On Riemann’s mapping theorem.

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Abstract. In this paper we give a new proof of Riemann’s well known mapping theorem. The suggested method permits to prove an analog of that theorem for three dimensional case.

Keywords: Quasi - conformal mapping, Riemann’s theorem.

1 Introduction

By Liouville’s theorem, see [2], p. 130, in three dimensional case, only superposition of isometric, dilatation and inverse transformations are conformal. To get an analog for Riemann’s mapping theorem, one introduce a family of mappings named quasi - conformal. This family is wider, nevertheless we do not have a natural analog of conformal mappings like of two dimensional case. In this paper we introduce a new family of mappings, named weak - conformal and obtain more natural generalization of Riemann’s theorem.

The proof of the main result of the present paper is interesting for two dimensional case too. Actually, we give a new proof of Riemann’s classical theorem, where the specific properties of complex analysis do not used. This permits us to prove a similar theorem in three dimensional case.

2 Classes of mappings

For any matrix $M = \{a_{ij}\}$ with eigenvalues $\lambda_1, \ldots, \lambda_n$ denote by

$$|M|^2 = \sum_{i=1}^{n} \sum_{j=1}^{n} a_{ij}^2 = \sum_{i=1}^{n} |\lambda_i|^2,$$

$$\text{tr}(M) = \sum_{i=1}^{n} a_{ii} = \sum_{i=1}^{n} \lambda_i$$
and
\[ \det(M) = \prod_{i=1}^{n} \lambda_i. \]

Let \( \varphi(x, y, z) = (A, B, C) \) be a continuously differentiable mapping. Denote by
\[
J = \begin{pmatrix}
A'_x & A'_y & A'_z \\
B'_x & B'_y & B'_z \\
C'_x & C'_y & C'_z
\end{pmatrix}
\]
the Jacobi matrix. Let \( G = J^*J \). We have
\[
|\varphi(\vec{x} + \Delta\vec{x}) - \varphi(\vec{x})|^2 = (J\Delta\vec{x}, J\Delta\vec{x}) + o(|\Delta\vec{x}|^2) = (\Delta\vec{x}, G\Delta\vec{x}) + o(|\Delta\vec{x}|^2).
\]

**Definition 1.** A continuously differentiable one to one mapping
\[
\varphi : \Omega_1 \to \Omega_2
\]
of the domain \( \Omega_1 \subset \mathbb{R}^3 \) on \( \Omega_2 \subset \mathbb{R}^3 \) is conformal if for each point \( \vec{x} \in \Omega_1 \) there is a number \( M(\vec{x}) \) such that
\[
|\varphi(\vec{x} + \Delta\vec{x}) - \varphi(\vec{x})| = M(\vec{x}) |\Delta\vec{x}| + o(|\Delta\vec{x}|).
\]

**Lemma 1.** Let \( \varphi \) be a continuously differentiable mapping with the Jacobi matrix \( J \) and \( G = J^*J \). Then \( \varphi \) is conformal if and only if
\[ 27 \det(G) = \text{tr}^3(G). \]

**Proof.** The eigenvalues \( \lambda_1, \lambda_2, \lambda_3 \) of the matrix \( G \) are nonnegative. The lemma’s condition means that
\[
\left(\frac{\lambda_1 + \lambda_2 + \lambda_3}{3}\right)^3 = \lambda_1\lambda_2\lambda_3
\]
This equality is valid only if all eigenvalues are the same, i.e. \( \lambda_1 = \lambda_2 = \lambda_3 \).

**Example.** Let us consider the inverse transformation, which the point \( (x, y, z) \neq (0, 0, 0) \) maps to \( (A, B, C) \), where
\[
(A, B, C) = \left( \frac{x}{x^2 + y^2 + z^2}, \frac{y}{x^2 + y^2 + z^2}, \frac{z}{x^2 + y^2 + z^2}, \right)
\]
We have
\[
J = \begin{pmatrix}
A'_x & A'_y & A'_z \\
B'_x & B'_y & B'_z \\
C'_x & C'_y & C'_z
\end{pmatrix} =
\]
Consequently,

$$G = \frac{1}{(x^2 + y^2 + z^2)^2} \begin{pmatrix}
-x^2 + y^2 + z^2 & -2xy & -2xz \\
-2xy & x^2 - y^2 + z^2 & -2yz \\
-2xz & -2yz & x^2 + y^2 - z^2
\end{pmatrix}$$

So, the condition of lemma 1 is satisfy and hence this mapping is conformal.

**Definition 2.** A quasi-conformal mapping is a continuously differentiable homeomorphism

$$\varphi : \Omega_1 \to \Omega_2$$

for which the ball

$$B(\vec{x}, r) = \{\vec{y}; |\vec{x} - \vec{y}| < r\}$$

maps to

$$\{\varphi(\vec{y}); \vec{y} \in B(\vec{x}, r)\} = \{\varphi(\vec{x}) + J(\vec{y} - \vec{x}); \vec{y} \in B(\vec{x}, r)\} + o(r^2)$$

and the ratio of the main diagonals of the ellipsoid

$$\{J(\vec{z}); |\vec{z}| = r\}$$

are uniformly bounded for all points $\vec{x} \in \Omega$.

In this paper we introduce a new family of mappings, which are generalizations of conformal mappings. For those mappings, which we name weak - conformal, we have an analog of Riemann’s mapping theorem.

**Definition 3.** A weak-conformal mapping is a continuously differentiable homomorphism

$$\varphi : \Omega_1 \to \Omega_2$$

for which the ball

$$B(\vec{x}, r) = \{\vec{y}; |\vec{x} - \vec{y}| < r\}$$

maps to

$$\{\varphi(\vec{y}); \vec{y} \in B(\vec{x}, r)\} = \{\varphi(\vec{x}) + J(\vec{y} - \vec{x}); \vec{y} \in B(\vec{x}, r)\} + o(r^2)$$

and the the main diagonals of the ellipsoid

$$\{J(\vec{z}); |\vec{z}| = r\}$$

form geometric progression for all points $\vec{x} \in \Omega$. 
Lemma 2. Let \( \varphi \) be a continuously differentiable mapping with Jacobi matrix \( J \). Then it is weak - conformal if and only if

\[
(\text{tr}^2(G) - |G|^2)^3 = 8 \det(G) \text{tr}^3(G),
\]

where \( G = J^*J \).

Proof. In terms of eigenvalues of the matrix \( G = J^*J \), this condition one can write as follows

\[
\lambda_1\lambda_2\lambda_3 (\lambda_1 + \lambda_2 + \lambda_3)^3 = (\lambda_1\lambda_2 + \lambda_3\lambda_1 + \lambda_3\lambda_2)^3.
\]

So,

\[
(\lambda_1\lambda_2\lambda_3 - \lambda_3^3) (\lambda_1 + \lambda_2 + \lambda_3)^3 - (\lambda_1\lambda_2 + \lambda_3\lambda_1 + \lambda_3\lambda_2)^3 + (\lambda_1\lambda_3 + \lambda_2\lambda_3 + \lambda_3^2)^3 = 0.
\]

After simple transformations we get

\[
(\lambda_1\lambda_2 - \lambda_2^2) (\lambda_1\lambda_2 + \lambda_3\lambda_1 + \lambda_3\lambda_2) (\lambda_1^2 + \lambda_2^2 + \lambda_1\lambda_2) - \lambda_1\lambda_2 (\lambda_1 + \lambda_2 + \lambda_3)^2 = 0.
\]

The last condition is equivalent to the following one

\[
(\lambda_1\lambda_2 - \lambda_2^2) (\lambda_1\lambda_3 - \lambda_3^2) (\lambda_3\lambda_2 - \lambda_1^2) = 0.
\]

Consequently, our condition means that eigenvalues of the matrix \( J^*J \) form a geometric progression.

3 Green’s function in \( R^2 \)

In this section we introduce Green function and prove some of its properties.

Definition 4. Let \( \Omega \) be a domain in \( R^2 \). A function \( G(x, y) \), \( x \neq y \in \Omega \) is called Green function for the domain \( \Omega \), if it satisfies the following conditions:

1. \( G(x, y) \) is continuous from below and

\[
G(x, y) > 0, \quad x \neq y \in \Omega;
\]

2. for each fixed point \( y \in \Omega \) there is a harmonic function \( h(x, y) \), \( x \in \Omega \) such that

\[
G(x, y) = \frac{1}{2\pi} \log \frac{1}{|x - y|} + h(x, y);
\]

3. if \( u(x) \) is an arbitrary harmonic function defined in \( \Omega \) and satisfying the condition

\[
u(x) \leq G(x, y), \quad x \in \Omega \setminus \{y\}, \]

\[
u(y) = 0.
\]
then
\[ u(\vec{x}) \leq 0, \quad \vec{x} \in \Omega. \]

In three dimension case, if \( \Omega \subset \mathbb{R}^3 \), the Green’s function can be defined by the same way replacing the second condition to the following one
\[ G(\vec{x}, \vec{y}) = \frac{1}{4\pi|\vec{x} - \vec{y}|} + h(\vec{x}, \vec{y}), \quad \vec{x} \in \Omega \setminus \{\vec{y}\}. \]

It is well known, that if the boundary of a domain \( \Omega \neq \mathbb{R}^2 \) has positive capacity, then it has unique Green function, see [4], p. 138. In particular, if \( \Omega \neq \mathbb{R}^2 \) is simply connected then it has Green function.

For a fixed point \( \vec{y} \in \Omega \) and for an arbitrary number \( 0 < t < +\infty \) let us denote
\[ \Omega_t = \{\vec{x}; \quad G(\vec{x}, \vec{y}) > t\}. \]

Note that for arbitrary value of \( t > 0 \) the domain \( \Omega_t \) is connected and its Green function is \( G(\vec{x}, \vec{y}) - t \).

**Lemma 3.** Let \( u(\vec{x}), \quad \vec{x} \in \Omega \), be a harmonic function and
\[ \{\vec{x}; \quad |\vec{x} - \vec{x}_0| \leq r\} \subset \Omega. \]

If for some point \( \vec{x} \), \( |\vec{x} - \vec{x}_0| = r \), we have
\[ u(\vec{x}) = \inf\{u(\vec{y}); \quad |\vec{y} - \vec{x}_0| < r\} \]
then
\[ |\nabla u(\vec{x})| \geq \frac{1}{2r}(u(\vec{x}_0) - u(\vec{x})). \]

**Proof.** For arbitrary \( 0 \leq \varphi < 2\pi \) and \( 0 < t < 1 \) we have
\[ \frac{r^2 - (rt)^2}{|re^{i\varphi} - t(\vec{x} - \vec{x}_0)|^2} \geq \frac{r^2 - (rt)^2}{(r + rt)^2} \geq \frac{1 - t}{2}. \]

So,
\[
\frac{u(\vec{x}_0 + t(\vec{x} - \vec{x}_0)) - u(\vec{x})}{|\vec{x}_0 + t(\vec{x} - \vec{x}_0) - \vec{x}|} = \\
= \frac{1}{2\pi(r - rt)} \int_0^{2\pi} \frac{r^2 - (rt)^2}{|re^{i\varphi} - t(\vec{x} - \vec{x}_0)|^2} (u(\vec{x}_0 + re^{i\varphi}) - u(\vec{x})) d\varphi \geq \\
\geq \frac{1}{4\pi r} \int_0^{2\pi} (u(\vec{x}_0 + re^{i\varphi}) - u(\vec{x})) d\varphi = \frac{1}{2r}(u(\vec{x}_0) - u(\vec{x})).
\]
Passing to the limit if \( t \to 1 - 0 \) we get the required result.

**Remark.** The analogous result is true in \( R^3 \).

**Theorem 1.** Let \( G(\vec{x}, \vec{y}) \) be a Green function for a simply connected domain \( \Omega \) in \( R^2 \). Then
\[
|\nabla G(\vec{x}, \vec{y})| \neq 0, \quad \vec{x} \in \Omega \setminus \{\vec{y}\}.
\]

**Proof.** Let us assume, that at some point \( \vec{x}_0 \in \Omega \) we have
\[
|\nabla G(\vec{x}_0, \vec{y})| = 0.
\]

Denote
\[
\Omega^+ = \{\vec{x}, \quad G(\vec{x}, \vec{y}) > G(\vec{x}_0, \vec{y})\}
\]
and
\[
\Omega^- = \{\vec{x}, \quad G(\vec{x}, \vec{y}) < G(\vec{x}_0, \vec{y})\}.
\]

Note that the domain \( \Omega^+ \) is connected. For sufficiently small number \( \epsilon > 0 \), such that the following condition
\[
B(\vec{x}_0, \epsilon) \subset \Omega \setminus \{\vec{y}\},
\]
holds, we consider the open set
\[
A = B(\vec{x}_0, \epsilon) \setminus \{\vec{x}; \quad G(\vec{x}, \vec{y}) = G(\vec{x}_0, \vec{y})\}.
\]

The set \( A \) consists of an even number of components. Otherwise, we could find a point
\[
\vec{x}_1 \in B(\vec{x}_0, \epsilon) \cap \{\vec{x}; \quad G(\vec{x}, \vec{y}) = G(\vec{x}_0, \vec{y})\}
\]
in some neighborhood of which the function \( G(\vec{x}, \vec{y}) - G(\vec{x}_0, \vec{y}) \) would preserve its sign. So, \( \vec{x}_1 \) would be the point of local extremum, which is impossible for the nonconstant harmonic function \( G(\vec{x}, \vec{y}), \quad \vec{x} \in B(\vec{x}_0, \epsilon) \). Moreover, the set \( A \) cannot have only two components. Indeed if it had two components then the boundary \( \partial \Omega^+ \cap B(\vec{x}_0, \epsilon) \) would be smooth. Consequently, by lemma 1 we would have
\[
|\nabla G(\vec{x}_0, \vec{y})| > 0.
\]

Thus, the domain \( A \) has at least four connected components. This implies that the open set \( \Omega^- \) consists of more than two connected components. Since our domain is simply connected, one of those components has the boundary, completely laying inside of \( \partial \Omega^+ \). On that connected component the function \( G(\vec{x}, \vec{y}) \) is identically constant end equal \( G(\vec{x}_0, \vec{y}) \). This is a contradiction.

Note that in theorem 1, the condition ”simply connected”, is essential. Indeed, for the domain \( \{\vec{x}; \quad 1 < |\vec{x}| < 2\} \) theorem 1 does not valid.
4 New proof of Riemann’s theorem

In this section we give a new proof of Riemann’s well known theorem on conformal mapping. In this proof we do not use methods of complex analysis.

Let us denote

\[ D(y, r) = \{ x; |x - y| < r \}. \]

**Theorem 2.** Let \( \Omega \) be a simply connected domain in \( \mathbb{R}^2 \). If \( \Omega \neq \mathbb{R}^2 \) then there is a one to one conformal mapping

\[ \varphi: \Omega \to D \]

of the domain \( \Omega \) on the unit disk \( D = D(\bar{0}, 1) \).

**Proof.** Let us fix a point \( \bar{y} \in \Omega \) and \( G(\bar{x}, \bar{y}) \) be Green function of the domain \( \Omega \). Let us consider the following dynamical system in \( \Omega \setminus \{ \bar{y} \} \)

\[
\frac{d\bar{x}(t)}{dt} = -\frac{\nabla G(\bar{x}(t), \bar{y})}{2\pi |\nabla G(\bar{x}(t), \bar{y})|^2} e^{2\pi G(\bar{x}(t), \bar{y})}, \quad 0 < t < 1. \tag{1}
\]

For an arbitrary solution of this equation we have

\[
\frac{d}{dt} \left( e^{-2\pi G(\bar{x}(t), \bar{y})} \right) = -2\pi e^{-2\pi G(\bar{x}(t), \bar{y})} \left( \nabla G(\bar{x}(t), \bar{y}), \frac{d\bar{x}(t)}{dt} \right) = 1.
\]

Consequently,

\[ G(\bar{x}(t), \bar{y}) = \frac{1}{2\pi} \ln \frac{1}{t}, \quad 0 < t < 1. \]

In the neighborhood of each point \( \bar{x} \in \Omega \setminus \{ \bar{y} \} \) the equation (1) has a unique solution passing through the point \( \bar{x} \), see [1] p. 19.

In the neighborhood of the point \( \bar{y} \) the equation (1) may be written in the following form

\[
\frac{d\bar{x}(t)}{dt} = \bar{x}(t) - \bar{y} \exp\{2\pi h(\bar{y}, \bar{y})\} + o(t), \quad t \to 0.
\]

So, for each solution of our equation we have

\[ \bar{x}(t) = \bar{y} + \bar{a} t \exp\{2\pi h(\bar{y}, \bar{y})\} + o(t), \quad t \to 0, \]

where \( \bar{a} \) is a vector with norm one.
Consequently, for each point \( x \in \Omega \setminus \{ \vec{y} \} \) we can find a unique vector \( \vec{a} = \vec{a}(\vec{x}) \), such that there is a solution \( \vec{x}(t) \) of our equation which passes through the point \( \vec{x} \) and at the same time in the neighborhood of the point \( \vec{y} \) satisfies the condition

\[
\lim_{t \to 0} \frac{\vec{x}(t) - \vec{y}}{t} = \vec{a} \exp\{2\pi h(\vec{y}, \vec{y})\}.
\]

Let us define the mapping

\[
\phi : \Omega \to D
\]
as follows, \( \phi(\vec{y}) = 0 \) and for the arbitrary point \( \vec{x} \in \Omega \setminus \{ \vec{y} \} \) we put

\[
\phi(\vec{x}) = \vec{a}(\vec{x}) e^{-2\pi G(\vec{x}, \vec{y})}.
\]

It is obvious, that \( \phi(\vec{x}) \) is a one to one mapping and \( \phi(\Omega) = D \).

Recall some facts about the constructed mapping, which permit to assert that it is conformal.

Let us take two solutions

\[
\vec{x}(t), \quad \vec{x}_1(t)
\]
of the equation (1). We denote by \( \alpha \) the angle between the vectors \( \vec{a}(\vec{x}(t)) \) and \( \vec{a}(\vec{x}_1(t)) \). For arbitrary numbers \( 0 < t_0 < t_1 < 1 \) denote by \( U \) the domain bounded by the curves

\[
\gamma_1 = \{ \vec{x}(t); \quad t_0 < t < t_1 \}, \quad \gamma_2 = \{ \vec{x}_1(t); \quad t_0 < t < t_1 \}
\]

and

\[
\gamma_3 = \{ \vec{x}; \quad G(\vec{x}, \vec{y}) = G(x(t_0), \vec{y}) \}, \quad \gamma_4 = \{ \vec{x}; \quad G(\vec{x}, \vec{y}) = G(x(t_1), \vec{y}) \}.
\]

Let \( \vec{m}(\vec{x}) \) be the unite outer normal to the boundary of the domain \( U \) at the point \( \vec{x} \in \partial U \). For an arbitrary point \( \vec{x} \in \gamma_1 \cup \gamma_2 \) we have

\[
\left( \frac{d\vec{x}(t)}{dt}, \vec{m}(\vec{x}(t)) \right) = 0, \quad t_0 < t < t_1.
\]

Consequently,

\[
(\nabla G(\vec{x}, \vec{y}), \vec{m}(\vec{x})) = \frac{\partial G(\vec{x}, \vec{y})}{\partial \vec{n}} = 0.
\]

If \( \vec{x} \in \gamma_3 \) then we have \( \vec{m}(\vec{x}) = -\vec{n}(\vec{x}) \), where \( \vec{n}(\vec{x}) \) is the outer normal to the boundary of the domain \( \{ \vec{x}; \quad G(\vec{x}, \vec{y}) > t_0 \} \). If \( \vec{x} \in \gamma_4 \) then we have \( \vec{m}(\vec{x}) = \vec{n}(\vec{x}) \), where \( \vec{n}(\vec{x}) \) is the outer normal to the domain \( \{ \vec{x}; \quad G(\vec{x}, \vec{y}) > t \} \). Therefore,

\[
\int_{\gamma_3} \frac{\partial G(\vec{x}, \vec{y})}{\partial \vec{n}} \, ds = \int_{\gamma_4} \frac{\partial G(\vec{x}, \vec{y})}{\partial \vec{n}} \, ds.
\]
Passing to the limit we get
\[
\alpha = 2\pi \lim_{t_0 \to +0} \int_{\gamma_4} \frac{\partial G(\vec{x}, \vec{y})}{\partial n} ds = 2\pi \int_{\gamma_4} \frac{\partial G(\vec{x}, \vec{y})}{\partial n} ds.
\]

From definition of the mapping \( \varphi(\vec{x}) \) we have
\[
|\varphi(\vec{x}(t)) - \varphi(\vec{x}_1(t))| = |t(\vec{x})||\vec{a}(\vec{x}(t)) - \vec{a}(\vec{x}_1(t))| =
\]
\[
= |t(\vec{x})| \left| 2\pi \int_{\gamma_4} \frac{\partial G(\vec{x}, \vec{y})}{\partial n} ds \right| =
\]
\[
= 2\pi \frac{\partial G(\vec{x}(t), \vec{y})}{\partial n} \exp\{-2\pi G(\vec{x}(t), \vec{y})\} |\vec{x}(t) - \vec{x}_1(t)| + o(|\vec{x}(t) - \vec{x}_1(t)|).
\]

Further on we can write
\[
|\varphi(\vec{x}(t + \Delta t)) - \varphi(\vec{x}(t))| + o(|\Delta t|) = |\Delta t| + o(|\Delta t|) =
\]
\[
= |\vec{x}(t + \Delta t) - \vec{x}(t)| \left| \frac{d\vec{x}(t)}{dt} \right|^{-1}
\]
\[
= 2\pi \frac{\partial G(\vec{x}(t), \vec{y})}{\partial n} \exp\{-2\pi G(\vec{x}(t), \vec{y})\} |\vec{x}(t + \Delta t) - \vec{x}(t)| + o(|\Delta t|).
\]

Let \( r > 0 \) be sufficiently small. We choose \( \Delta t \) and \( \vec{x}_1(t) \) such that the equalities
\[
|\vec{x}(t + \Delta t) - \vec{x}(t)| = |\vec{x}(t) - \vec{x}_1(t)| = r
\]
hold. The vectors
\[
\vec{x}(t + \Delta t) - \vec{x}(t)
\]
and
\[
\vec{x}(t) - \vec{x}_1(t)
\]
are orthogonal. Consequently, the image of the disk \( D(\vec{x}(t), r) \) is a circle, as a first approximation, once if the orthogonal vectors
\[
\varphi(\vec{x}(t + \Delta t)) - \varphi(\vec{x}(t))
\]
and
\[
\varphi(\vec{x}(t)) - \varphi(\vec{x}_1(t))
\]
satisfy the condition
\[
|\varphi(\vec{x}(t + \Delta t)) - \varphi(\vec{x}(t))| = |\varphi(\vec{x}(t)) - \varphi(\vec{x}_1(t))| + o(r).
\]
The last condition holds since
\[ |\varphi(\vec{x}(t + \Delta t)) - \varphi(\vec{x}(t))| = 2\pi \frac{\partial G(\vec{x}(t), \vec{y})}{\partial n} \exp\{-2\pi G(\vec{x}(t), \vec{y})\} r + o(r) \]
and
\[ |\varphi(\vec{x}(t)) - \varphi(\vec{x}_1(t))| = 2\pi \frac{\partial G(\vec{x}(t), \vec{y})}{\partial n} \exp\{-2\pi G(\vec{x}(t), \vec{y})\} r + o(r). \]

**Remark.** For constructed mapping at the points \( \vec{x} \in \Omega \setminus \{ \vec{y} \} \) we have
\[ |\varphi'(\vec{x})| = 2\pi |\nabla G(\vec{x}, \vec{y})| \exp\{-2\pi G(\vec{x}, \vec{y})\}. \]
At the point \( \vec{y} \) we have
\[ |\varphi'(\vec{y})| = 2\pi \exp\{-2\pi h(\vec{y}, \vec{y})\}. \]

## 5 Green’s function in \( \mathbb{R}^3 \)

**Definition 5.** We say that a domain \( \Omega \subset \mathbb{R}^3 \) is simply connected if
1. for an arbitrary bounded domain \( \Omega_1 \subset \mathbb{R}^3 \) if we have \( \partial \Omega_1 \subset \Omega \) then it follows \( \Omega_1 \subset \Omega \);
2. an arbitrary closed curve laying in domain \( \Omega \) permits continuous deformation in domain \( \Omega \) to the point.

**Lemma 4.** Let \( \Omega \) be a simply connected domain in \( \mathbb{R}^3 \). Let \( \Omega \) be a bounded domain with smooth boundary and \( G(\vec{x}, \vec{y}) \) is its Green function. Then
\[ \nabla G(\vec{x}, \vec{y}) \neq 0, \quad \vec{x} \in \Omega \setminus \{ \vec{y} \}. \]

**Proof.** Since the boundary of our domain is smooth so, we have
\[ \nabla G(\vec{x}, \vec{y}) \neq 0, \quad \vec{x} \in \partial \Omega. \]
Let us assume that
\[ \{ \vec{x}; \vec{x} \in \Omega, \nabla G(\vec{x}, \vec{y}) = 0 \} \neq \emptyset. \]
Let \( 0 < t_0 < \infty \) be the biggest number for which there is a point \( x_0 \in \Omega \) such that \( G(\vec{x}_0, \vec{y}) = t_0 \) and
\[ \nabla G(\vec{x}_0, \vec{y}) = 0. \]
Denote
\[ \Omega^+ = \{ \vec{x}, \quad G(\vec{x}, \vec{y}) > t_0 \} \]
and 
\[ \Omega^- = \{ \vec{x}, \ G(\vec{x}, \vec{y}) < t_0 \}. \]

Note that the domain \( \Omega^+ \) is connected. If \( \Omega^- \) does not connected we come to the contradiction like of two dimensional case.

It turns out, that in three dimensional case, it is possible that the domain \( \Omega^- \) is connected too.

In the domain 
\[ \{ \vec{x}; \vec{x} \in \Omega, G(\vec{x}, \vec{y}) > t_0 \} \]

we consider the following dynamic system

\[ \frac{d\vec{x}(t)}{dt} = - \frac{\nabla G(\vec{x}(t), \vec{y})}{4\pi |\nabla G(\vec{x}(t), \vec{y})|^2} G^2(\vec{x}(t), \vec{y}), \quad t_0 < t. \]

For an arbitrary solution of this equation we have

\[ \frac{d}{dt} \frac{1}{G(\vec{x}(t), \vec{y})} = - \frac{1}{G^2(\vec{x}(t), \vec{y})} \left( \nabla G(\vec{x}(t), \vec{y}), \frac{d\vec{x}(t)}{dt} \right) = \frac{1}{4\pi}. \]

Consequently, we have

\[ G(\vec{x}(t), \vec{y}) = \frac{1}{4\pi t}, \quad 0 < t < \infty. \]

So, for each \( 0 < \epsilon \), the solutions of this equation generate the following transformation

\[ x(\infty) \rightarrow x(t_0 + \epsilon) \]

which settle a one to one correspondence between the points of the manifolds \( \partial \Omega \) and \( \partial \Omega_{t_0 + \epsilon} \). Hence, those manifolds are homotopic equivalent.

In the domain 
\[ \{ \vec{x}, \ G(\vec{x}, \vec{y}) > t_0 + \epsilon \} \]

there is a smooth closed curve \( \gamma_1 \), which passes through the points \( x_0 \) and \( y \).

For sufficiently small \( \epsilon > 0 \) the plane orthogonal to the curve \( \gamma_1 \) at the point \( x_0 \), cut a closed curve \( \gamma_2 \) on the boundary \( \partial \Omega_{t_0 + \epsilon} \) which have nonzero index in compare to the curve \( \gamma_1 \).

Since \( \partial \Omega_{t_0 + \epsilon} \) and \( \partial \Omega \) are homotopic equivalent so, the curve \( \gamma_2 \), by continuously deformation, staying on the boundary \( \partial \Omega_{t_0 - \epsilon} \), is possible to tie up to a point.

This is a contradiction since each curve on the boundary \( \partial \Omega_{t_0 + \epsilon} \) having sufficiently small diameter, has zero index in compare with the curve \( \gamma_1 \).
6 Weak-conformal mapping in $\mathbb{R}^3$

In this section we prove the main result of the paper.

**Theorem 3.** Let $\Omega$ be a simply connected domain in $\mathbb{R}^3$. If $\Omega$ is a bounded and has smooth boundary then there is a one to one weak - conformal mapping 

$$\varphi : \Omega \to B$$

of the domain $\Omega$ onto the unit ball $B = \{x \in \mathbb{R}^3; |x| < 1\}$.

**Proof.** We consider the following dynamic system

$$\frac{d\vec{x}(t)}{dt} = -\frac{\nabla G(\vec{x}(t), \vec{y})}{4\pi|\nabla G(\vec{x}(t), \vec{y})|^2}G^2(\vec{x}(t), \vec{y}), \quad 0 < t < \infty.$$ 

In neighborhood of the point $\vec{y}$ we have

$$-\frac{\nabla G(\vec{x}, \vec{y})}{4\pi|\nabla G(\vec{x}, \vec{y})|^2}G^2(\vec{x}, \vec{y}) =$$

$$= \left(\frac{\vec{x} - \vec{y}}{4\pi|\vec{x} - \vec{y}|^3} - \nabla h\right)\left(\frac{1}{4\pi|\vec{x} - \vec{y}|} + h\right)^2$$

$$= \left(\frac{1}{16\pi^2|\vec{x} - \vec{y}|^4} - \frac{\vec{x} - \vec{y}, \nabla h}{2\pi|\vec{x} - \vec{y}|^2} + |\nabla h|^2\right)^{-1} =$$

$$= \frac{\vec{x} - \vec{y}}{|\vec{x} - \vec{y}|} + \frac{1}{|\vec{x} - \vec{y}| - 4\pi|\vec{x} - \vec{y}|^2\nabla h} \frac{(1 + 4\pi|\vec{x} - \vec{y}|h)^2}{1 - 8\pi|\vec{x} - \vec{y}|(|\vec{x} - \vec{y}, \nabla h) + 16\pi^2|\vec{x} - \vec{y}|^4|\nabla h|^2} =$$

$$= \frac{\vec{x} - \vec{y}}{|\vec{x} - \vec{y}|} + 8\pi h(\vec{y}, \vec{y})(\vec{x} - \vec{y}) + O(|\vec{x} - \vec{y}|^2)$$

So, for each solution of our equation we have

$$\vec{x}(t) = \vec{y} + \vec{a}t + 4\pi\vec{a}t^2h(\vec{y}, \vec{y}) + o(t^2), \quad t \to 0,$$

where $\vec{a}$ is a vector with norm one.

Consequently, for each point $\vec{x} \in \Omega \setminus \{\vec{y}\}$ we can find the unique vector $\vec{a} = \vec{a}(\vec{x})$ of unit norm, such that a solution $\vec{x}(t)$ passes through the point $\vec{x}$ and

$$\lim_{t \to 0} \frac{\vec{x}(t) - \vec{y}}{t} = \vec{a}.$$ 

By definition the vector $\vec{a}(\vec{x}(t))$ is the same for all values of $0 < t < \infty$. 

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Let \( \vec{x} = \vec{x}(t_0) \). We denote by
\[
\gamma(\vec{x}) = \{ \vec{x}(t); \ t_0 \leq t < \infty \}
\]
the curve begins at the point \( \vec{x} \) and goes to the boundary of the domain \( \Omega \).

If for each point \( \vec{x} \in \Omega \) the curve \( \gamma(\vec{x}) \) has a finite length, then we can define the mapping
\[
\varphi : \Omega \to B
\]
as follows, \( \varphi(\vec{y}) = 0 \) and for the point \( \vec{x} \in \Omega \setminus \{ \vec{y} \} \) we put
\[
\varphi(\vec{x}) = \vec{a}(\vec{x}) \exp \left\{ - \int_{\gamma(\vec{x})} \sqrt{4\pi|\nabla G(\vec{z}, \vec{y})|} \, ds(\vec{z}) \right\}.
\]
It is obvious, that \( \varphi \) is a one to one mapping onto the unit ball \( B \).

Now let us consider the properties of the constructed mapping.

For arbitrary nonzero vector \( \vec{a} \) let us denote by \( D_{\alpha}(\vec{a}) \) the round cone with bisector \( \vec{a} \) and the spherical sector
\[
\{ \vec{y}; \ |\vec{y}| = 1, \ \vec{y} \in D_{\alpha}(\vec{a}) \}
\]
has area equal \( \alpha \).

Let us fix a point \( \vec{x} \in \Omega \) and a number \( 0 < \alpha < 4\pi \). For arbitrary numbers \( 0 < t_0 < t_1 < \infty \) denote by \( U \) the following domain
\[
U = \bigcup_{\vec{a}(\vec{x}(t_0)) \in D_{\alpha}(\vec{a}(\vec{x}))} \{ \vec{x}(t); \ t_0 < t < t_1 \}
\]
We denote
\[
W(t_0, \alpha) = \{ \vec{x}(t_0); \ \vec{a}(\vec{x}(t_0)) \in D_{\alpha}(\vec{a}(\vec{x})) \}
\]
and
\[
W(t_1, \alpha) = \{ \vec{x}(t_1); \ \vec{a}(\vec{x}(t_1)) \in D_{\alpha}(\vec{a}(\vec{x})) \}
\]
By Green’s formula we have
\[
\int_{W(t_0, \alpha)} \frac{\partial G(\vec{z}, \vec{y})}{\partial \vec{n}} \, ds(\vec{z}) = \int_{W(t_1, \alpha)} \frac{\partial G(\vec{z}, \vec{y})}{\partial \vec{n}} \, ds(\vec{z}).
\]
Passing to the limit if \( t_0 \to 0 \) we get
\[
\int_{W(t_1, \alpha)} \frac{\partial G(\vec{z}, \vec{y})}{\partial \vec{n}} \, ds(\vec{z}) = \lim_{t_0 \to +0} \int_{W(t_0, \alpha)} \frac{\partial G(\vec{z}, \vec{y})}{\partial \vec{n}} \, ds(\vec{z}) = \frac{\alpha}{4\pi}.
\]
Consequently, for small $\alpha$ we have

$$s(W(t_1, \alpha)) \frac{\partial G(\vec{x}(t_1), \vec{y})}{\partial \vec{n}} = \frac{\alpha}{4\pi} + o(\alpha).$$

The vector $\vec{x}(t_1 + \Delta t) - \vec{x}(t_1)$ is orthogonal to the surface $W(t_1, \alpha)$ and

$$|\vec{x}(t_1 + \Delta t) - \vec{x}(t_1)| = \left| \frac{dx(t_1)}{dt} \Delta t \right| = \frac{G^2(x(t_1), y)}{4\pi |\nabla G(x(t_1), y)|} |\Delta t| + o(|\Delta t|).$$

We choose the parameters $\alpha$ and $\Delta t$ such that

$$s(W(t_1, \alpha)) = \pi |\vec{x}(t_1 + \Delta t) - \vec{x}(t_1)|^2.$$ 

This means that we have

$$\frac{G^4(x(t_1), y)}{16\pi |\nabla G(x(t_1), y)|^2} |\Delta t|^2 = \frac{\alpha}{4\pi |\nabla G(x(t_1), y)|} + o(\alpha).$$

The vector $\varphi(\vec{x}(t_1 + \Delta t) - \varphi(\vec{x}(t_1))$ is orthogonal to the surface $\varphi(W(t_1, \alpha))$.

Note that the image of the subset $W(t_1, \alpha)$ is a round sector on the sphere with the center at the point $\vec{0}$ and with the radius $|\varphi(\vec{x}(t_1))|$. So, we have

$$s(\varphi(W(t_1, \alpha))) = \alpha |\varphi(\vec{x}(t_1))|^2.$$ 

Since

$$|\varphi(\vec{x}(t_1))| = \exp \left\{ - \int_{\gamma(\vec{x}(t_1))} \sqrt{4\pi |\nabla G(\vec{x}, \vec{y})|} ds(\vec{z}) \right\} =$$

$$= \exp \left\{ - \int_{t_1}^{\infty} \frac{G^2(x(t), y)}{\sqrt{4\pi |\nabla G(x(t), y)|}} dt \right\}$$

So,

$$|\varphi(\vec{x}(t_1 + \Delta t)) - \varphi(\vec{x}(t_1))| = |\varphi(\vec{x}(t_1))| \frac{G^2(\vec{x}(t_1), \vec{y})}{\sqrt{4\pi |\nabla G(\vec{x}(t_1), \vec{y})|}} |\Delta t| + o(|\Delta t|).$$

Consequently, we have

$$s(\varphi(W(t_1, \alpha))) = \alpha |\varphi(\vec{x}(t))|^2 = \pi |\varphi(\vec{x}(t + \Delta t)) - \varphi(\vec{x}(t))|^2 + o(|\Delta t|^2).$$

This relation is equivalent to the weak - conformal condition at the point $\vec{x} \in \Omega$ for constructed mapping.

**Remark.** For any point $\vec{x} \neq \vec{y}$ we have

$$\lim_{\Delta t \to 0} \frac{|\varphi(\vec{x}(t + \Delta t)) - \varphi(\vec{x}(t))|}{|\vec{x}(t + \Delta t) - \vec{x}(t)|} =$$
\[ = \sqrt{4\pi |\nabla G(\vec{x}, \vec{y})|} \exp \left\{ - \int_{\gamma(\vec{x})} \sqrt{4\pi |\nabla G(\vec{z}, \vec{y})|} ds(\vec{z}) \right\} \]

where \( \vec{x} = \vec{x}(t) \). Hence, we have

\[ \varphi(\vec{x}) = \varphi(\vec{x}) - \varphi(\vec{y}) = \vec{x} - \vec{y} + o(|\vec{x} - \vec{y}|). \]

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