STABILITY WITH RESPECT TO ACTIONS OF REAL REDUCTIVE LIE GROUPS

LEONARDO BILIOTTI AND MICHELA ZEDDA

Abstract. We give a systematic treatment of the stability theory for action of a real reductive Lie group $G$ on a topological space. More precisely, we introduce an abstract setting for actions of non-compact real reductive Lie groups on topological spaces that admit functions similar to the Kempf-Ness function. The point of this construction is that one can characterize stability, semi-stability and polystability of a point by numerical criteria, that is in terms of a function called maximal weight. We apply this setting to the actions of a real non-compact reductive Lie group $G$ on a real compact submanifold $M$ of a Kähler manifold $Z$ and to the action of $G$ on measures of $M$.

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1. Introduction

Stability theory in Kähler geometry has been intensively studied by many authors and from several points of view, see e.g. [15, 17, 18, 20, 21, 30, 31, 36, 40, 41]. This paper is inspired by the works of I. Mundet i Riera [38] and A. Teleman [42] where a systematical presentation of the stability theory in the non-algebraic Kählerian geometry of complex reductive Lie groups is given, and by the recent paper [8] where the first author jointly with A. Ghigi develops a geometrical
invariant theory on topological spaces, without assuming the existence of a symplectic structure. In particular, they apply the main results to the action of $U^C$ on measures on a compact Kähler manifold $Z$, where $U$ is a compact connected Lie group acting in Hamiltonian fashion on $Z$. This was also motivated by an application to upper bounds for the first eigenvalue of the Laplacian on functions \[2, 3, 4, 10, 28\].

In this paper we identify an abstract setting to develop the geometrical invariant theory for actions of real reductive Lie groups. More precisely, given a Hausdorff topological space $M$ with a continuous action of a non-compact real reductive Lie group $G = K \exp(p)$ and a set of functions formally similar to the classical Kempf-Ness function we define an analogue of the gradient map $\mathfrak{F} : M \rightarrow p$ and the usual concepts of stability.

The gradient map has been intensively studied in \[22, 23, 24, 26\] and many other papers. The main idea is to investigate a class of actions of real reductive Lie groups on complex spaces and on real submanifolds using momentum map techniques. This means that we consider a Kähler manifold $(Z, \omega)$ acted on by a complex reductive Lie group $U^C$ of holomorphic maps. The Kähler form $\omega$ is $U$-invariant, where $U$ is a compact form of $U^C$, and there exists a momentum map $\mu : Z \rightarrow u^*$. We recall that a momentum map $\mu$ is $U$-equivariant and for any $\xi \in u$, the gradient of the function $\mu^Z(x) = \mu(x)(\xi)$ is given by $J(\xi_Z)(p) = \frac{d}{dt}|_{t=0} \exp(t\xi)p$ is the vector field corresponding to $\xi \in u$ and $J$ is the complex structure of $Z$ (see \[19, 34\] for more details about momentum map). Since $U$ is compact we may identify $u \cong u^*$ by means of an Ad($U$)-invariant scalar product on $u$. Hence we may think the momentum map as a $u$-valued map, i.e., $\mu : Z \rightarrow u$.

Let $G \subset U^C$ be compatible. Then $G$ is closed and the Cartan decomposition $U^C = U \exp(iu)$ induces a Cartan decomposition $G = K \exp(p)$, where $K = G \cap U$ and $p = g \cap iu$. Identifying $iu \cong u$ the inclusion $p \hookrightarrow iu$ induces a $K$-equivariant map $\mu_p : Z \rightarrow p$. Finally if $M$ is a $G$-stable real submanifold of $Z$, we may restrict $\mu_p$ to $M$ and so considering $\mu_p : M \rightarrow p$. The map $\mu_p : M \rightarrow p$ is called gradient map. In Section 7 we extend the construction given in \[37\] for the gradient map, defining a Kempf-Ness function of $(\mathcal{P}(M), G, K)$.

The $G$-action on $M$ induces in a natural way a continuous action on measures of $M$, that we denote by $\mathcal{P}(M)$, with respect to the weak-$*$ topology. In Section 8 we prove there exists a Kempf-Ness function for $(\mathcal{P}(M), G, K)$ and the map

$$\mathfrak{F}(\nu) = \int_M \mu_p(x)d\nu(x),$$

is the analogue of the gradient map in this setting. These are our basic examples and the main motivations to develop a geometrical invariant theory for actions of real reductive Lie groups.

Stability and semi-stability are checked using the position of the $G$-orbit with respect to the vanishing locus of the gradient map. The main point of our construction is that one can characterize stability, semi-stability and polystability of a point by numerical criteria, that is in terms of a function called maximal weight, which is defined on the Tits boundary of the symmetric space of non-compact type $G/K$. Roughly speaking we extend criteria for stability, semi-stability and polystability due to Teleman \[42\], Mundet I Riera \[37, 38\], Kapovich, Leeb
and Milson [29], Biliotti and Ghigi [8] and probably many others, for a large class of actions of complex reductive Lie groups, to actions of non-compact real reductive Lie groups. Our criterion for polystability is weaker than those proved by Mundet i Riera [38] and by the first author and Ghigi in [8] for complex reductive Lie groups. However if $G = K^C = K \exp(\mathfrak{k})$ is complex reductive then condition (P3) in Section 3 i.e., $\frac{d^2}{dt^2} \bigg| _{t=0} \Psi(x, \exp(tv)) = 0$ if and only if $\exp(\mathbb{R}v) \subset G_x$, does not imply $\exp(\mathbb{C}v) \subset G_x$ as required by (P3) in [8, p. 6]. This condition is crucial in Mundet’s proof [38] and in the proof given in [8] for polystability. Indeed, thanks to the $K$-equivariance of $\mathfrak{g}$, if $\exp(\mathbb{C}v) \subset G_x$, then $\mathfrak{g}(x) \in \mathfrak{p}^v = \{ u \in \mathfrak{p} : [u, v] = 0 \}$ and thus a sort of a reduction principle applied.

In the abstract setting introduced in this paper, the above condition is equivalent to the following: if $\exp(\mathbb{R}v) \subset G_x$ then $\mathfrak{g}(x) \in \mathfrak{p}^v = \{ u \in \mathfrak{p} : [u, v] = 0 \}$. This does not hold for a general gradient map $\mathfrak{g}$ since it is only $K$-equivariant. On the other hand this condition holds for the gradient map [24] and the gradient map defined by the Kempf-Ness function with respect to the $G$ action on measure (Proposition 45). The authors believe that the polystability criterion due to Mundet [38] holds under the above condition. We leave this problem for future investigation.

What is satisfactory of Theorem 33 is that the reductivity of the stabilizer is obtained as a consequence of conditions involving only the maximal weight and the set on which the maximal weight is zero. We also prove a version of the Hilbert-Mumford criterion and the openness of the set of stable points. Finally we completely characterize stable, semi-stable and polystable measures on real projective spaces.

The paper is organized as follows.

In Section 2 we review basic facts on real reductive Lie groups and Tits boundary of a Hadamard manifold.

In Section 3 we define the abstract setting and the general gradient map with respect to a Kempf-Ness function of $(\mathcal{M}, G, K)$.

In Section 4 we define the maximal weight on the Tits boundary of $X = G/K$. Since the Kempf-Ness function is $K$-invariant, for any $x \in \mathcal{M}$ the Kempf-Ness function descends to a function $\psi_x : X \longrightarrow \mathbb{R}$ which is geodesically convex. If $\psi_x$ is Lipschitz then Lemma 9 defines what is called maximal weight on the Tits boundary of $X$. We also point out that the maximal weight is $G$-equivariant.

In Section 5 we define stable, semi-stable and polystable points giving a numerical criterion for an element $x \in \mathcal{M}$ to be stable (Theorem 23). We give a version of the Hilbert-Mumford criterion (Corollary 28) and we prove the openness of the set of stable points (Corollary 29).

In Section 6 we give numerical criteria for semi-stability (Theorem 35) and polystability (Theorem 33) and a Hilbert-Mumford criterion for semi-stable points (Corollary 36).

In Section 7 we discuss the basic example, i.e., the classical gradient map, and in Section 8 we apply our setting on the $G$ action on measures. Using the Morse-Bott theory of the gradient map on $M$ we compute rather explicitly the maximal weight. Moreover, assuming the convexity
theorem holds for abelian subgroup $A = \exp(a)$ where $a \subset \mathfrak{p}$, see [6, 26] for more details, if $0 \in E(\mu_p)$, where $E(\mu_p)$ is the convex hull of the image of the gradient map $\mu_p$, then any smooth measures is semi-stable (Proposition 55). The condition $0 \in E(\mu_p)$ is always satisfied up to shifting the gradient map with respect to some $\text{Ad}(K)$-fixed point of $\mathfrak{p}$. We also prove that the set of semi-stable points is dense. If $0$ lies in the interior of $E(\mu_p)$ then any smooth measures is stable and the set of stable points is open and dense. This condition is always satisfied if $M$ is an adjoint orbit of $K$ in $\mathfrak{p}$ and $K$ acts irreducibly on $\mathfrak{p}$.

In Section 9 we completely describe stable, semi-stable and polystable measures on real projective spaces.

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2. Tits boundary of $G/K$

Let $G$ be a non-compact real reductive Lie group and denote by $\mathfrak{g}$ its Lie algebra. Recall that such $G$ has a finite number of connected components and its algebra splits as $\mathfrak{g} = [\mathfrak{g}, \mathfrak{g}] \oplus \mathfrak{z}(\mathfrak{g})$, where $[\mathfrak{g}, \mathfrak{g}]$ is semisimple and $\mathfrak{z}(\mathfrak{g})$ is the center of $\mathfrak{g}$. Further, maximal compact subgroups of $G$ always exist and meet every connected components, and any two of them are conjugate under an element of the identity component $G^0$ of $G$. Assume that there exists a Cartan involution $\theta : G \to G$ with fixed points set $K$ and let us denote also by $\theta : \mathfrak{g} \to \mathfrak{g}$ its differential. Then $\mathfrak{g} = \mathfrak{k} \oplus \mathfrak{p}$ and the map $f : K \times \mathfrak{p} \to G$, $f(g, v) = g \exp v$ is a diffeomorphism. This means that $G = K \exp(\mathfrak{p})$ and $G/K$ is simply connected. Since $\theta|_\mathfrak{k} = \text{Id}$ and $\theta|_\mathfrak{p} = -\text{Id}$, we have $[\mathfrak{k}, \mathfrak{k}] \subset \mathfrak{k}$, $[\mathfrak{k}, \mathfrak{p}] \subset \mathfrak{p}$ and $[\mathfrak{p}, \mathfrak{p}] \subset \mathfrak{k}$. Therefore if $\mathfrak{a} \subset \mathfrak{p}$ is a Lie subalgebra, then it must be abelian. Moreover, two maximal abelian subalgebras contained in $\mathfrak{p}$ are conjugate with respect to the identity component $K^0$. We refer the reader to [9, 27, 32] for more details on real reductive Lie groups.

Set 

$$X := G/K.$$ 

Observe that $G$ acts isometrically on $X$ from the left by:

$$L_g : X \to X, \quad L_g(hK) := ghK, \quad g \in G.$$ 

To simplify the notation, we will often write $gx$ instead of $L_g(x)$. The choice of an $\text{Ad}(K)$-invariant scalar product on $\mathfrak{p}$ induces a $G$-invariant Riemannian metric on $X$. It is well known that $X$ endowed with this metric is a symmetric space of non-compact type and thus a Hadamard manifold [13, 27]. The Riemannian exponential map arises by the exponential map of Lie groups. Hence a geodesic on $X$ is given by $g \exp(tv)K$, where $g \in G$ and $v \in \mathfrak{p}$. In the sequel we denote by $\gamma^v(t) = \exp(tv)K$.

Since $X$ is a Hadamard manifold there is a natural notion of boundary at infinity $\partial_\infty X$ which can be described using geodesics.
Two unit speed geodesic rays $\gamma, \gamma' : (0, +\infty) \to X$ are equivalent, denoted by $\gamma \sim \gamma'$, if $
exists t \in (0, +\infty) d(\gamma(t), \gamma'(t)) < +\infty$. The *Tits boundary* of $X$, denoted by $\partial X$, is the set of equivalence classes of unit speed geodesic ray in $X$.

Set $o := K \in X$. Mapping $v \mapsto \dot{\gamma}_v(0)$ yields an isomorphism $p \cong T_oX$. Since any geodesic ray in $X$ is equivalent to a unique ray starting from $o$, the map 

\[ e : S(p) \to \partial X, \quad e(v) := [\gamma_v], \]

where $S(p)$ is the unit sphere in $p$, is a bijection. The *sphere topology* is the topology on $\partial X$ such that $e$ is a homeomorphism. (For more details on the Tits boundary see for example [9, §1.2] and [13].)

Since $G$ acts by isometries on $X$, if $\gamma$ is a unit speed geodesic in $X$, then for each $g \in G$ also $g\gamma$ is. Further, since $\gamma \sim \gamma'$ implies $g\gamma \sim g\gamma'$, we get a $G$-action on the Tits boundary $\partial X$ by:

\[ g \cdot [\gamma] = [g\gamma], \]

which also induces by (1) a $G$-action on $S(p)$ given by:

\[ g : v = e^{-1}(g \cdot e(v)). \]

Observe that this last one is discontinuous with respect to the sphere topology on $S(p)$.

**Definition 2.** Let $H \subset G$ be a closed subgroup. Set $L := H \cap K$ and $\hat{p} := \mathfrak{h} \cap p$. According to [24] [25], we say that $H$ is compatible if $H = L \exp(\hat{p})$.

If $H$ is a compatible subgroup of $G$, then it follows that it is a real reductive subgroup of $G$, the Cartan involution of $G$ induces a Cartan involution of $H$, $L$ is a maximal compact subgroup of $H$ and finally $\mathfrak{h} = \mathfrak{t} \oplus \hat{p}$. Note that $H$ has finitely many connected components. Moreover, there are totally geodesic inclusions $X' := H/L \hookrightarrow X$ and $\partial X' \subset \partial X$.

### 3. Kempf-Ness functions

Let $\mathcal{M}$ be a Hausdorff topological space and let $G$ be a non-compact real reductive group which acts continuously on $\mathcal{M}$. Observe that with these assumptions we can write $G = K \exp(p)$, where $K$ is a maximal compact subgroup of $G$. Starting with these data we consider a function $\Psi : \mathcal{M} \times G \to \mathbb{R}$, subject to five conditions. The first four are the following ones:

1. **(P1)** For any $x \in \mathcal{M}$ the function $\Psi(x, \cdot)$ is smooth on $G$.
2. **(P2)** The function $\Psi(x, \cdot)$ is left–invariant with respect to $K$, i.e.: $\Psi(x, kg) = \Psi(x, g)$.
3. **(P3)** For any $x \in \mathcal{M}$, and any $v \in \mathfrak{p}$ and $t \in \mathbb{R}$:

$$\frac{d^2}{dt^2} \Psi(x, \exp(tv)) \geq 0.$$  

Moreover:

$$\left. \frac{d^2}{dt^2} \right|_{t=0} \Psi(x, \exp(tv)) = 0$$

if and only if $\exp(\mathbb{R}v) \subset G_x$.  


(P4) For any \( x \in \mathcal{M} \), and any \( g, h \in G \):
\[
\Psi(x, g) + \Psi(gx, h) = \Psi(x, hg).
\]

This equation is called the **cocycle condition**.

As in the previous section, let \( X = G/K \). If \( \Psi \) is a function satisfying (P1)–(P4), then by (P2) the function \( g \mapsto \Psi(x, g^{-1}) \) descends to a function on \( X \):
\[
\psi_x : X \to \mathbb{R}, \quad \psi_x(gK) := \Psi(x, g^{-1}),
\]
and the cocycle condition (P4) can be rewritten in terms of \( \psi_x \) as:
\[
(P4') \quad \psi_x(ghK) = \psi_x(gK) + \psi_{g^{-1}x}(hK),
\]
which is also equivalent to the following identity between two functions and a constant:
\[
L^*_g \psi_x = \psi_{g^{-1}x} + \psi_x(gK),
\]
where \( L_g \) denotes the action of \( G \) on \( X \) (see previous section).

In order to state our fifth condition, let \( \langle \cdot, \cdot \rangle : p^* \times p \to \mathbb{R} \) be the duality pairing. For \( x \in \mathcal{M} \) define \( \mathfrak{F}(x) \in p^* \) by requiring that:
\[
\langle \mathfrak{F}(x), v \rangle = -d(\psi_x)_o(\dot{\gamma}^v(0)) = \left. \frac{d}{dt} \right|_{t=0} \psi_x(\exp(-tv)K) = \left. \frac{d}{dt} \right|_{t=0} \Psi(x, \exp(tv)).
\]

The following is the fifth and last condition imposed on the function \( \Psi \):

(P5) The map \( \mathfrak{F} : \mathcal{M} \to p^* \) is continuous.

We call \( \mathfrak{F} \) the **gradient map** of \((\mathcal{M}, G, K, \Psi)\). As immediate consequence of the definition of \( \mathfrak{F} \) we have the following result.

**Proposition 5.** The map \( \mathfrak{F} : \mathcal{M} \to p^* \) is \( K \)-equivariant.

**Proof.** It is an easy application of the cocycle condition and the left-invariance with respect to \( K \) of \( \Psi(x, \cdot) \). Indeed,
\[
\langle \mathfrak{F}(kx), v \rangle = \left. \frac{d}{dt} \right|_{t=0} \Psi(x, \exp(tv)k) = \left. \frac{d}{dt} \right|_{t=0} \Psi(x, k^{-1}\exp(tv)k)
\]
\[
= \left. \frac{d}{dt} \right|_{t=0} \Psi\left(x, \exp(t\text{Ad}(k^{-1})(v))\right) = \text{Ad}^*(k)(\mathfrak{F}(x))(v).
\]
\(\square\)

The following definition summarizes the above discussion.

**Definition 6.** Let \( G \) be a non-compact real reductive Lie group, \( K \) a maximal compact subgroup of \( G \) and \( \mathcal{M} \) a topological space with a continuous \( G \)-action. A Kempf-Ness function for \((\mathcal{M}, G, K)\) is a function
\[
\Psi : \mathcal{M} \times G \to \mathbb{R},
\]
that satisfies conditions (P1)–(P5).
Remark 7. Taking \( g = h = e \) in the cocycle condition \((P4)\) we have \( \Psi(x,e) = 0 \). Hence \( \Psi(x,k) = 0 \) for every \( k \in K \), since \( \Psi(x,\cdot) \) is \( K \)-invariant on the second factor. Moreover, for any \( x \in \mathcal{M} \) and for any \( g, h \in G_x \) we have:

\[
\Psi(x, hg) = \Psi(x, g) + \Psi(x, h),
\]

which implies that \( \Psi(x, \cdot) : G_x \to \mathbb{R} \) is a homomorphism.

4. Maximal weights

Let \( X = G/K \) and let \( u : X \to \mathbb{R} \) be a smooth function. We say that \( u \) is geodesically convex on \( X \) if \( u(\gamma(t)) \) is a convex function for any geodesic \( \gamma(t) \) in \( X \). The following lemma is proven in greater generality by Kapovich, Leeb and Millson in [29, §3.1] (see also [8, §2.3]).

Lemma 9. Let \( u : X \to \mathbb{R} \) be a smooth geodesically convex function on \( X \). Assume that \( u \) is globally Lipschitz continuous. Then the function \( u_\infty : \partial_\infty X \to \mathbb{R} \) given by:

\[
u_\infty([\gamma]) := \lim_{t \to +\infty} (u \circ \gamma)'(t),\]

is well-defined. Moreover \( u \) is an exhaustion if and only if \( u_\infty > 0 \) on \( \partial_\infty X \).

Recall that a continuous function \( f : X \to \mathbb{R} \) is an exhaustion if for any \( c \in \mathbb{R} \) the set \( f^{-1}((-\infty, c]) \) is compact, condition which is equivalent for \( f \) to be bounded below and proper.

As in [8], the following result holds.

Lemma 11. The function \( \psi_x \) is geodesically convex on \( X \). More precisely, if \( v \in p \) and \( \alpha(t) = g \exp(tv)K \) is a geodesic in \( X \), then \( \psi_x \circ \alpha \) is either strictly convex or affine. The latter case occurs if and only if \( g \exp(Rv)g^{-1} \subset G_x \). In the case \( g = e \), the function \( \psi_x \circ \alpha \) is linear if \( \exp(Rv) \subset G_x \) and strictly convex otherwise.

Due to Lemma 11, in order to apply Lemma 9 to \( \psi_x \), we need only to add this last assumption:

\((P6)\) For any \( x \in \mathcal{M} \), the function \( \psi_x : X \to \mathbb{R} \) is globally Lipschitz on \( X \).

When property \((P6)\) holds, for any \( x \in \mathcal{M} \) the function \( \lambda_x := (\psi_x)_\infty \) given by:

\[
\lambda_x : \partial_\infty X \to \mathbb{R} \quad \lambda_x([\gamma]) := \lim_{t \to +\infty} \frac{d}{dt} \psi_x(\gamma(t)),
\]

is well-defined and finite. We call \( \lambda_x \) maximal weight. Moreover for any \( x \in \mathcal{M} \), any \( g \in G \) and any \( p \in \partial_\infty X \) we have (see [8, Lemma 2.28] for a proof):

\[
\lambda_{g^{-1}x}(p) = \lambda_x(g \cdot p).
\]

It is also well-defined and finite the function:

\[
\lambda : \mathcal{M} \times \partial_\infty X \to \mathbb{R}, \quad \lambda(x, p) := \lambda_x(p).
\]

Since we set the sphere topology on \( \partial_\infty X \), i.e., the topology on \( \partial_\infty X \) such that \( e : S(p) \to \partial_\infty X \) is an homeomorphism (see Section 2), by [8, Lemma 4.9], \( \lambda \) is lower semicontinuous and for
$$v \in S(\mathfrak{p})$$ it follows:

$$\lambda_x(e(v)) = \lim_{t \to +\infty} \frac{d}{dt} \psi_x(e(tv)K) = \lim_{t \to +\infty} \frac{d}{dt} \Psi(x, e(-tv)).$$

5. Stability

Let $$(\mathcal{M}, G, K)$$ be as above and let $$\Psi$$ be a Kempf-Ness function. In particular, according to Definition 6 we assume that $$\Psi$$ satisfies conditions (P1)–(P5).

Definition 16. Let $$x \in \mathcal{M}$$. Then:

a) $$x$$ is polystable if $$Gx \cap \mathfrak{z}^{-1}(0) \neq \emptyset$$.

b) $$x$$ is stable if it is polystable and $$g_x$$ is conjugate to a subalgebra of $$\mathfrak{k}$$.

c) $$x$$ is semi-stable if $$Gx \cap \mathfrak{z}^{-1}(0) \neq \emptyset$$.

d) $$x$$ is unstable if it is not semi-stable.

Remark 17. The four conditions above are $$G$$-invariant in the sense that if a point $$x$$ satisfies one of them, then every point in the orbit of $$x$$ satisfy the same condition. This follows directly from the definition for polystability, semi-stability and unstability, while for stability it is enough to recall that $$g_x = \text{Ad}(g)(g_x)$$.

The following result establishes a relation between the Kempf-Ness function and polystable points.

Proposition 18. Let $$x \in \mathcal{M}$$. The following conditions are equivalent:

a) $$g \in G$$ is a critical point of $$\Psi(x, \cdot)$$;

b) $$\mathfrak{z}(gx) = 0$$;

c) $$g^{-1}K$$ is a critical point of $$\psi_x$$.

Proof. Let $$v \in \mathfrak{p}$$. Using the cocycle condition (P4), one gets:

$$\Psi(x, e(tv)g) = \Psi(x, g) + \Psi(gx, e(tv)).$$

Therefore,

$$\left. \frac{d}{dt} \right|_{t=0} \Psi(x, e(tv)g) = \left. \frac{d}{dt} \right|_{t=0} \Psi(gx, e(tv)) = \langle \mathfrak{z}(gx), v \rangle.$$ (19)

Since for any $$k \in K$$, $$\Psi(x, kg) = \Psi(x, g)$$, then $$\mathfrak{z}(gx) = 0$$ if and only if $$g$$ is a critical point of $$\Psi(x, \cdot)$$ if and only if $$g^{-1}K$$ is a critical point of $$\psi_x$$. \qed

Proposition 20. If $$\mathfrak{z}(x) = 0$$, then $$G_x$$ is compatible.

Proof. Let $$g \in G_x$$. Then $$g = k \exp(v)$$ for some $$k \in K$$ and $$v \in \mathfrak{p}$$. By Proposition 5 we have $$\mathfrak{z}(\exp(v)x) = 0$$. Let $$f(t) := \mathfrak{z}^v(\exp(tv)x)$$. Then $$f(0) = f(1) = 0$$ and

$$\frac{d}{dt} f(t) = \frac{d}{dt} \mathfrak{z}^v(\exp(tv)x) = \frac{d^2}{dt^2} \Psi(x, e(tv)) \geq 0.$$ 

Therefore $$\frac{d^2}{dt^2} \Psi(x, e(tv)) = 0$$ for $$0 \leq t \leq 1$$. It follows from (P3) that $$\exp(tv)x = x$$ for any $$t \in \mathbb{R}$$ and thus $$G_x$$ is compatible. \qed
Next we give a numerical criteria for an element \( x \in \mathcal{M} \) to be stable. We begin with the following lemma.

**Lemma 21.** If \( a \subset \mathfrak{g} \) is a subalgebra which is conjugate to a subalgebra of \( \mathfrak{k} \), then \( a \cap \mathfrak{p} = \{0\} \).

**Proof.** It is enough to show that \( \text{Ad}(g)(\mathfrak{k}) \cap \mathfrak{p} = \{0\} \) for any \( g \in G \). Let \( x \in \text{Ad}(g)(\mathfrak{k}) \cap \mathfrak{p} \). By the Cartan decomposition \( G = K \exp(\mathfrak{p}) \), it follows that \( \Gamma = \exp(\mathbb{R}X) \) is a closed abelian subgroup of \( G \) isomorphic to \( \mathbb{R} \). On the other hand \( X = \text{Ad}(g)(Y) \) for some \( Y \in \mathfrak{k} \) which implies \( \Gamma = \text{Ad}(g)(\exp(\mathbb{R}Y)) \) is a torus. Hence \( X = 0 \). \( \square \)

Consider the function:

\[
\Lambda : \mathcal{M} \times \mathfrak{p} \to [-\infty, +\infty],
\]

\[
\Lambda(x, \xi) := \lim_{t \to +\infty} \frac{d}{dt} \Psi(x, \exp(t\xi)) = \lim_{t \to +\infty} \frac{d}{dt} \psi_x(-t\xi K).
\]

The following Lemma is proven in \[42, \text{Lemma 2.10}\].

**Lemma 22.** Let \( V \) be a subspace of \( \mathfrak{p} \). For a point \( x \in \mathcal{M} \) the following conditions are equivalent:

a) The map \( \Psi(x, \exp(\xi)) \) is linearly proper on \( V \), i.e. there exist positive constants \( C_1 \) and \( C_2 \) such that:

\[
||\xi||^2 \leq C_1 \Psi(x, \exp(\xi)) + C_2, \quad \forall \xi \in V.
\]

b) \( \Lambda(x, \xi) > 0 \) for any \( \xi \in V - \{0\} \).

**Theorem 23.** Let \( x \in \mathcal{M} \). Then \( x \) is stable if and only if \( \Lambda(x, \xi) > 0 \) for any \( \xi \in \mathfrak{p} - \{0\} \).

**Proof.** Let first \( x \in \mathcal{M} \) be stable. Then \( \mathfrak{g}(gx) = 0 \) for some \( g \in G \) and by Proposition \[18\] \( g \) is a critical point of \( \Psi(x, \cdot) \). Set \( y = gx \). We start by proving \( \Lambda(y, \xi) > 0 \) for any \( \xi \in \mathfrak{p} - \{0\} \). By \( (P3) \) the function \( f(t) = \Psi(y, \exp(t\xi)) \) is a convex function. Hence:

\[
\Lambda(y, \xi) \geq f'(0) = \frac{d}{dt} \bigg|_{t=0} \Psi(y, \exp(t\xi)) = \langle \mathfrak{g}(y), \xi \rangle = 0.
\]

Assume \( \Lambda(y, \xi) = 0 \). By assumption \( f \) is a convex function satisfying \( \lim_{t \to +\infty} f'(t) = 0 \) and \( f'(0) = 0 \). Hence \( f'(t) = 0 \) for \( t \geq 0 \) and so \( \frac{d^2}{dt^2} \Psi(x, \exp(t\xi)) = 0 \) for any \( t \geq 0 \). By \( (P3) \) it follows that \( \exp(\mathbb{R}\xi) \subset G_y \), so \( \xi \in \mathfrak{g}_y \cap \mathfrak{p} \). Since \( x \) is stable, \( \mathfrak{g}_y = \text{Ad}(g)(\mathfrak{g}_x) \) is conjugate to a subalgebra of \( \mathfrak{k} \), thus Lemma \[21\] implies that \( \xi = 0 \).

By Lemma \[22\] the function \( \Psi(y, \cdot) \) is linearly proper on \( \mathfrak{p} \). By the cocycle condition we have

\[
\Psi(x, \exp(\xi)) = \Psi(g^{-1}y, \exp(\xi)) = \Psi(y, \exp(\xi)g^{-1}) - \Psi(y, g^{-1}).
\]

Write \( \exp(\xi)g^{-1} = \kappa(\xi) \exp(\theta(\xi)) \). Then \( \Psi(x, \exp(\xi)) = \Psi(y, \exp(\theta(\xi))) - \Psi(y, g^{-1}) \). Using the same arguments in \[37\], we get an estimate of the form

\[
||\xi||^2 \leq A_1 ||\theta(\xi)||^2 + A_2,
\]

where \( A_1 \) and \( A_2 \) are positive constants. Therefore the linearly properness of \( \Psi(y, \cdot) \) on \( \mathfrak{p} \) implies the linearly properness of \( \Psi(x, \cdot) \) on \( \mathfrak{p} \). Hence, by Lemma \[22\] \( \Lambda(x, \xi) > 0 \) for any \( \xi \in \mathfrak{p} - \{0\} \).
Assume now that \( \Lambda(x, \xi) > 0 \) for any \( \xi \in \mathfrak{p} - \{0\} \). Then \( \Lambda(x, \cdot) \) restricted on the unit sphere \( S(\mathfrak{p}) \) of \( \mathfrak{p} \) has a minimum \( C > 0 \).

Let \( \xi \in S(\mathfrak{p}) \) and let \( f(t) = \Psi(x, \exp(t\xi)) \). The function \( f \) is a convex function and \( \lim_{t \to -\infty} f'(t) \geq C \), respectively \( \lim_{t \to -\infty} f'(t) \leq -C \). Hence \( f \) has a global minimum and \( \lim_{t \to +\infty} f(t) = +\infty \). Thus, for any \( M > 0 \), there exists \( t(\xi) > 0 \) such that \( f(t) = \Psi(x, \exp(t\xi)) > M \) for any \( t \geq t(\xi) \).

We claim that there exists \( \gamma_0 > 0 \) such that \( \Psi(x, \exp(\xi)) > \frac{M}{2} \) for \( \xi \in \mathfrak{p} \) with \( ||\xi|| \geq \gamma_0 \). Indeed, otherwise there exist sequences \( \xi_n \in S(\mathfrak{p}) \) and \( t_n \in \mathbb{R} \) with \( t_n \to +\infty \) such that \( \Psi(x, \exp(t_n\xi_n)) \leq \frac{M}{2} \). We may assume \( t_n \to t_0 \). Since \( \Psi(x, \exp(t_0\xi_0)) \geq M \) for \( t > t(\xi_0) \) and keeping in mind that the function

\[
\mathbb{R} \times S(\mathfrak{p}) \to \mathbb{R}, \quad (t, \xi) \to \Psi(x, \exp(t\xi)),
\]

is continuous, there exists a neighborhood \( U \) of \( \xi_0 \) in \( S(\mathfrak{p}) \) and a neighborhood \( (t(\xi_0) - \epsilon, t(\xi_0) + \epsilon) \) of \( (t(\xi_0), 0) \) in \( \mathbb{R} \), such that \( \Psi(x, \exp(t\xi)) > \frac{M}{2} \) for any \( t \in (t(\xi_0) - \epsilon, t(\xi_0) + \epsilon) \) and for any \( \xi \in U \).

Now, there exists \( \tilde{n} \in \mathbb{N} \) such that \( \xi_n \in U \) and \( t_n > t(\xi_0) \) for \( n \geq \tilde{n} \). Since the function \( t \mapsto \Psi(x, \exp(t\xi)) \) increases, it means \( \Psi(x, \exp(t_n\xi_n)) > \frac{M}{2} \) for \( n \geq \tilde{n} \) which is a contradiction.

Now, keeping in mind that \( \psi_x \circ \exp(\xi) = \Psi(x, \exp(-\xi)) \), we have proved that the function \( \psi_x \circ \exp \) has a minimum and so a critical point. Since \( \exp : \mathfrak{p} \to G/K \) is a diffeomorphism, it follows that \( \psi_x \) has a critical point. By Proposition \( \ref{prop:polystab} \) the point \( x \) is polystable. Let \( g \in G \) such that \( \mathfrak{g}(gx) = 0 \). Set \( y = gx \). Since

\[
\Lambda(y, \xi) \geq \left. \frac{d}{dt} \right|_{t=0} \Psi(y, \exp(t\xi)) = \langle \mathfrak{g}(y), \xi \rangle = 0,
\]

by the same arguments used before, we have \( \Lambda(y, \xi) > 0 \) for any \( \xi \in \mathfrak{p} - \{0\} \). To conclude the proof we prove \( \mathfrak{g}_y \cap \mathfrak{p} = \{0\} \).

Let \( \xi \in \mathfrak{g}_y \cap \mathfrak{p} \). By Remark \( \ref{rem:polystab} \) the function \( t \mapsto \Psi(y, \exp(t\xi)) \) is linear. Since both \( \Lambda(y, \xi) \) and \( \Lambda(y, -\xi) \) are positive it follows

\[
\lim_{t \to +\infty} \frac{d}{dt} \Psi(y, \exp(t\xi)) = a \geq 0, \quad \lim_{t \to +\infty} \frac{d}{dt} \Psi(y, \exp(-t\xi)) = -a \geq 0.
\]

This implies \( a = 0, \Lambda(y, \xi) = 0 \) and so \( \xi = 0 \). By Proposition \( \ref{prop:g-y-locally-nilpotent} \) \( \mathfrak{g}_y \) is a compatible subalgebra of \( \mathfrak{g} \) with \( \mathfrak{g}_y \cap \mathfrak{p} = \{0\} \). Hence \( \text{Ad}(g)(\mathfrak{g}_x) = \mathfrak{g}_y \subset \mathfrak{k} \) proving \( x \) is stable. \( \square \)

**Remark 24.** One may prove that the condition \( \Lambda(x, \xi) > 0 \) for any \( \xi \in \mathfrak{p} - \{0\} \) is equivalent to \( \psi_x \) being an exhaustion.

**Corollary 25.** If \( x \in \mathcal{M} \) is stable, then \( G_x \) is compact.

**Proof.** Let \( g \in G \) be such that \( \mathfrak{g}(gx) = 0 \) and set \( y = gx \). By Proposition \( \ref{prop:g-y-locally-nilpotent} \) the stabilizer of \( y \), i.e. \( G_y \), is compatible and so has only finitely many connected components. Moreover \( G_0^y \) is compact since \( \mathfrak{g}_y \subset \mathfrak{k} \). It follows that \( G_y \) and \( G_x = g^{-1}G_yg \) are both compact. \( \square \)

If \( \mathcal{M}' \) is a \( G \)-invariant subspace of \( \mathcal{M} \), the restriction of \( \Psi \) to \( G \times \mathcal{M}' \) is a Kempf-Ness function for \( (\mathcal{M}', G, K) \). The functions \( \Lambda \) and \( \mathfrak{g} \) for \( (\mathcal{M}', G, K) \) are simply the restrictions of those for \( \mathcal{M} \). If \( G' \subset G \) is a compatible subgroup of \( G \), i.e., \( G' = K' \exp(p') \), then \( K' \subset K \), \( p' \subset \mathfrak{p} \) and
$X' := G'/K' \hookrightarrow X$ is a totally geodesic inclusion. If $\Psi$ is a Kempf-Ness function for $(G, K, \mathcal{M})$, then $\Psi^K' := \Psi|_\mathcal{M} \times G'$ is a Kempf-Ness function for $(G', K', \mathcal{M})$. The related functions are

$$
\tilde{\mathfrak{g}}^{K'} : \mathcal{M} \to \mathfrak{p}^*, \quad \tilde{\mathfrak{g}}^{K'}(x) := \tilde{\mathfrak{g}}(x)|_{\mathfrak{p}'},
$$

$$
\psi^{K'}_2 := \psi_{x'}|_{\mathfrak{p}'}, \quad \Lambda^{K'} = \Lambda|_{\mathcal{M} \times \mathfrak{p}'}.
$$

A subalgebra contained in $\mathfrak{p}$ must be abelian since $[\mathfrak{p}, \mathfrak{p}] \subset \mathfrak{k}$. The following Corollary is analogous to the stability part in the Hilbert-Mumford criterion.

**Corollary 28.** A point $x \in \mathcal{M}$ is $G$-stable if and only if it is $A$-stable for any abelian group $A = \exp(a)$, where $a$ is a subalgebra of $\mathfrak{g}$ contained in $\mathfrak{p}$.

**Proof.** By Theorem 23 it is enough to prove that we have $\Lambda(x, \xi) > 0$ for any $\xi \in \mathfrak{p} - \{0\}$ if and only if for any abelian group $A = \exp(a)$, where $a$ is a subalgebra of $\mathfrak{g}$ contained in $\mathfrak{p}$ we have $\Lambda^A(x, \xi) > 0$ for any $\xi \in a - \{0\}$. The necessary condition is trivial, being $\Lambda^A(x, \xi)$ the restriction of $\Lambda(x, \xi)$ to $a$. For the sufficient, observe that for any $\xi \in S(\mathfrak{p})$ we can set $a = \mathbb{R}\xi$ and conclusion follows since with this choice we have $\Lambda(x, \xi) = \Lambda^A(x, \xi)$.

We conclude this section with the following interesting result.

**Corollary 29.** The function $\Lambda : \mathcal{M} \times S(\mathfrak{p}) \to \mathbb{R}$ is lower semicontinuous and the set of stable points is open in $\mathcal{M}$.

**Proof.** The proof of [8, Lemma 3.9] works also for $\Lambda$ proving it is lower semicontinuous. The openness of the stable points can be proved as in [8, Corollary 3.10].

## 6. Polystability and semi-stability

The aim of this section is to characterize polystability and semi-stability of $x \in \mathcal{M}$ in terms of the maximal weight $\lambda_x$. Throughout this section we assume that the Kempf-Ness function of $(\mathcal{M}, G, K)$ satisfies not only (P1)–(P5) but also (P6). Further, for semi-stability we also assume that $\mathcal{M}$ is compact. This will be enough for the case of measures on a compact manifold.

Let us denote by $\mathcal{M}^{ps}$ the set of polystable points, i.e. according to Definition 10

$$
\mathcal{M}^{ps} = \{ x \in \mathcal{M} : Gx \cap \tilde{\mathfrak{g}}^{-1}(0) \neq \emptyset \}.
$$

It follows by an easy argument that if $x \in \mathcal{M}$ is polystable then $Gx \cap \tilde{\mathfrak{g}}^{-1}(0)$ contains exactly one $K$-orbit. Indeed, let $y \in Gx$ be such that $\tilde{\mathfrak{g}}(y) = 0$. We shall prove that $Ky = Gy \cap \tilde{\mathfrak{g}}^{-1}(0)$. Assume that $gy \in \tilde{\mathfrak{g}}^{-1}(0)$. Set $g = k \exp(v)$. By the $K$-equivariance of $\tilde{\mathfrak{g}}$ it follows $\tilde{\mathfrak{g}}(\exp(v)y) = 0$. As in the proof of Proposition 20, we get $\mathbb{R}v \in \mathfrak{g}_y$ and so $Gy \cap \tilde{\mathfrak{g}}^{-1}(0) = Ky$. Hence we have proven the following result.

**Proposition 30.** The inclusion $\tilde{\mathfrak{g}}^{-1}(0) \hookrightarrow \mathcal{M}^{ps}$ induces a bijection

$$
\tilde{\mathfrak{g}}^{-1}(0)/K \longrightarrow \mathcal{M}^{ps}/G.
$$

In this section we give a numerical criteria for an element $x \in \mathcal{M}$ to be a polystable point. Let $x \in \mathcal{M}$. We define $Z(x) = \{p \in \partial_{\infty}X : \lambda_x(p) = 0\}$. We start with the following result.
Proposition 31. Let \( x \in \mathfrak{g}^{-1}(0) \). Then \( \lambda_x \geq 0 \), \( \mathfrak{g}_x = \mathfrak{k}_x \oplus \mathfrak{q} \subset \mathfrak{k} \oplus \mathfrak{p} \) is compatible and \( Z(x) = e(S(q)) = \partial_{\infty} \mathcal{G}_x / K_x \).

Proof. By Proposition 20 the stabilizer \( \mathcal{G}_x \) is compatible. Hence \( \mathfrak{g}_x = \mathfrak{k}_x \oplus \mathfrak{q} \) with \( \mathfrak{k}_x \subset \mathfrak{k} \) and \( \mathfrak{q} \subset \mathfrak{p} \). Further, observe that for \( \xi \in \mathfrak{p} \), since \( \Psi(x, \exp(t\xi)) \) is a convex function, we get:

\[
\Lambda(x, \xi) \geq \frac{d}{dt} \bigg|_{t=0} \Psi(y, \exp(t\xi)) = \langle \mathfrak{g}(y), \xi \rangle = 0.
\]

To conclude, we shall prove that \( v \in S(\mathfrak{q}) \) if and only if \( \lambda_x(e(-v)) = 0 \). Let first \( v \in S(\mathfrak{q}) \). By Remark 7 the function:

\[
f : \mathbb{R} \to \mathbb{R}, \quad t \mapsto \Psi(x, \exp(tv)),
\]

is linear. Since \( \lambda_x \geq 0 \), we have \( \lim_{t \to +\infty} f'(t) = a \geq 0 \) and \( \lim_{t \to +\infty} f'(-t) = -a \geq 0 \). Thus, \( f(t) = \Psi(x, \exp(tv)) = 0 \) and condition (P3) implies \( \lambda_x(e(-v)) = 0 \).

Vice-versa, assume \( \lambda_x(e(-v)) = 0 \) and consider again the function \( f(t) = \Psi(x, \exp(tv)) \). Observe that \( f \) is convex and by assumptions \( \lim_{t \to +\infty} f'(t) = 0 \) and \( f'(0) = \frac{d}{dt} \bigg|_{t=0} \Psi(x, \exp(tv)) = \langle \mathfrak{g}(x), v \rangle = 0 \). Hence \( f'(t) = 0 \) for \( t \geq 0 \). Therefore \( f''(t) = \frac{d^2}{dt^2} \bigg|_{t=0} \Psi(x, \exp(tv)) = 0 \). By property (P3) we get \( \mathbb{R} v \subset \mathfrak{q} \) concluding the proof.

Note that the inclusion \( \mathcal{G}_x / K_x \hookrightarrow X \) is totally geodesic. We claim that a vice-versa of Proposition 31 holds as well. We start with the following Lemma.

Lemma 32. Let \( x \in \mathcal{M} \). Assume \( \lambda_x \geq 0 \) and \( Z(x) = \partial_{\infty} X' \), where \( X' \) is a totally geodesic submanifold of \( X \). Then, there exists \( g \in \mathcal{G} \) such that setting \( y = gx \) we have \( Z(y) = \partial_{\infty} \mathcal{G}' / K' \), where \( \mathcal{G}' \) is compatible, \( G' \cap K = K' \) and \( G' \subset \mathcal{G}_y \).

Proof. Assume first \( o = [K] \subset X' \). We shall prove that the statement holds for \( g = e \). Since \( X' \) is a totally geodesic submanifold of \( X \) there exists a subspace \( \mathfrak{q} \subset \mathfrak{p} \), called Lie triple system of \( \mathfrak{p} \), such that \( X' = \exp(\mathfrak{q}) \) and \( [[\mathfrak{q}, \mathfrak{q}], \mathfrak{q}] \subset \mathfrak{q} \) (see e.g. [27]). We claim \( \mathfrak{q} \subset \mathfrak{g}_x \). Indeed, let \( v \in S(\mathfrak{q}) \). Since \( \lambda_x(e(-v)) = \lambda_x(e(v)) = 0 \), the convex function \( f(t) = \Psi(x, \exp(tv)) \) satisfies \( \lim_{t \to \pm\infty} f'(t) = 0 \). Hence \( f' \) is constant and so

\[
f''(0) = \frac{d^2}{dt^2} \bigg|_{t=0} \Psi(x, \exp(tv)) = 0.
\]

By properties (P3) we have \( v \in \mathfrak{g}_x \). Let \( \mathfrak{g}' = [\mathfrak{q}, \mathfrak{q}] \oplus \mathfrak{q} \). Observe that \( \mathfrak{g}' \) is a subalgebra of \( \mathfrak{g} \) due to the fact that \( \mathfrak{q} \) is a Lie triple system of \( \mathfrak{p} \) (see e.g. [27]). Let \( \mathcal{G}' \) denote the connected subgroup of \( \mathcal{G} \) with Lie algebra \( \mathfrak{g}' \). Hence \( \mathcal{G}' = (\mathcal{G}' \cap K) \exp(\mathfrak{q}) \) and \( \mathcal{G}' \subset \mathcal{G}_x \). Therefore \( \mathcal{G}' = \mathcal{G}' / K' \exp(\mathfrak{q}) \) is compatible, \( \mathcal{G}' \subset \mathcal{G}_x \) and if we denote by \( K' = \mathcal{G}' \cap K \) we have \( \partial_{\infty} X' = \partial_{\infty} \mathcal{G}' / K' \).

In general, for any \( g \in \mathcal{G} \) we can consider the totally geodesic submanifold defined by \( X'' = gX' \). Since by [13] it follows \( Z(gx) = g(Z(x)) \), we have:

\[
Z(gx) = g \partial_{\infty} X' = \partial_{\infty} X''
\]

and we are done.
Theorem 33. An element \( x \in \mathcal{M} \) is a polystable point if and only if \( \lambda_x \geq 0 \) and \( Z(x) = \partial_\infty X' \) for some totally geodesic submanifold \( X' \subset X = G/K \).

Proof. One direction is proved in Proposition 31. Assume \( \lambda_x \geq 0 \) and \( Z(x) = \partial_\infty X' \) for some totally geodesic submanifold \( X' \subset X = G/K \). By the above lemma and property [13], we may assume \( Z(x) = \partial_\infty G'/K' \) where \( G' = K' \exp(q) \subset G_x \), \( q' = \mathfrak{t}' \oplus q \) with \( \mathfrak{t}' \subset \mathfrak{t} \) and \( q \subset \mathfrak{p} \), \( G' = K' \exp(q) \) and \( Z(x) = e(S(q)) \). Write \( \mathfrak{p} = q \oplus q^\perp \). By a Mostow decomposition, see [23, Th. 9.3 p. 211], any \( g \in G \) can be written as \( g = k \exp(\theta)h \), where \( k \in K \), \( h \in G' \) and \( \theta \in q^\perp \).

Therefore by the \( K \)-invariants and the cocycle condition of \( \Psi \), keeping in mind that \( G' \subset G_x \), we get:

\[
\Psi(x, g) = \Psi(x, k \exp(\theta)h) = \Psi(x, \exp(\theta)) + \Psi(x, h).
\]

We claim that \( \Psi(x, h) = 0 \). Indeed, \( h = k \exp(v) \) with \( k \in K' \) and \( v \in q \). Hence \( \Psi(x, h) = \Psi(x, \exp(v)) \). As in the above lemma, we consider the function \( f(t) = \Psi(x, \exp(tv)) \) which is linear due to Remark [7]. Since \( \lambda_x(e(\pm v)) = 0 \), we have \( \lim_{t \to \pm \infty} f'(t) = 0 \), which implies \( f \equiv 0 \) and thus \( \Psi(x, h) = 0 \). Hence \( \Psi(x, g) = \Psi(x, \exp(\theta)) \). Since \( \Lambda(x, \cdot) > 0 \) on \( q^\perp - \{0\} \), by Lemma [22] there exist positive constants \( C_1 \) and \( C_2 \) such that

\[
||\theta||^2 \leq C_1 \Psi(x, \exp(\theta)) + C_2.
\]

This means \( \Psi(x, \cdot)_{|q^\perp} \) is an exhaustion and so it has a minimum. Since \( \Psi(x, g) = \Psi(x, \exp(\theta)) \) with \( \theta \in q^\perp \), this means that \( \Psi(x, \cdot) \) has a minimum and thus a critical point. By Proposition [18] the point \( x \) is polystable.

Corollary 34. Let \( x \in \mathcal{M} \) be a polystable point. Then there exist \( g \in G \) and an abelian subalgebra \( \mathfrak{a} \subset \mathfrak{p} \) such that \( \mathfrak{a} \subset \mathfrak{g}_{gx} \) and \( gx \) is \( G^\mathfrak{a} \) polystable, where \( G^\mathfrak{a} = \{ g \in G : Ag(g)(\xi) = \xi \) for all \( \xi \in \mathfrak{a} \} \). Moreover if we denote by \( G'_{ss} \) the semisimple part of \( G^\mathfrak{a} \), then \( gx \) is stable with respect to \( G'_{ss} \).

Proof. Let \( x \in \mathcal{M} \) be a polystable point and let \( g \in G \) be such that \( \mathfrak{g}(gx) = 0 \). Set \( y = gx \). By Proposition [31] \( G_y \) is compatible, and thus \( \mathfrak{g}_y = \mathfrak{t}_y \oplus \mathfrak{p}_y \subset \mathfrak{t} \oplus \mathfrak{p} \), and \( Z(y) = e(S(\mathfrak{p}_y)) \). Let \( \mathfrak{a} \) be a maximal abelian subalgebra of \( \mathfrak{p}_y \) and let \( G^\mathfrak{a} \) be the centralizer of \( \mathfrak{a} \) in \( G \). \( G^\mathfrak{a} \) is a compatible subgroup of \( G \) (see [32]) and by [26] it follows \( \mathfrak{g}^\mathfrak{a}(y) = 0 \) and so \( y \) is polystable with respect to \( G^\mathfrak{a} \). Let \( G'_{ss} \) be the semisimple part of \( G^\mathfrak{a} \). By [26] it follows that \( y \) is \( G'_{ss} \) polystable and so \( (G'_{ss})_y \) is compatible. We claim \( (G'_{ss})_y \cap \mathfrak{p} = \{0\} \). Indeed, if \( v \in (G'_{ss})_y \cap \mathfrak{p} \), then \( v \in \mathfrak{p}_y \) and \( [v, \mathfrak{a}] = 0 \). Since \( v \notin \mathfrak{a} \) and \( \mathfrak{a} \) is a maximal abelian subalgebra of \( \mathfrak{p}_y \) we get a contradiction. Since \( (G'_{ss})_y \) is compatible it follows \( (G'_{ss})_y \subset \mathfrak{t} \) and so \( (G'_{ss})_y \) is compact. Therefore \( y \) is \( G'_{ss} \) stable concluding the proof.

The following theorem, in analogy with [8 Th. 4.17], gives a numerical criteria for semi-stable points in terms of maximal weights. The proof is the same of the proof of [42, Theorem 4.3] and thus it follows by [29, Lemma 3.4] due to Kapovich, Leeb and Millson.

Theorem 35. If \( \mathcal{M} \) is compact, then a point \( x \in \mathcal{M} \) is semi-stable if and only if \( \lambda_x \geq 0 \).
The following result is a Hilbert-Mumford criterion for semi-stability. The proof is totally similar to Corollary 28’s one.

**Corollary 36.** A point \( x \in \mathcal{M} \) is \( G \) semi-stable if and only if it is \( A \) semi-stable for any abelian group \( A = \exp(a) \), where \( a \) is a subalgebra of \( \mathfrak{g} \) contained in \( \mathfrak{p} \).

We conclude this section with the following corollaries.

**Corollary 37.** Let \( x \in \mathcal{M} \) be a semi-stable point. Then either \( x \) is stable or \( Gx \cap \mathfrak{g}^{-1}(0) \subset \mathcal{M}^{ps} \).

**Proof.** Let \( x \in \mathcal{M} \) be a semi-stable point which is not stable. Setting \( \mathcal{M}' = Gx \), the restriction of \( \Psi \) to \( G \times \mathcal{M}' \) is a Kempf-Ness function for \( (\mathcal{M}',G,K) \) and the functions \( \Lambda \) and \( F \) for \( (\mathcal{M}',G,K) \) are simply the restrictions of those for \( \mathcal{M} \). By Corollary 29 the set of stable points of \( \mathcal{M}' \) is open. By definition the set of stable points is \( G \)-invariant. Hence if a point \( z \in \mathcal{M}' \) were stable, then \( x \) would also be stable contradicting our assumption. \( \square \)

**Corollary 38.** If \( x \in \mathcal{M} \) is semistable then any \( y \in Gx \) also is.

**Proof.** Let \( g_\alpha \in G \) be a net such that \( g_\alpha x \to y \) and let \( v \in \partial_\infty X \). By the \( G \)-equivariance of the maximal weight \( \langle \cdot, \cdot \rangle \) and the semicontinuity of \( \lambda \), we get:

\[
\lambda_y(v) = \lambda_{g_\alpha^{-1}y}(g_\alpha v) \geq \liminf_{\alpha} \lambda_{g_\alpha^{-1}x}(g_\alpha v) \geq 0,
\]

concluding the proof. \( \square \)

7. **The integral of the gradient map**

Let \( U \) be a compact connected Lie group and denote by \( u \) its Lie algebra and by \( U^C \) its complexification. Let \((Z,\omega)\) be a Kähler manifold on which \( U^C \) acts holomorphically. Assume that \( U \) acts in a Hamiltonian fashion with momentum map \( \mu : Z \to u^* \). Consider a closed connected subgroup \( G \) of \( U^C \) compatible with respect to the Cartan decomposition of \( U^C \), i.e. \( G = K \exp(\mathfrak{p}) \), for \( K = U \cap G \) and \( \mathfrak{p} = \mathfrak{g} \cap i\mathfrak{u} \) (see [24, 25]). The inclusion \( i\mathfrak{p} \hookrightarrow \mathfrak{u} \) induces by restriction a \( K \)-equivariant map \( \mu_{i\mathfrak{p}} : Z \to (i\mathfrak{p})^* \). There is a \( \text{Ad}(U^C) \)-invariant and non-degenerate bilinear form \( B : u^C \times u^C \to \mathbb{R} \) which is positive definite on \( i\mathfrak{u} \), negative definite on \( \mathfrak{u} \) and such that \( B(u,iu) = 0 \) (see [5, p. 585]). Therefore \( B \) is \( \text{Ad}(U^C) \)-invariant, non-degenerate and its restriction to \( \mathfrak{g} \) satisfies the following conditions: \( B \) is \( \text{Ad}(G) \)-invariant, \( B(\mathfrak{t},\mathfrak{p}) = 0 \), \( B \) restricted to \( \mathfrak{t} \) is negative definite and \( B \) restricted to \( \mathfrak{p} \) is positive definite. Using \( \langle \cdot, \cdot \rangle \), we identify \( u \cong u^* \). For \( z \in Z \), let \( \mu_\mathfrak{p}(z) \in \mathfrak{p} \) denote \(-i\) times the component of \( \mu(z) \) in the direction of \( i\mathfrak{p} \). In other words we require that \( \langle \mu_\mathfrak{p}(z),\beta \rangle = -\langle \mu(z),i\beta \rangle \), for any \( \beta \in \mathfrak{p} \). Then, we view \( \mu_\mathfrak{p} \) as a map:

\[
\mu_\mathfrak{p} : Z \to \mathfrak{p},
\]

which is called the \( G \)-gradient map or restricted momentum map associated to \( \mu \). We also set:

\[
\mu_\mathfrak{p}^{-i\beta} := \langle \mu_\mathfrak{p}, \beta \rangle = \mu_\mathfrak{p}^{-i\beta}.
\]
By definition, it follows that \( \text{grad} \mu^\beta_k = \beta_Z \), where \( \beta_Z(x) = \frac{d}{dt} \bigg|_{t=0} \exp(t\beta)x \).

Throughout this section we fix a \( G \)-stable subset \( M \subset Z \) and we consider the gradient map \( \mu_p : M \rightarrow p \) restricted on \( M \). Further, we denote by \( \beta_M = \frac{d}{dt} \bigg|_{t=0} \exp(t\beta)x \). Observe that if \( M \) is a manifold, then \( \beta_M \) is the gradient of \( \mu^\beta_k \) restricted to \( M \) with respect to the induced Riemannian structure on \( M \).

As Mundet pointed out in [39], the existence of the Kempf-Ness function for an action of a complex reductive group on a Kähler manifold given in [37] also holds for the setting introduced in [23, 24, 26].

**Theorem 39.** There exists a Kempf-Ness function for \((M,G,K)\) satisfying the conditions \((P1) - (P5)\). Furthermore, if \( M \) is a \( G \)-stable compact submanifold of \( Z \), then \((P6)\) holds as well.

**Proof.** Fix \( x \in M \). Let \( \pi_p : g \rightarrow p \) be the linear projection induced by the decomposition \( g = \mathfrak{k} \oplus p \) and identify \( T_eG \) with \( g \) in the usual way. For \( g \in G \) and \( v \in T_gG \), one has \( dR_{g^{-1}}(v) \in g \). Thus, we can define a 1-form \( \sigma \) on \( G \) by setting:

\[
\sigma_g(v) := \langle \mu_p(gx), \pi_p(dR_{g^{-1}}(v)) \rangle.
\]

Observe that \( \sigma_g \in T_g G^* \) and \( \sigma \in \Lambda^1(G) \). When we need to stress the dependence on \( x \) we will write \( \sigma^x \). We claim that \( \sigma \) is closed. In order to prove it, fix \( g \in G, v, w \in T_gG \) and let \( \xi, \eta \in g \) be such that \( dR_g(\xi) = v \) and \( dR_g(\eta) = w \). Further, let also \( X, Y \in \mathfrak{X}(G) \) be the fundamental vector fields corresponding to \( \xi \) and \( \eta \) under the action of left multiplication. In other words \( X \) is the right-invariant vector field such that \( X(e) = v \), i.e. for \( h \in G \),

\[
X(h) := dR_h(v) = \frac{d}{dt} \bigg|_{t=0} \exp(tv)h.
\]

For a left action the map that sends a vector in \( g \) to its fundamental vector field is an anti-isomorphism of Lie algebras. Thus \([X,Y]\) is the fundamental vector field corresponding to \(-[\xi, \eta]\). Hence:

\[
[X,Y](g) := dR_g(-[\xi, \eta]),
\]

\[
\sigma([X,Y])(g) = \langle \mu_p(gx), \pi_p([\xi, \eta]) \rangle.
\]

We can assume by linearity that \( \xi, \eta \in \mathfrak{k} \cup p \).

It is immediate from the definition that \( \sigma(X) = \sigma(Y) = \sigma([X,Y]) \equiv 0 \) if \( \xi, \eta \in \mathfrak{k} \). Thus recalling that:

\[
(d\sigma)_g(v, w) = X(g)\sigma(Y) - Y(g)\sigma(X) - \sigma([X,Y])(g),
\]

for \( \xi, \eta \in \mathfrak{k} \) the claim is proven.

Assume now that \( \xi \in \mathfrak{k} \) and \( \eta \in p \). Then \( \sigma(X) \equiv 0 \) and for \( h \in G \),

\[
\sigma(Y)(h) = \langle \mu_p(hx), \eta \rangle = \mu^\eta_p(hx).
\]
By the $K$-equivariance of the gradient map we have:

\[
(X\sigma)(Y)(g) = \frac{d}{dt} \bigg|_{t=0} \sigma(Y)(\exp(t\xi)g) = \frac{d}{dt} \bigg|_{t=0} \mu_p^0(\exp(t\xi)gx)
\]

\[
= \frac{d}{dt} \bigg|_{t=0} \langle \text{Ad}(\exp(t\xi))(\mu_p(gx)), \eta \rangle = \langle [\xi, \mu_p(gx)], \eta \rangle.
\]

Thus:

\[
d\sigma(v, w) = \langle [\xi, \mu_p(gx)], \eta \rangle - \langle \mu_p(gx), \pi_p([\eta, \xi]) \rangle
\]

\[
= \langle [\xi, \mu_p(gx)], \eta \rangle - \langle \mu_p(gx), [\eta, \xi] \rangle
\]

\[
= \langle [\xi, \mu_p(gx)], \eta \rangle - \langle [\xi, \mu_p(gx)], \eta \rangle
\]

\[
= 0.
\]

Finally, we consider the last possibility, $\xi, \eta \in \mathfrak{p}$. In this case $[\xi, \eta] \in \mathfrak{k}$ and thus $\sigma([X, Y]) \equiv 0$. On the other hand:

\[
(X\sigma)(Y)(g) = \frac{d}{dt} \bigg|_{t=0} \sigma(Y)(\exp(t\xi)g) = (d\mu_p^0)(gx)(\xi_M) = \langle \eta_M, \xi_M \rangle,
\]

which is symmetric in $\xi$ and $\eta$, implying $d\sigma(v, w) = 0$ also in this case.

This shows that $\sigma$ is closed. Let $\gamma \in \Omega(G, e, e)$. Then there exists $\gamma' \in \Omega(K, e, e)$ such that $\gamma \sim i \circ \gamma'$, where $i : K \hookrightarrow G$, and thus:

\[
\int \gamma = \int \gamma'.
\]

Since $i^* \sigma = 0$, it follows that $\sigma$ is exact. Let $\Psi_x \in C^\infty(G)$ be the unique function such that $\Psi_x(e) = 0$ and $d\Psi_x = \sigma^x$. Since $\sigma^x|_{TK} \equiv 0$, then $\Psi_x(h) = 0$ for any $h \in K$. Moreover, for any $\eta \in \mathfrak{p}$, we have:

\[
(d\Psi_x)_e(\eta) = \mu_p^0(x).
\]

Thus, the function:

\[
\Psi : M \times G \to \mathbb{R} \quad \Psi(x, g) := \Psi_x(g),
\]

satisfies conditions $(P_1)$ and $(P_5)$. In order to prove $(P_3)$, compute:

\[
\frac{d}{dt} \Psi_x(\exp(t\eta)) = (\sigma^x)_{\exp(t\eta)} \left( \frac{d}{dt} \exp(t\eta) \right)
\]

\[
= (\sigma^x)_{\exp(t\eta)}(dR_{\exp(t\eta)}(\eta))
\]

\[
= \langle \mu_p(\exp(t\eta)x), \eta \rangle
\]

\[
= \mu_p^0(\exp(t\eta)x).
\]

Therefore,

\[
\frac{d^2}{dt^2} \Psi_x(\exp(t\eta)) = d\mu_p^0(\eta_M)(\exp(t\eta)x) = ||\eta_M||^2(\exp(t\eta)x),
\]

and thus $(P_3)$ follows.
In order to prove \((P_4)\), let \(g \in G\) and \(x \in M\). We claim that \(R_g^* \sigma^x = \sigma^{gx}\). Indeed if \(v \in T_h G\) and \(w = dR_{h^{-1}}(v)\), then:

\[
\sigma_h^{gx}(v) = \langle \mu(hgx), \pi_p(w) \rangle,
\]

\[
(R_g^* \sigma^x)_h(v) = (\sigma^x)_h(dR_g(v)) = \langle \mu(hgx), \pi_p(dR_h^{-1}dR_g(v)) \rangle = \langle \mu(hgx), \pi_p(w) \rangle.
\]

Thus the claim is proven. Therefore \(\Psi_{gx} - R_g^* \Psi_x = c\) is a constant. Evaluating at \(h = e\) we get:

\[c = 0 - \Psi_x(g)\]

and thus:

\[\Psi_{gx}(h) + \Psi_x(g) = \Psi_x(hg),\]

as desired. Property \((P2)\) follows by the cocycle condition together with the fact that for any \(x \in M\), \(\Psi_x(h) = 0\) for all \(h \in K\).

Finally, if \(M\) is a compact \(G\)-stable submanifold of \(Z\), then the norm square of the gradient map restricted to \(M\) is bounded. Hence \(\psi_x\) is Lipschitz since its differential is bounded and thus \((P6)\) holds.

As direct consequence of Corollary \([23]\) we get the following result.

**Theorem 40.** Let \(M \subset Z\) be a \(G\)-invariant subset of \(Z\). Then the set of stable points for the gradient map \(\mu_p : M \to p\) restricted to \(M\) is open. Moreover, if \(G = A = \exp(\mathfrak{a})\), where \(\mathfrak{a} \subset \mathfrak{p}\) is an abelian subalgebra, and \(\mu_\mathfrak{a} : M \to \mathfrak{a}\) is the gradient map of \(A\), then for any \(\beta \in \mathfrak{a}\), the set \(\{p \in M : Ap \cap \mu_\mathfrak{a}^{-1}(\beta) \neq \emptyset\}\) is open.

When \(M\) is a compact \(G\)-stable submanifold of \(Z\), Theorems \([33]\) and \([35]\) also hold for the gradient map \(\mu_p : M \to \mathfrak{p}\) restricted on \(M\). More precisely we have:

**Theorem 41.** Let \(M \subset Z\) be a compact \(G\)-invariant submanifold of \(Z\) and let \(\mu_p : M \to \mathfrak{p}\) be the gradient map restricted to \(M\). Then \(x \in M\) is semi-stable if and only if \(\lambda_x \geq 0\). Furthermore, a point \(x \in M\) is polystable if and only if \(\lambda_x \geq 0\) and \(Z(x) = \partial_\infty X'\) for some totally geodesic submanifold \(X' \subset X = G/K\).

8. Measures

Let \(M\) be a compact Hausdorff space. Denote by \(\mathcal{M}(M)\) the vector space of finite signed Borel measures on \(M\). Observe that they are automatically Radon \([13]\) Thm. 7.8, p. 217. Denote by \(C(M)\) the space of real continuous functions on \(M\) which is a Banach space with the sup–norm. By the Riesz Representation Theorem (see e.g. \([14]\) p.223) \(\mathcal{M}(M)\) is the topological dual of \(C(M)\). We endow \(\mathcal{M}(M)\) with the weak–* topology as dual of \(C(M)\) that it is usually called the weak topology on measures. We use the symbol \(\mu_\alpha \rightharpoonup \nu\) to denote the weak convergence of the net \(\{\nu_\alpha\}\) to the measure \(\nu\). Finally, we denote by \(\mathcal{P}(M) \subset \mathcal{M}(M)\) the set of Borel probability measures on \(M\). It is well-known that \(\mathcal{P}(M)\) is a compact convex subset of \(\mathcal{M}(M)\). Indeed the cone of positive measures is closed and \(\mathcal{P}(M)\) is the intersection of this cone with the closed
affine hyperplane \( \{ \nu \in \mathcal{M}(M) : \nu(M) = 1 \} \). Therefore \( \mathcal{P}(M) \) is closed and it is contained in the closed unit ball in \( \mathcal{M}(M) \), which is compact in the weak topology by the Banach-Alaoglu Theorem [12, p. 425]. Since \( C(M) \) is separable, the weak topology on \( \mathcal{P}(M) \) is metrizable (see [12, p. 426]).

If \( f : M \to N \) is a measurable map between measurable spaces and \( \nu \) is a measure on \( M \), the \textit{image measure} \( f_* \nu \) is the measure on \( Y \) such that \( f_* \nu(A) := \nu(f^{-1}(A)) \). Observe that it satisfies the \textit{change of variables formula}

\[
\int_{f(N)} u(y) d(f_*\nu)(y) = \int_M u(f(x)) d\nu(x).
\]

If \( G \) acts on \( M \), then we have an action on the probability measures on \( M \) as follows:

\[
G \times \mathcal{P}(M) \to \mathcal{P}(M), \quad (g, \nu) \mapsto g_* \nu.
\]

Let \( U \) be a compact connected Lie group and \( U^\mathbb{C} \) its complexification. As in section 7 we assume that \( G = K \exp(\mathfrak{p}) \) is a compatible subgroup of \( U^\mathbb{C} \) and \( M \) is a \( G \)-stable compact subset of a \( K \)ähler manifold \((Z, \omega)\). One can prove in a totally similar way as in the proof of [8] Lemma 5.5 p. 18 that the action \([\mathfrak{g}]\) is continuous with respect to the weak topology.

**Lemma 44.** Let \( X \) be a vector field on \( Z \) such that its flow \( \{ \varphi_t \} \) preserves \( M \). If \( \nu \in \mathcal{M}(M) \) and \( X \) vanishes \( \nu \)-almost everywhere, then \( \varphi_t \nu = \nu \) for any \( t \). Hence, if \( \nu \in \mathfrak{g} \) and \( \nu_M(x) = 0 \) for every \( x \) outside a set of \( \nu \)-measure zero, then \( \exp(\mathbb{R}v) \subset G \nu \).

**Proof.** Set \( N := \{ p \in M : X(p) \neq 0 \} \). Then \( \nu(N) = 0 \) and for any \( t \in \mathbb{R} \) and any \( x \notin N \), \( \varphi_t(x) = x \). In particular both \( N \) and \( M - N \) are \( \varphi_t \)-invariant. If \( A \subset M \) is measurable, then

\[
\varphi_{-t}(A) = \varphi_{-t}((A - N) \cup (N \cap A)) = (A - N) \cup \varphi_{-t}(N \cap A).
\]

Since \( \varphi_{-t}(N \cap A) \subset N \), \( \varphi_{t_*} \nu(A) = \nu(\varphi_{-t}(A)) = \nu(A - N) = \nu(A) \). \qed

**Proposition 45.** Let \( M, G, K \) and \( \mu_\mathfrak{p} \) be as in §17 and let \( \Psi^M \) be the Kempf-Ness function of \((M, G, K)\). The function:

\[
\Psi^\mathfrak{p} : \mathcal{P}(M) \times G \to \mathbb{R}, \quad \Psi^\mathfrak{p}(\nu, g) := \int_M \Psi^M(x, g) d\nu(x),
\]

is a Kempf-Ness function for \((\mathcal{P}(M), G, K)\) satisfying conditions (P1) – (P5). If in addition \( M \) is compact then \( \Psi \) also satisfies condition (P6). Moreover, if we denote by \( X = G/K \), then

\[
\psi^\mathfrak{p} : X \to \mathbb{R}, \quad \psi^\mathfrak{p}(gK) := \Psi^\mathfrak{p}(\nu, g^{-1}) = \int_M \psi^M_x(gK) d\nu(x),
\]

and if \( \nabla \) denotes the gradient map, then:

\[
\nabla : \mathcal{P}(M) \to \mathfrak{p}^*, \quad \nabla(\nu) := \int_M \mu_\mathfrak{p}(x). d\nu(x).
\]

Finally, if \( \exp(\mathbb{R}\beta) \subset G_\nu \), for some \( \beta \in \mathfrak{p} \), then \( \nabla(\nu) \in \mathfrak{p}^\beta \).

For a sake of completeness we sketch the proof which is totally similar to that of Proposition 5.12 in [8].
Proof. Since $\Psi^M$ is left-invariant with respect to $K$, the same holds for $\Psi^\mathfrak{p}$.

Fix $\nu \in \mathcal{P}(M)$. By differentiation under the integral sign $\Psi^\mathfrak{p}(\nu, \cdot)$ is a smooth function on $G$ and for $v \in \mathfrak{p}$ we have:

$$\frac{d^2}{dt^2} \Psi^\mathfrak{p}(\nu, \exp(tv)) = \int_M \left( \frac{d^2}{dt^2} \Psi^M(x, \exp(tv)) \right) dv(x) \geq 0,$$

since the integrand is non-negative by (P3). If $\left. \frac{d^2}{dt^2} \Psi^\mathfrak{p}(\nu, \exp(tv)) \right|_{t=0} = 0$, then:

$$\frac{d^2}{dt^2} \left. \Psi^M(\nu, \exp(tv)) = 0 \quad \nu\text{-almost everywhere.} \right|_{t=0}$$

Again by (P3) this implies that $v_M = 0 \ \nu$-almost everywhere. By Lemma 14 it follows that $\exp(\mathbb{R}v) \subset G_v$. We have proven that $\Psi^\mathfrak{p}$ satisfies (P1) – (P3). The cocycle condition for $\Psi^\mathfrak{p}$ follows immediately from the cocycle condition for $\Psi^M$. Fix $\nu \in \mathcal{P}(M)$. It is immediate to verify that the function $\psi^\mathfrak{p}$ associated to $\Psi^\mathfrak{p}$ as in (8) is the one given by (17). Therefore it is clearly continuous on $\mathcal{P}(M)$. Finally, it is easy to check that $\Psi^\mathfrak{p}_\nu$ is Lipschitz whenever $M$ is a compact manifold.

Let $\beta \in \mathfrak{p}$. Since $X^\beta = \{ y \in M ; \beta_M(x) = 0 \}$, is the set of fixed points $\{ y \in M : \exp(t\beta)y = y, \text{ for all } t \in \mathbb{R} \}$, then $X^\beta$ is $G^\beta$-stable and $\mu_{\mathfrak{p}}(X^\beta) \subset \mathfrak{p}^\beta$ (see [24]). If $\exp(\mathbb{R}\beta) \in G_v$, using the same argument of the proof of Proposition 52, then $\nu$ is supported on $X^\beta$ and so $\mathfrak{z}(\nu) \in \mathfrak{p}^\beta$. □

From now on we assume that $M$ is a compact $G$-stable submanifold of $Z$. We shall compute the maximal weight using the geometry of the gradient map. We begin recalling the following slice theorem proved in [23, 24].

**Theorem 49 (Linearization Theorem).** Let $M$, $G$, $K$ and $\mu_\mathfrak{p}$ be as in §7. If $x$ is a fixed point of $G$, then there exist an open subset $S \subset T_xM$, stable under the isotropy representation of $G$, an open $G$-stable neighborhood $\Omega$ of $x$ in $M$ and a $G$-equivariant diffeomorphism $h : S \to \Omega$. One can further require that $h(0) = x$ and $dh_0 = \text{id}_{T_xM}$.

Fix $v \in \mathfrak{p}$. The gradient flow of a function $f \in C^\infty(M)$ is usually defined as the flow of the vector field $-\text{grad} f$. Let $\{ \varphi_t \}$ denote the gradient flow of $\mu^v$. Since $\text{grad} \mu^v = \beta_M$, we have $\varphi_t(x) = \exp(tv)x$. Then the function $\mu_\mathfrak{p}^v$ is a Morse-Bott function [23, 24, 25]. If we denote by $c_1 > \cdots > c_r$ the critical values of $\mu^v$, then the corresponding level sets of $\mu_\mathfrak{p}^v$, $C_i := (\mu^v)^{-1}(c_i)$ are submanifolds which are the components of $\text{Crit}(\mu^v)$. By Theorem 49 it follows that for any $x \in M$ the limit:

$$\alpha(x) := \lim_{t \to -\infty} \varphi_t(x) = \lim_{t \to +\infty} \exp(tv) \cdot x,$$

exists. Let us denote by $W_i$ the unstable manifold of the critical component $C_i$ for the gradient flow of $\mu^v$:

$$W_i := \{ x \in M : \alpha(x) \in C_i \}.$$
Then:

\[ M = \bigsqcup_{i=1}^{r} W_i, \]

and for any \( i \) the map:

\[ \alpha|_{W_i} : W_i \to C_i, \]

is a smooth fibration with fibres diffeomorphic to \( \mathbb{R}^{l_i} \) where \( l_i \) is the index (of negativity) of the critical submanifold \( C_i \).

**Proposition 52.** Let \( \nu \) be a polystable measure which is not stable. Hence there exist an abelian subalgebra \( a \subset g_\nu \) such that \( \nu \) is supported on \( M^a = \{ x \in M : \xi_M(x) = 0 \text{ for any } \xi \in a \} \).

**Proof.** By Proposition 31, Lemma 32 and Theorem 33, \( g_\nu = \text{Ad}(g)(\mathfrak{k}' \oplus \mathfrak{q}) \), i.e., it is conjugate to a compatible subalgebra of \( g \) and \( \partial_\infty G_\nu/K_\nu = Z(\nu) = g(e(S(\mathfrak{q}))) \).

Let \( a' \subset \mathfrak{q} \) be a maximal abelian subalgebra of \( \mathfrak{q} \). Then \( a = \text{Ad}(g)(a') \) is an abelian subalgebra of \( g_\nu \) and \( S(a) \subset Z(\nu) \). Let \( u \in a \). Then \( \exp(tu) \in G_\nu \) and thus:

\[ \lim_{n \to -\infty} \exp(nu) \nu = \nu. \]

Let \( A \subset M \) be a measurable subset. Then \( \nu(A) = \lim_{n \to -\infty} \nu(\exp(nu)(A)) = \nu(\alpha(A)) \), where \( \alpha \) is the gradient flow of \( \mu^u_p \). Hence \( \nu \) is supported on the critical submanifolds of \( \mu^u_p \) for any \( u \in a \). Hence \( \nu \) is supported on \( M^a \). \( \square \)

Now, we explicitly compute the maximal weights.

**Theorem 53.** With the notation above we have

\[ \lambda_\nu(e(-v)) = \sum_{i=1}^{r} c_i \nu(W_i). \]

We give a sketch of the proof, which follows essentially that of [8, Th. 5.23].

**Proof.** By definition of \( \lambda_\nu \) and by differentiating under the integral sign we get

\[ \lambda_\nu(e(-v)) = \lim_{t \to +\infty} \frac{d}{dt} \int_M \Psi^M(x, \exp(tv)) d\nu(x) \]

\[ = \lim_{t \to +\infty} \int_M \left( \frac{d}{dt} \Psi^M(x, \exp(tv)) \right) d\nu(x). \]

Applying the dominated convergence theorem, since \( \frac{d}{dt} \bigg|_{t=t_0} \Psi^M(x, \exp(tv)) = \mu^u_p(\exp(tv) \cdot x) \) and \( \mu^u_p \) is bounded, we get

\[ \lambda_\nu(e(-v)) = \lim_{t \to +\infty} \int_M \mu^u_p(\exp(tv) \cdot x) d\nu(x) \]

\[ = \int_M \mu^u(\alpha(x)) d\nu(x) = \sum_{i=1}^{r} \int_{W_i} \mu^u_p(\alpha(x)) d\nu(x). \]
Since for \( x \in W_i, \alpha(x) \in C_i \) and so \( \mu_p^{v}(\alpha(x)) = c_i \), we finally obtain:

\[
\lambda_{\nu}(e(-v)) = \sum_{i=1}^{r} c_i \nu(W_i).
\]

\( \square \)

Let \( E(\mu_p) \) denote the convex hull of \( \mu_p(M) \subset p \), i.e. a \( K \)-invariant convex body in \( p \). Let \( a \subset p \) be a abelian subalgebra and let \( \pi : p \rightarrow a \) be the orthogonal projection onto \( a \). Then \( \mu_a = \pi \circ \mu_p \) is the gradient map associated to \( A = \exp(a) \). Denote by \( P = \mu_a(M) \). It is well-known that \( P \) is a finite union of polytopes \([26]\). In the sequel we always assume that \( P \) is a polytope, hypothesis which holds e.g. if \( G = U^\mathbb{C} \) and \( M \) is a complex connected submanifold by the Atiyah-Guillemin-Sternberg convexity theorem \([1, 16]\) or when \( M \) is an irreducible semi-algebraic subset of a Hodge manifold \( Z \) \([6, 26, 33]\). We point out that the convex bodies \( E(\mu_p) \) and \( P \) are strongly related \([7]\). Observe that under such hypothesis for any \( v \in p \), a local maxima of \( \mu_p^{v} \) is a global maxima. Then the Morse-Bott decomposition of \( M \) with respect to \( \mu_p^{v} \), i.e.,

\[
M = \bigsqcup_{i=0}^{r} W_i,
\]

has a unique open and dense unstable manifold \( W^u_r \) and the others unstable manifolds are proper submanifolds. Therefore, if \( \nu \) is a smooth measure of \( M \) then \( W^u_r \) has full measure and so \( \lambda_{\nu}(e(-v)) = c_r = \max_{x \in M} \mu_p^{v} \). Summing up we have proved the following result.

**Corollary 54.** If \( \nu \) is a smooth measure on \( M \), then for any \( v \in p \):

\[
\lambda_{\nu}(e(-v)) = \max_{x \in M} \mu_p^{v}.
\]

Since \( \nu \) is a probability measures, it follows that \( \overline{\nu} \in E(\mu_p) \). Indeed, \( \overline{\nu} \) is the barycenter of the gradient map \( \mu_p \) with respect to \( \nu \) and so it lies in \( E(\mu_p) \). If \( 0 \notin E(\mu_p) \), then there exists \( v \in E(\mu_p) \) realizing the minimum distance of \( E(\mu_p) \) to the origin. Moreover \( v \) is a \( K \) fixed point due to the fact that \( E(\mu_p) \) is \( K \)-invariant. Hence up to shifting the gradient map we may assume that \( 0 \in E(\mu_p) \). Under this assumption we get the following result.

**Proposition 55.** If \( 0 \in E(\mu_p) \) then any smooth measure on \( M \) is semi-stable.

**Proof.** Let \( v \in p \). By the above corollary, we have \( \lambda_{\nu}(e(-v)) = \max_{x \in M} \mu_p^{v} \). Since \( 0 \in E(\mu_p) \), it follows that \( \lambda_{\nu}(e(-v)) = \max_{x \in M} \mu_p^{v} \geq 0 \). By Theorem 35 \( \nu \) is semi-stable. \( \square \)

**Corollary 56.** If \( 0 \in E(\mu_p) \), then the set \( \mathcal{P}_{ss}(M) := \{ \nu \in \mathcal{P}(M) : \nu \text{ is semi-stable} \} \) is dense in \( \mathcal{P}(M) \). Moreover, if \( 0 \) lies in the interior of \( E(\mu_p) \) then the set \( \mathcal{P}_{s}(M) := \{ \nu \in \mathcal{P}(M) : \nu \text{ is stable} \} \) is open and dense.

**Proof.** By the above Proposition any smooth measure is semi-stable. Since smooth measures are dense, then the set of semi-stable measures is dense. If \( 0 \) belongs to the interior of the \( E(\mu_p) \), then for any \( v \in p \) the function \( \mu_p^{v} \) change sign and so it has a strictly positive maxima. By Corollary 54 \( \lambda_{\nu}(e(-v)) > 0 \) and by Theorem 23 we get that it is stable. Since by Corollary 29 the set of the stable points is also open, it means \( \mathcal{P}_{s}(M) \) is open and dense. \( \square \)
9. Measures on real projective spaces

In the recent paper [8] the authors completely describe stable, semi-stable and polystable measures on complex projective spaces (see also [11, 35]). Here we consider the real projective space:

\[ \mathbb{P}^n(\mathbb{R}) = \frac{\mathbb{R}^{n+1} - \{0\}}{\sim} = \frac{\mathbb{S}^n}{\{\pm \text{Id}_{n+1}\}}, \]

where we denote by \( \text{Id}_{n+1} \) the identity matrix of order \( n+1 \). Consider on \( \mathbb{P}^n(\mathbb{R}) \) the action of \( \text{SL}(n+1, \mathbb{R}) \) and recall that its Lie algebra \( \mathfrak{sl}(n+1) \) decomposes as \( \mathfrak{sl}(n+1) = \mathfrak{t} \oplus \mathfrak{p} = \mathfrak{so}(n+1) \oplus \text{sym}_0(n+1) \). A gradient moment map for this action is given by:

\[ \mu_p : \mathbb{P}^n(\mathbb{R}) \to \mathfrak{p}, \quad \mu_p([x]) = \frac{1}{2} \left[ \frac{x x^T}{|x|^2} - \frac{1}{n+1} \text{Id}_{n+1} \right]. \]

Observe that \( \text{sym}_0(n+1) \) admits the maximal abelian subalgebra \( \mathfrak{a} \) of traceless diagonal matrices, which we identify with \( \mathbb{R}^n \subset \mathbb{R}^{n+1} \). Given an element \( \xi \in \text{sym}_0(n+1) \), let \( \lambda_1 > \cdots > \lambda_k \) be its eigenvalues and denote by \( V_1, \ldots, V_k \) the corresponding eigenspaces. In view of the orthogonal decompositions \( \mathbb{R}^{n+1} = V_1 \oplus \cdots \oplus V_k \) we can write \( x \in \mathbb{R}^{n+1} \) as \( x = x_1 + \cdots + x_k \) with \( x_j \in V_j \), \( j = 1, \ldots, k \). With this notation we have:

\[ \mu^\xi_p([x]) = \frac{1}{2} \frac{\lambda_1 |x_1|^2 + \cdots + \lambda_k |x_k|^2}{|x_1|^2 + \cdots + |x_k|^2}, \]

where \( \langle \cdot, \cdot \rangle \) is the dual pairing. Consider the projection \( \pi : \mathbb{R}^{n+1} - \{0\} \to \mathbb{P}^n(\mathbb{R}) \). Since \( (d\pi)_x (\xi_{\mathbb{R}^{n+1} - \{0\}}(x)) = \xi_{\mathbb{P}^n(\mathbb{R})} \) and \( \xi_{\mathbb{R}^{n+1} - \{0\}}(x) = \lambda_1 x_1 + \cdots + \lambda_k x_k \), one has \( \xi_{\mathbb{P}^n(\mathbb{R})} \equiv 0 \) iff \( \xi_{\mathbb{R}^{n+1} - \{0\}}(x) \) is parallel to \( x \), i.e. iff \( x = x_j \) for some \( j = 1, \ldots, k \). Thus, critical points of \( \mu^\xi_p \) are given by \( \text{Crit}(\mu^\xi_p) = \mathbb{P}(V_1) \cup \cdots \cup \mathbb{P}(V_k) \) and critical values are \( c_j = \frac{1}{2} \lambda_j, j = 1, \ldots, k \).

In order to describe:

\[ W^\xi_j = \{ [x] \in \mathbb{P}^n(\mathbb{R}) : \alpha([x]) \in C_j \}, \]

for \( j = 1, \ldots, n+1 \), where by definition:

\[ \alpha([x]) = \lim_{t \to +\infty} \exp(t\xi)x, \]

observe that:

\[ \exp(t\xi)x = [\exp(t\lambda_1)x_1 + \cdots + \exp(t\lambda_k)x_k], \]

which implies:

\[ \alpha([x]) = \lim_{t \to +\infty} [\exp(t\lambda_1)x_1 + \cdots + \exp(t\lambda_k)x_k] = \begin{cases} [x_1] & \text{if } x_1 \neq 0; \\ [x_2] & \text{if } x_1 = 0, x_2 \neq 0; \\ \vdots \\ [x_k] & \text{otherwise.} \end{cases} \]

Thus, since \( [x] \in W^\xi_j \) iff \( \alpha([x]) \in \mathbb{P}(V_j) \) we have:

\[ W^\xi_1 = \mathbb{P}^n(\mathbb{R}) - \mathbb{P}(V_2 \oplus \cdots \oplus V_k), \]

\[ W^\xi_2 = \mathbb{P}(V_2 \oplus \cdots \oplus V_k) - \mathbb{P}(V_3 \oplus \cdots \oplus V_k), \]
\[ W_{k-1}^\xi = P(V_{k-1} \oplus V_k) - P(V_k). \]
\[ W_k^\xi = P(V_k). \]

By Theorem 53 it follows:
\[
\lambda_\nu(e(-\xi)) = \frac{1}{2} \left( \sum_{j=1}^{r} \lambda_j \nu(W_j^\xi) \right) = \frac{1}{2} (\lambda_1 - (\lambda_1 - \lambda_2)\nu(P(V_2 \oplus \cdots \oplus V_k)) - \cdots - (\lambda_{k-1} - \lambda_k)\nu(P(V_k))).
\]

In the following two examples we develop in details the cases \( n = 1 \) and \( n = 2 \).

**Example 58.** Let \( n = 1 \). We have \( \xi = (\lambda_1, -\lambda_1) \) and \( R^2 = V_1 \oplus V_2 \). Denote \( p_i = P(V_i) \) for \( i = 1, 2 \). Then, \( \text{Crit}(\mu_\xi) = \{p_1, p_2\} \). If we denote \( x = x_1 + x_2 \) as before, we have:
\[
\alpha(X) = \lim_{t \to +\infty} \left[ \exp(t\lambda_1)x_1 + \exp(t\lambda_2)x_2 \right] = \begin{cases} p_1 & \text{if } x_1 \neq 0; \\ p_2 & \text{if } x_1 = 0, \end{cases}
\]
which implies:
\[ W_1^\xi = P^1(R) - p_2, \quad W_2^\xi = p_2. \]
It follows that:
\[ \lambda_\nu(e(-\xi)) = \frac{\lambda_1}{2} (1 - 2\nu(p_2)). \]
Thus \( \nu \) is stable iff for any \( p \in P^1(R) \):
\[ \nu(p) < \frac{1}{2}, \]
semistable iff for any \( p \in P^1(R) \):
\[ \nu(p) \leq \frac{1}{2}, \]
polystable but not stable iff \( \nu \) is only supported by two points, i.e.:
\[ \nu = \frac{1}{2} \delta_1 + \frac{1}{2} \delta_2. \]
Indeed, if \( \nu \) is polystable, by Corollary 34, there exists \( \xi \in \mathfrak{p} \) such that \( \exp(t\xi) \in \mathrm{SL}(2, \mathbb{R})_\nu \), \( \nu \) is supported by two points \( p_1 \) and \( p_2 \) and by:
\[ 0 = \lambda_\nu(e(-\xi)) = \frac{\lambda_1}{2} (1 - 2\nu(p_2)) \]
it follows \( \nu = \frac{1}{2} \delta_{p_1} + \frac{1}{2} \delta_{p_2} \). Vice-versa, if \( \nu = \frac{1}{2} \delta_{p_1} + \frac{1}{2} \delta_{p_2} \) with \( p_1 \neq p_2 \), then there exists \( g \in \mathrm{SL}(2, \mathbb{R}) \) such that\( gp_1 = [1 : 0] \) and \( gp_2 = [0 : 1] \). It is easy to check that
\[ \mathfrak{f}(g\nu) = \frac{1}{2}(\mu_\mathfrak{p}([1 : 0]) - \mu_\mathfrak{p}([0 : 1])) = 0, \]
proving \( \nu \) is polystable.

**Example 59.** Let \( n = 2 \). We have three cases:
(a) \( \xi = (\lambda_1, \lambda_2, \lambda_3), \) with \( \lambda_3 = -\lambda_1 - \lambda_2, \) \( R^3 = V_1 \oplus V_2 \oplus V_3, \) \( \dim(V_j) = 1; \)
(b) $\xi = (\lambda_1, -\frac{1}{2}\lambda_1, -\frac{1}{2}\lambda_1)$ and $\mathbb{R}^3 = V_1 \oplus V_2$, where $\text{dim}(V_1) = 1$, $\text{dim}(V_2) = 2$;
(c) $\xi = (\lambda_1, \lambda_1, -2\lambda_1)$ and $\mathbb{R}^3 = V_1 \oplus V_2$, where $\text{dim}(V_1) = 2$, $\text{dim}(V_2) = 1$.

Let us deal first with the case (a). Denote $p_i = \mathbb{P}(V_i) \subset \mathbb{P}^2(\mathbb{R})$ for $i = 1, 2, 3$ and let $\xi = (\lambda_1, \lambda_2, \lambda_3)$. Then $\text{Crit}(\mu^\xi_p) = \{p_1, p_2, p_3\}$ and:

$$\alpha(x) = \lim_{t \to +\infty} \left[\exp(t\lambda_1)x_1 + \exp(t\lambda_2)x_2 + \exp(t\lambda_3)x_3\right] = \begin{cases} p_1 & \text{if } x_1 \neq 0; \\ p_2 & \text{if } x_1 = 0, y_2 \neq 0; \\ p_3 & \text{if } [x] = p_3, \end{cases}$$

and

$$W^\xi_1 = \mathbb{P}^2(\mathbb{R}) - \mathbb{P}(V_2 \oplus V_3), \quad W^\xi_2 = \mathbb{P}(V_2 \oplus V_3) - p_3, \quad W^\xi_3 = p_3.$$  

It follows that:

$$\lambda_\nu(e(-\xi)) = \frac{\lambda_1}{2} - \frac{\lambda_1 - \lambda_2}{2} \nu(\mathbb{P}(V_2 \oplus V_3)) - \frac{2\lambda_2 + \lambda_1}{2} \nu(p_3)$$

$$= \frac{\lambda_1}{2} \left(1 - \left(1 - \frac{\lambda_2}{\lambda_1}\right) \nu(\mathbb{P}(V_2 \oplus V_3)) - \left(2\frac{\lambda_2}{\lambda_1} + 1\right) \nu(p_3)\right).$$

Observe that from $\lambda_1 > \lambda_2 > -\lambda_1 - \lambda_2$ we get $-1/2 < \lambda_2/\lambda_1 < 1$.

For the case (b), namely for $\xi = (\lambda_1, -\frac{1}{2}\lambda_1, -\frac{1}{2}\lambda_1)$, we have $\text{Crit}(\mu^\xi) = \{p_1\} \cup \mathbb{P}(V_2)$,

$$\alpha(x) = \lim_{t \to +\infty} \left[\exp(t\lambda_1)x_1 + \exp(t\lambda_2)x_2\right] = \begin{cases} p_1 & \text{if } x_1 \neq 0; \\ [0 : y] & \text{if } x_1 = 0, \end{cases}$$

and

$$W^\xi_1 = \mathbb{P}^2(\mathbb{R}) - \mathbb{P}(V_2) = p_1, \quad W^\xi_2 = \mathbb{P}(V_2) = \mathbb{P}^2(\mathbb{R}) - \{p_1\}.$$  

It follows that:

$$\lambda_\nu(e(-\xi)) = \lambda_1 \left(\frac{1}{4} - \frac{3}{4} \nu(p_1)\right).$$

Finally, when $\xi = (\lambda_1, \lambda_1, -2\lambda_1)$, $\text{Crit}(\mu^\xi) = \mathbb{P}(V_1) \cup \{p_3\}$,

$$\alpha(x) = \lim_{t \to +\infty} \left[\exp(t\lambda_1)x_1 + \exp(t\lambda_2)x_2\right] = \begin{cases} [x] & \text{if } x_1 \neq 0; \\ p_3 & \text{if } x_1 = 0, \end{cases}$$

and

$$W^\xi_1 = \mathbb{P}^2(\mathbb{R}) - \{p_3\}, \quad W^\xi_2 = \mathbb{P}(V_2) = \{p_3\}.$$  

It follows that:

$$\lambda_\nu(e(-\xi)) = \frac{\lambda_1}{2} \left(1 - 3 \nu(p_3)\right).$$

Denote by $L_i \subset \mathbb{R}^3$ a linear subspace of $\mathbb{R}^3$ of dimension 2 and let $p \in \mathbb{P}^2(\mathbb{R})$. Then, $\nu$ is stable iff for any choice of $L_i$ and $p$:

$$\nu(\mathbb{P}(L_i)) < \frac{2}{3}, \quad \nu(p) < \frac{1}{3},$$

$\nu$ is semistable iff for any choice of $L_i$ and $p$:

$$\nu(\mathbb{P}(L_i)) \leq \frac{2}{3}, \quad \nu(p) \leq \frac{1}{3},$$
and \( \nu \) is polystable iff either it is stable or it is one of the following:

\[
\nu := \frac{2}{3} \delta_{\mathbb{P}(L)} + \frac{1}{3} \delta_p, \quad \nu := \frac{1}{3} \delta_1 + \frac{1}{3} \delta_2 + \frac{1}{3} \delta_3,
\]

i.e. it is supported by some \( \mathbb{P}(L) \) and by a point \( p \) or by three points (see the proof of Prop. \[00\] below for details).

We conclude with the following proposition which states necessary and sufficient conditions for stability and polystability in general dimension.

**Proposition 60.** The measure \( \nu \) is stable iff for any choice of a linear subspace \( L_i \subset \mathbb{R}^{n+1} \):

\[
\nu(\mathbb{P}(L)) < \frac{\dim(L_i)}{n + 1},
\]

\( \nu \) is semistable iff:

\[
\nu(\mathbb{P}(L)) \leq \frac{\dim(L_i)}{n + 1}.
\]

The measure \( \nu \) is polystable iff there exists a splitting \( \mathbb{R}^{n+1} = L_1 \oplus \cdots \oplus L_r \) such that \( \nu \) is supported on \( \mathbb{P}(L_1) \cup \cdots \cup \mathbb{P}(L_r) \). Moreover

\[
\nu := \sum_j \frac{\dim(L_j)}{n + 1} \delta_{\mathbb{P}(L_j)},
\]

where \( \delta_{\mathbb{P}(L_j)} \) is a stable measure of \( \mathbb{P}(L_j) \) with respect to \( \text{SL}(L_j) \).

**Proof.** As before, let \( \xi \in \mathfrak{a}, \lambda_1 > \cdots > \lambda_k \) be its eigenvalues and \( V_1, \ldots, V_k \) be the corresponding eigenspaces, with \( \sum_{j=1}^k \dim(V_j) \lambda_j = 0 \). From (57) we have \( \lambda_\nu(e(-\xi)) > 0 \) iff:

\[
(61) \quad \lambda_1 - (\lambda_1 - \lambda_2) \nu(\mathbb{P}(V_2 \oplus \cdots \oplus V_k)) - \cdots - (\lambda_{k-1} - \lambda_k) \nu(\mathbb{P}(V_k)) > 0.
\]

Assume that \( \nu(\mathbb{P}(L)) < \frac{\dim(L_i)}{n + 1} \) for any linear subspace \( L_i \subset \mathbb{R}^{n+1} \). Then, since \( \lambda_j - \lambda_{j+1} > 0 \):

\[
\lambda_1 - (\lambda_1 - \lambda_2) \nu(\mathbb{P}(V_2 \oplus \cdots \oplus V_k)) - \cdots - (\lambda_{k-1} - \lambda_k) \nu(\mathbb{P}(V_k)) >
\]

\[
> \lambda_1 - (\lambda_1 - \lambda_2) \frac{\dim(V_2) + \cdots + \dim(V_k)}{n + 1} - \cdots - (\lambda_{k-1} - \lambda_k) \frac{\dim(V_k)}{n + 1} = 0,
\]

where the last equality follows by applying \( \sum_{j=1}^k \dim(V_j) \lambda_j = 0 \) several times. Vice versa, let \( L_i \) be a linear subspace of \( \mathbb{R}^{n+1} \) of dimension \( 0 < r < n + 1 \) such that \( \nu(\mathbb{P}(L_i)) \geq \frac{\dim(L_i)}{n + 1} \). Then, \( \mathbb{R}^{n+1} = L_i \oplus L_i^\perp \), where we denote by \( L_i^\perp \) the orthogonal complement of \( L_i \), and we can choose \( \xi \) is such a way that \( \xi = (\lambda_1, \lambda_2), r \lambda_1 + (n + 1 - r) \lambda_2 = 0 \), with corresponding eigenspaces \( L_i \) and \( L_i^\perp \). We can assume without loss of generality that \( \lambda_1 > 0 \). Conclusion follows since by (57) we have:

\[
\lambda_\nu(e(-\xi)) = \lambda_1 - (\lambda_1 - \lambda_2) \nu(\mathbb{P}(L_i^\perp)) \leq \lambda_1 - \lambda_1 \frac{n + 1 - r}{n + 1} - \lambda_1 \frac{r}{n + 1} = 0,
\]

where we use that \( r \lambda_1 + (n + 1 - r) \lambda_2 = 0 \).

In order to prove the polystability part, assume that \( \nu \) is polystable. Then there exists \( g \in \text{SL}(n + 1, \mathbb{R}) \) such that \( \mathfrak{F}(g \nu) = 0 \). Set \( \nu' = g \nu \). By Lemma [32] and Proposition [52] there
exists an abelian subalgebra $\mathfrak{a} \subset \text{sym}_0(n + 1)$ such that $\nu'$ is supported on $\mathbb{P}^n(\mathbb{R})^{\mathfrak{a}}$. We can diagonalize simultaneously any element of $\mathfrak{a}$. Hence there exists an orthogonal splitting:

$$\mathbb{R}^{n+1} = V_1 \oplus \cdots \oplus V_r,$$

such that for any $\xi \in \mathfrak{a}$, we have $\xi|_{V_i} = \lambda_j(\xi)\text{Id}_{V_j}$. Therefore $\mathbb{P}^n(\mathbb{R})^{\mathfrak{a}} = \mathbb{P}(V_1) \cup \cdots \cup \mathbb{P}(V_r)$ and so $\nu'$ is supported on $\mathbb{P}(V_1) \cup \cdots \cup \mathbb{P}(V_r)$. This means that $\nu' = \sum_{j=1}^r \lambda_j \delta_{\mathbb{P}(V_j)}$, where $\delta_{\mathbb{P}(V_j)} \in \mathcal{P}(\mathbb{P}(V_j))$, $\lambda_j \geq 0$ for $j = 1, \ldots, r$ and $\sum_{j=1}^r \lambda_j = 1$. Since $\text{SL}(n+1, \mathbb{R})^{\mathfrak{a}} = \text{SL}(V_1 \oplus \cdots \oplus V_r)$ its semisimple part is given by $\text{SL}(V_1) \times \cdots \times \text{SL}(V_r)$. By Corollary $\exists! \nu'$ is $\text{SL}(V_1) \times \cdots \times \text{SL}(V_r)$ stable and so its stabilizer:

$$(\text{SL}(V_1) \times \cdots \times \text{SL}(V_r))\nu' = \text{SL}(V_1)\delta_{\mathbb{P}(V_1)} \times \cdots \times \text{SL}(V_r)\delta_{\mathbb{P}(V_r)}$$

is compact. In particular $\text{SL}(V_j)\delta_{\mathbb{P}(V_j)}$ is compact. If we decompose $x = x_1 + \cdots + x_r$ by means of the above splitting, we have:

$$0 = \mathfrak{z}(\nu') = \int_{\mathbb{P}^n(\mathbb{R})} \mu_p(x) d\nu'(x) = \int_{\mathbb{P}^n(\mathbb{R})} \frac{xx^T}{||x||^2} d\nu'(x) - \frac{1}{n+1} \text{Id}_{n+1}$$

$$= \sum_{j=1}^r \lambda_j \int_{\mathbb{P}(V_j)} \left( \frac{x_jx_j^T}{||x||^2} - \frac{1}{\text{dim} V_j} \text{Id}_{V_j} \right) d\delta_{\mathbb{P}(V_j)}(x_j) + \sum_{j=1}^r \lambda_j \frac{1}{\text{dim} V_j} - \frac{1}{n+1} \text{Id}_{n+1}$$

$$= \sum_{j=1}^r \lambda_j \mathfrak{z}^j(\delta_{\mathbb{P}(V_j)}) + \sum_{j=1}^r \left( \frac{\lambda_j}{\text{dim} V_j} - \frac{1}{n+1} \right) \text{Id}_{V_j}.$$
respect to $\text{SL}(L_i)$, then $g_i \delta_{P(V_j)}$ is stable with respect to $\text{SL}(V_j)$. Hence there exists $g_j \in \text{SL}(V_j)$ such that $\mathfrak{h}^j(g_j \delta_{P(V_j)}) = 0$. Let $h = g_1 \times \cdots \times g_r \in \text{SL}(V_1) \times \cdots \times \text{SL}(V_r) \subset \text{SL}(n + 1, \mathbb{R})$. Then

$$\mathfrak{h}(hg_\nu) = \sum_{j=1}^r \frac{\dim V_j}{n+1} \mathfrak{h}^j(g_j \delta_{P(V_j)}) = 0,$$

concluding the proof. □

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(Leonardo Biliotti) Dipartimento di Matematica e Informatica, Università di Parma (Italy)
E-mail address: leonardo.biliotti@unipr.it

(Michela Zedda) Dipartimento di Matematica e Fisica “Ennio De Giorgi”, Università del Salento
(Italy)
E-mail address: michela.zedda@gmail.com