digital plane and Jordan Theorem

- Human factor

Differential Spaces

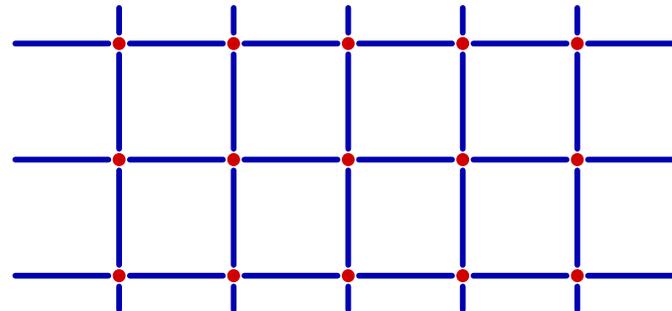
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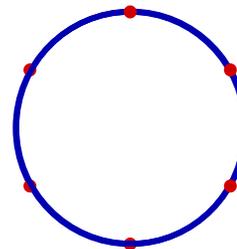
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Digital circle



Digital plane and Jordan Theorem

- Human factor

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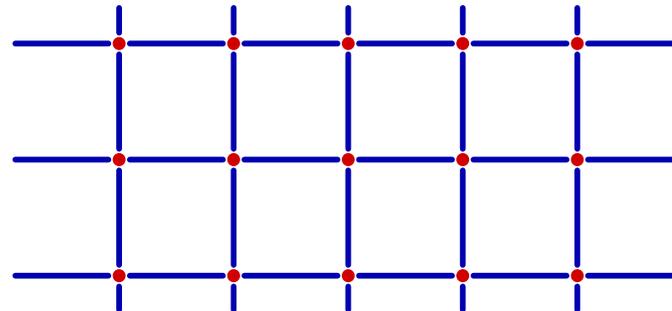
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Digital Jordan Theorem. (Khalimsky, Kiselman) *A digital circle embedded in the digital plane divides it into two connected sets.*

Digital plane and Jordan Theorem

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Differential Spaces

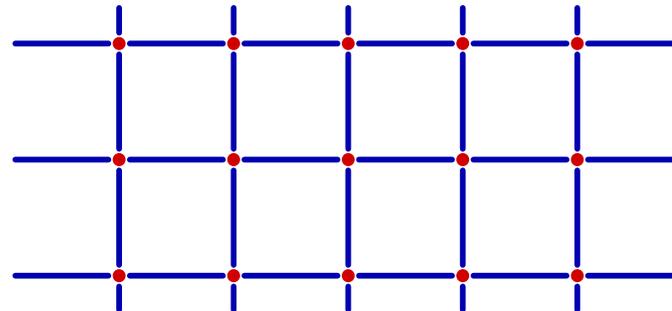
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Digital Jordan Theorem. (Khalimsky, Kiselman) *A digital circle embedded in the digital plane divides it into two connected sets.*

Not finite, but *locally finite*.

Arbitrary finite space

- Human factor

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In any topological space there is *T_0 -equivalence relation*:

$x \sim y$ if x and y have the same neighborhoods.

Arbitrary finite space

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In any topological space there is *T_0 -equivalence relation*:

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The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 :

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for any pair of points x, y at least one of them has a neighborhood not containing the other one.

Arbitrary finite space

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The quotient space by the T_0 -equivalence relation satisfies the Kolmogorov separation axiom T_0 .

In any T_0 -space the relation $x \in \text{Cl } y$ is a **partial order**.

Arbitrary finite space

- Human factor

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(if x and y are T_0 -equivalent, then both $x \in \text{Cl } y$ and $y \in \text{Cl } x$).

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How far is a poset topology from the face space of a polyhedron?

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How far is a poset topology from the face space of a polyhedron?
Not really far, just one step construction.

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How far is a poset topology from the face space of a polyhedron?

Let (X, \prec) be a poset.

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How far is a poset topology from the face space of a polyhedron?

Let (X, \prec) be a poset. Consider

$$X' = \{a_1 \prec a_2 \prec \cdots \prec a_n \mid a_i \in X\}.$$

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How far is a poset topology from the face space of a polyhedron?

Let (X, \prec) be a poset. Consider

$X' = \{a_1 \prec a_2 \prec \cdots \prec a_n \mid a_i \in X\}$, the set of all non-empty finite subsets of X in each of which \prec defines a linear order.

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X' is partially ordered by inclusion.

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Poset (X', \subset) is called the *baricentric subdivision of (X, \prec)* .

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The baricentric subdivision of any finite poset is the space of simplices of a compact triangulated polyhedron.

Baricentric subdivision

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This construction is used in combinatorics to define homology groups of a poset.

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Theorem. *Any finite topological space is weak homotopy equivalent to a compact polyhedron.*