Equivalence of Dynamical Systems

C*-Crossed products

Generalized Kakutani and Morita Equivalence

C*-algebras and Kakutani Equivalence of minimal Cantor systems

A Characterization for minimal \mathbb{Z}^d actions on the Cantor set

Frédéric Latrémolière, PhD Nicholas Ormes, PhD

University of Denver

October 16^{th} , 2011

Equivalence of Dynamical Systems

C*-Crossed products

Generalized Kakutani and Morita

Object of the talk

This talk presents a new form of equivalence between minimal free Cantor systems which has a natural dynamical and a natural C*-algebraic picture.

Latrémolière PhD

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Generalized Kakutani and Morita Equivalence

Object of the talk

This talk presents a new form of equivalence between minimal free Cantor systems which has a natural dynamical and a natural C*-algebraic picture.

This talk is based upon:

Paper

C*-algebraic characterization of bounded orbit injection equivalence for minimal free Cantor systems
Frédéric Latrémolière, Nic Ormes, **2011**, Rocky Mountain Journal of Mathematics (Accepted in 2009), ArXiv: 0903.1881.

Equivalence of Dynamical Systems

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Generalized Kakutani and Morita Equivalence

Classifying dynamics

Problem

When are two actions of \mathbb{Z}^d on two compact spaces equivalent?

Generalized Kakutani and Morita Equivalence

Classifying dynamics

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Maybe the most natural equivalence is *conjugacy*. Two actions (X,ϕ) and (Y,ψ) of \mathbb{Z}^d are conjugate when there exists a homeomorphism $h:X\to Y$ such that:

$$\forall z \in \mathbb{Z}^d \ \psi^z \circ h = h \circ \phi^z.$$

Generalized Kakutani and Morita Equivalence

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However, there is no good general invariant known, and it is usually a delicate problem.

As the problem of classification up to conjugacy is complicated, one may try to define weaker equivalence notions which may be more approachable. An example is (strong) Orbit equivalence.

Generalized Kakutani and Morita Equivalence

Kakutani Equivalence: Derived Systems

Let (X,ϕ,\mathbb{Z}) be a dynamical system and assume that the orbit of each point is dense.

Definition

Let $A \subseteq X$ be a nonempty clopen set. The derived system (A, \mathbb{Z}, ρ) is defined by setting $\rho^1(x)$ to be the first return time of $x \in A$ to A:

$$\forall x \in A \ \rho^1(x) = \inf\{n \in \mathbb{N}, n > 0 : \phi^n(x) \in A\}.$$

Equivalence of Dynamical Systems

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Generalized Kakutani and Morita Equivalence

Kakutani Equivalence: definition

Definition

Two dynamical systems (X,ϕ,\mathbb{Z}) and (Y,ψ,\mathbb{Z}) are Kakutani equivalent when they are conjugate to derived systems of some dynamical system (Z,ρ,\mathbb{Z}) .

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Definition

Two dynamical systems (X, ϕ, \mathbb{Z}) and (Y, ψ, \mathbb{Z}) are flip-Kakutani equivalent when they are Kakutani equivalent, or one is Kakutani equivalent to the other with time reversed.

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How to we generalize this notion to \mathbb{Z}^d ?

Equivalence of Dynamical Systems

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Generalized Kakutani and Morita Equivalence

Bounded orbit injection

We define a generalized notion of derived systems for \mathbb{Z}^d actions.

Definition (Lightwood, Ormes 2007)

Let (X,ϕ,\mathbb{Z}^d) and (Y,ψ,\mathbb{Z}^d) be two dynamical systems. A map $\theta:X\to Y$ is a *orbit injection* when it is a continuous open injection such that for all $x,y\in X$:

$$\exists z \in \mathbb{Z}^d \ \phi^z(x) = y \iff \exists n(z, x) \in \mathbb{Z}^d \ \psi^{n(z, x)}(\theta(x)) = \theta(y).$$

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The idea behind this definition is that a derived system defines a natural orbit injection, and conversely if an orbit injection exists between \mathbb{Z} -actions, we have in fact a derived system.

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The idea behind this definition is that a derived system defines a natural orbit injection, and conversely if an orbit injection exists between \mathbb{Z} -actions, we have in fact a derived system. The map n is unique if the action ψ is free. An orbit injection is bounded when it has a bounded cocycle.

BOIE

We can define a generalized notion of Kakutani equivalence as follows:

Definition (Lightwood, Ormes 2007)

Two dynamical systems (X,ϕ,\mathbb{Z}^d) and (Y,ψ,\mathbb{Z}^d) are bounded orbit injection equivalent when there exists a dynamical system (Z,ρ,\mathbb{Z}^d) and bounded orbit injections from (X,ϕ,\mathbb{Z}^d) and (Y,ψ,\mathbb{Z}^d) into (Z,ρ,\mathbb{Z}^d) .

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This notion generalizes flip-Kakutani equivalence for actions of \mathbb{Z}^d .

Generalized Kakutani and Morita Equivalence

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This notion generalizes flip-Kakutani equivalence for actions of \mathbb{Z}^d .

Are they any good invariant for this relation? For this, we shall restrict ourselves to a class of dynamical systems for which many of our equivalence relations have been successfuly understood.

C*-algebras and Kakutani Equivalence of minimal Cantor systems

Frédéric Latrémolière, PhD

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Minimal Free Cantor Systems

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Generalized Kakutani and Morita Equivalence

Minimal Free Cantor Systems

A cantor set is a topological space homeomorphic to the usual middle-third Cantor set, or equivalently it is a perfect, completely disconnected compact metrizable space.

Definition

Let X be a Cantor set. A minimal free Cantor system is a free action of \mathbb{Z}^d on X by homeomorphisms such that every point has a dense orbit in X.

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We will denote a free minimal dynamical system by (X, ϕ, \mathbb{Z}^d) where the homeomorphism of X defined by $z \in \mathbb{Z}^d$ is denoted ϕ^z .

Equivalence of Dynamical Systems

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Generalized Kakutani and Morita Equivalence

Definition

Let (X,ϕ,\mathbb{Z}^d) be a dynamical system. The continuous functions on the orbit space is:

$$\{f \in C(X) : \forall z \in \mathbb{Z}^d \ f \circ \phi^z = f\}.$$

This reduces to constants when ϕ is minimal. Is there a good (noncommutative) replacement? The idea is to require only that $f \in C(X)$ and $f \circ \phi^z$ be "equivalent" in some way. We arrive at:

Definition

Let (X,ϕ,\mathbb{Z}^d) be a dynamical system. The C*-crossed-product $C(X)\rtimes_\phi\mathbb{Z}^d$ is the universal C*-algebra generated by C(X) and unitaries U^z $(z\in\mathbb{Z}^d)$ such that $U^{z+z'}=U^zU^{z'}$ and $U^zfU^{-z}=f\circ\phi^{-z}$ for all $z,z'\in\mathbb{Z}^d$.

This notion was introduced by Zeller-Meier in 68 and has been a major source of examples.

Equivalence of Dynamical Systems

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Generalized Kakutani and Morita Equivalence

Giordano, Putnam, Skau

The two main results in the subject of minimal free Cantor systems were established by these three authors in 95.

Theorem (GPS, 95)

Two free minimal Cantor systems (X, ϕ, \mathbb{Z}) and (Y, ψ, \mathbb{Z}) are strongly orbit equivalent if and only if their C*-crossed-product algebras are *-isomorphic.

Equivalence of Dynamical Systems

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These C^* -algebras are fully characterized by their ordered K-theory, so ordered K-theory is a complete invariant for strong orbit equivalence for minimal free Cantor systems.

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Theorem (GPS, 95)

Two free minimal Cantor systems (X, ϕ, \mathbb{Z}) and (Y, ψ, \mathbb{Z}) are flip conjugate if and only if there is a *-isomorphism μ between their C*-crossed-products mapping C(X) onto C(Y).

What about Kakutani's equivalence?

Equivalence of Dynamical

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Generalized Kakutani an Morita Equivalence

Generalized Kakutani and Morita Equivalence

Kakutani

What about Kakutani's equivalence?

Theorem (GPS, 95)

Two free minimal Cantor systems (X,ϕ,\mathbb{Z}) and (Y,ψ,\mathbb{Z}) are strongly orbit Kakutani equivalent if and only if their C*-crossed-product algebras are Morita equivalent.

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We see that in principle, it is easier to show C*-algebras are Morita equivalent, so strong orbit Kakutani is indeed weaker than conjugacy.

Kakutani and Morita Equivalence

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Can we extend this result to characterize flip-Kakutani and its generalization, BOIE?

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Can we extend this result to characterize flip-Kakutani and its generalization, BOIE?

Note: continuity of the cocycle in orbit equivalence is the key difference between strong orbit eq and bounded orbit eq, the latter being flip-conjugacy in our case.

Equivalence of Dynamical Systems

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Generalized Kakutani and Morita Equivalence

Morita Equivalence

In general, Morita equivalence is an algebraic concept: two rings are Morita equivalent when their categories of modules are equivalent.

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Generalized Kakutani and Morita Equivalence

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In general, Morita equivalence is an algebraic concept: two rings are Morita equivalent when their categories of modules are equivalent. One can always choose an equivalence functor as a tensor by a bimodule.

Equivalence o Dynamical Systems

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Question

What is the appropriate notion of Morita equivalence for C*-algebras?

Though rings, C*-algebras are more. Rieffel proposes a stronger version of equivalence.

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Question

What is the appropriate notion of Morita equivalence for C*-algebras?

Though rings, C*-algebras are more. Rieffel proposes a stronger version of equivalence.

Definition (Rieffel)

Let A and B be two C*-algebras. They are Rieffel-Morita equivalent when their categories of hermitian modules are equivalent.

Generalized Kakutani and Morita Equivalence

Morita Equivalence, 2

We have:

Theorem (Rieffel)

Two C*-algebras A and B are Rieffel-Morita equivalent when there exists two Hilbert C*-bimodule M and N such that $M\otimes_B N=A$ and $N\otimes_A M=B$.

Generalized Kakutani and Morita Equivalence

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We have the following important:

Theorem

Let A be a simple C^* -algebra. Let $p \in A$ be a projection. Then pAp and A are Rieffel-Morita equivalent.

Generalized Kakutani and Morita Equivalence

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Theorem

Let A be a simple C^* -algebra. Let $p \in A$ be a projection. Then pAp and A are Rieffel-Morita equivalent.

Proof.

Let M = pA and N = Ap. Note that ApA = A by simplicity.



Equivalence Dynamical Systems

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Generalized Kakutani and Morita Equivalence We have:

Theorem (LO, 09)

Let (X,ϕ,\mathbb{Z}^d) and (Y,ψ,\mathbb{Z}^d) be two free minimal Cantor systems. Then the following are equivalent:

Equivalence Dynamical Systems

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Let (X,ϕ,\mathbb{Z}^d) and (Y,ψ,\mathbb{Z}^d) be two free minimal Cantor systems. Then the following are equivalent:

 $\ \, \bullet \, \, (X,\phi,\mathbb{Z}^d)$ and (Y,ψ,\mathbb{Z}^d) are bounded orbit injection equivalent,

Equivalence of Dynamical Systems

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Generalized Kakutani and Morita Equivalence We have:

Theorem (LO, 09)

Let (X,ϕ,\mathbb{Z}^d) and (Y,ψ,\mathbb{Z}^d) be two free minimal Cantor systems. Then the following are equivalent:

- There exists a *-monomorphism $\alpha: C(X) \rtimes_{\phi} \mathbb{Z}^d \to C(Y) \rtimes_{\psi} \mathbb{Z}^d$ such that the range of α is $pC(Y) \rtimes_{\psi} \mathbb{Z}^d p$ with $\alpha(1) = p$.

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Generalized Kakutani and Morita Equivalence We have:

Theorem (LO, 09)

Let (X, ϕ, \mathbb{Z}^d) and (Y, ψ, \mathbb{Z}^d) be two free minimal Cantor systems. Then the following are equivalent:

- **①** (X, ϕ, \mathbb{Z}^d) and (Y, ψ, \mathbb{Z}^d) are bounded orbit injection equivalent,
- ② There exists a *-monomorphism $\alpha: C(X) \rtimes_{\phi} \mathbb{Z}^d \to C(Y) \rtimes_{\psi} \mathbb{Z}^d \text{ such that the range of } \alpha \text{ is } pC(Y) \rtimes_{\psi} \mathbb{Z}^d p \text{ with } \alpha(1) = p.$

Thus, BOIE is a stronger notion that Morita equivalence, as we need to recall the base algebra on which the action occurs.

Equivalence o Dynamical Systems

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Generalized Kakutani and Morita Equivalence

$$p_h^z(y) = \left\{ \begin{array}{l} 1 \text{ if } y = \theta(x), x = \phi^z(x') \text{ and } y = \psi^h(\theta(x')) \\ 0 \quad \text{otherwise.} \end{array} \right.$$

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- ② For a fix z these projections are orthogonal,

Dynamical Systems

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- **3** $\{h: p_h^z \neq 0\}$ is finite for each z,

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- 2 For a fix z these projections are orthogonal,
- **3** $\{h: p_h^z \neq 0\}$ is finite for each z,
- **4** $\sum_h p_h^z = p$ where p is the projection on $\theta(X)$,
- **6** $p_h^{z+z'} = \sum_{h'} p_{h'}^z \cdot p_{h-h'}^{z'} \circ \psi^{-h'}$.

Equivalence Dynamical Systems

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Generalized Kakutani and Morita Equivalence

Step 1 - proof outline

 $\theta(X)$ is clopen in Y.

 $oldsymbol{\theta}$ is open and continuous.

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Generalized Kakutani and Morita Equivalence

Step 1 - proof outline

 p_h^z is well-defined.

- $oldsymbol{0}$ θ is open and continuous.
- 2 p_h^z is the indicator of the image by θ of $(n(\cdot,z))^{-1}(h)$, which is clopen.

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Generalized Kakutani and Morita Equivalence

Step 1 - proof outline

 p_h^z and $p_{h^\prime}^z$ are orthogonal.

- **1** θ is open and continuous.
- 2 p_h^z is the indicator of the image by θ of $(n(\cdot,z))^{-1}(h)$, which is clopen.
- **3** Let y such that $p_h^z(y) = p_{h'}^z(y) = 1$. Then: $y = \theta(x)$ and:

$$\psi^h(y) = \theta(\phi^z(x))$$

and same with h'. Since ψ is free we have h = h'.

Equivalence Dynamical Systems

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Generalized Kakutani and Morita Equivalence

Step 1 - proof (convolution)

$$p_h^{z+z'} = \sum_{h'} p_{h'}^z \cdot p_{h-h'}^{z'} \circ \psi^{-h'}$$

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$$p_h^{z+z'} = \sum_{h'} p_{h'}^z \cdot p_{h-h'}^{z'} \circ \psi^{-h'}$$

Let $y\in Y$ and $z,z',h\in\mathbb{Z}^d$ such that $p_h^{z+z'}(y)=1$. Then there exists $x,x'\in X$ such that:

$$y = \theta(x), x = \phi^{z+z'}(x'), \psi^h(y) = \theta(x').$$

Thus:

$$x = \phi^z(\phi^{z'}(x')).$$

Equivalence of Dynamical Systems

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Generalized Kakutani and Morita Equivalence

Step 1 - proof (convolution)

$$p_h^{z+z'} = \sum_{h'} p_{h'}^z \cdot p_{h-h'}^{z'} \circ \psi^{-h'}$$

$$x = \phi^z(\phi^{z'}(x))$$

so there exists $n(\phi^{z'}(x'), z)' := h'$ such that:

$$y = \psi^{h'}(\theta(\phi^{z'}(x')))$$

i.e. $p_{h'}^z(y)=1.$ This is the only possible nonzero $p_?^z(y)$ by orthogonality.

Equivalence of Dynamical Systems

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Step 1 - proof (convolution)

$$p_h^{z+z'} = \sum_{h'} p_{h'}^z \cdot p_{h-h'}^{z'} \circ \psi^{-h'}$$

We had $y = \psi^{h'}(\theta(\phi^{z'}(x')))$. So:

$$\psi^{-h'}(y) = \theta(\phi^{z'}(x')).$$

On the other hand:

$$\psi^h(y) = \theta(x')$$

SO

$$\psi^{-h'}(y) = \psi^{h-h'}(\theta(x'))$$

SO

$$p_{h-h'}^{z'}(\psi^{-h'}(y)) = 1.$$

Equivalence o Dynamical Systems

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Generalized Kakutani and Morita Equivalence We can define unitaries by:

$$V^{z} = \sum_{h} p_{h}^{z} U_{\psi}^{h} + (1 - p)$$

and we check that $z\mapsto V^z$ is a group homomorphism into the unitary group of $C(Y)\rtimes_\psi\mathbb{Z}^d$. This uses our convolution formula for the p^z_h .

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We then define $\pi:C(X)\mapsto C(Y)$ by $\pi(f)(y)=f(x)$ if $y=\theta(x)$ and 0 otherwise.

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We then define $\pi:C(X)\mapsto C(Y)$ by $\pi(f)(y)=f(x)$ if $y=\theta(x)$ and 0 otherwise. π goes backward! However, we check that (π,V) is a covariant representation for $(C(X),\phi,\mathbb{Z}^d)$.

Equivalence of Dynamical Systems

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and we check that $z\mapsto V^z$ is a group homomorphism into the unitary group of $C(Y)\rtimes_\psi\mathbb{Z}^d$. This uses our convolution formula for the p^z_h .

We then define $\pi:C(X)\mapsto C(Y)$ by $\pi(f)(y)=f(x)$ if $y=\theta(x)$ and 0 otherwise. π goes backward! However, we check that (π,V) is a covariant representation for $(C(X),\phi,\mathbb{Z}^d)$. To check this is tricky and uses the orbit injection property a lot!

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Generalized Kakutani and Morita Equivalence ① The pair (π,V) is covariant, so we can define a *-morphism $\alpha:C(X)\rtimes_\phi\mathbb{Z}^d\to C(Y)\rtimes_\psi\mathbb{Z}^d$ which extends it.

Equivalence of Dynamical Systems

C*-Crossed products

Generalized Kakutani and Morita Equivalence

- ① The pair (π,V) is covariant, so we can define a *-morphism $\alpha:C(X)\rtimes_\phi\mathbb{Z}^d\to C(Y)\rtimes_\psi\mathbb{Z}^d$ which extends it.
- ② Since the action of ϕ is minimal, α is injective. Its range is a sub-algebra of $pC(Y) \rtimes \mathbb{Z}^d p$. Is it all of it?

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- **③** We write $pU_{\psi}^{h}p$ as a sum of elements all in the range of α by decomposing $\theta(X)$ as the disjoint union of $\{x \in \theta(X) : \psi^{h}(x) \in \theta(X)\}.$

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Step 4 (converse)

Now, we suppose given a *-monomorphism with the listed properties. Is it induced by some bounded orbit injection?

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Lemma (generalized from GPS95)

Let v be a unitary in $C(X) \rtimes_{\phi} \mathbb{Z}^d$ such that vC(X)v*=C(X). Then:

$$v = f \sum_{z} p_z U_{\phi}^z$$

where $f \in C(X)$ and p_z are mutually ortogonal projections, only finitely nonzero, summing to 1.

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Define $p_z = |\mathbb{E}(vU_{\phi}^{-z})|$. Consider the regular representation π for the Dirac measure at some $x \in X$, which is faithful (minimality) and irreducible and acts on $l^2(\mathbb{Z}^d)$ by:

$$\pi(U_p^z)\delta_h = \delta_{h+z}$$
 and $\pi(f)(\delta_h) = f(\phi^{-h}(x)).$

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Note that $\pi(v)$ commutes with $\pi(C(X))$ so it commutes with $l^{\infty}(G)$. Hence, as it is a unitary, it is of the form $\pi(v)(\delta_h) = \lambda_h \delta_{\sigma(h)}$ for some permutation σ of \mathbb{Z}^d .

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A direct computation shows that $\pi(p_z)$ is a projection; that they are mutually orthogonal, and satisfy the desired properties.

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Generalized Kakutani and Morita Equivalence ① Thus, given a *-monomorphism with the described properties, the image of U^z_ϕ is a unitary V^z which stabilizes C(Y). The projections given by our lemma play the role of p^z_h in the first direction of the proof.

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- ② We can reconstruct an injection θ by $\alpha(f) = f \circ \theta^{-1}$ which makes sense when we restrict ourselves to $f \in pC(Y)p$. We then prove that it is an orbit injection.

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- We can reconstruct an injection θ by $\alpha(f) = f \circ \theta^{-1}$ which makes sense when we restrict ourselves to $f \in pC(Y)p$. We then prove that it is an orbit injection.
- 3 One direction of the orbit injection property namely that if two points are in the same orbit in Y and images of points in X by θ , the latter are in the same orbit for ϕ is quite tricky.