# On Lorentz Transformations and Continuity Equation of Angular Momentum in Relativistic Quantum Mechanics. 

By<br>Takashi Shibata<br>(Received Aug. 18, 1954)

## §1. Introduction and outlines.

In special relativity and relativistic quantum mechanics, the fundamental laws of mechanics are formulated so as they are form-invariant under the transformations of the general Lorentz group. The transformation of the Lorentz group is obtained by means of a suitable combination of spatial rotations of the axes of coordinates in two systems together with a special Lorentz transformation of the form:

$$
\begin{equation*}
x^{\prime}=\frac{x-u t}{\sqrt{1-u^{2} / c^{2}}}, \quad y^{\prime}=y, \quad z^{\prime}=z, \quad t^{\prime}=\frac{t-u x / c^{2}}{\sqrt{1-u^{2} / c^{2}}} \tag{1.1}
\end{equation*}
$$

where $x, y, z, t$ and $x^{\prime}, y^{\prime}, z^{\prime}, t^{\prime}$ are space-time coordinates in two systems $K$ and $K^{\prime}$, the uniform velocity of $K^{\prime}$ relative to $K$ being $u$ along $x$-axis of $K$. The equations (1.1) represent the relations between the coordinates in $K$ and $K^{\prime}$ where the relative velocity of $K^{\prime}$ to $K$ is parallel to the $x$-axis. However, sometimes we shall need explicit expressions for the Lorentz transformations in a more general case where the relative velocity of $K^{\prime}$ to $K$ is not parallel to the $x$-axis and where the Cartesian axes in $K$ and $K^{\prime}$ have the same orientation (not arbitrary orientations relative to each other). Such a transformation is the so-called Lorentz transformation without rotation $[\mathbf{1}]^{*)}$. The explicit expression for such Lorentz transformation without rotation is given by the following vector form: [1]

$$
\begin{align*}
\boldsymbol{X}^{\prime} & =\boldsymbol{X}+\boldsymbol{U}\left[\frac{(\boldsymbol{U} \boldsymbol{X})}{u^{2}}\left\{\left(1-u^{2} / c^{2}\right)^{-\frac{1}{2}}-1\right\}-t\left(1-u^{2} / c^{2}\right)^{-\frac{1}{2}}\right]  \tag{1.2}\\
t^{\prime} & =\left(1-u^{2} / c^{2}\right)^{-\frac{1}{2}}\left\{t-(\boldsymbol{U} \boldsymbol{X}) / c^{2}\right\}
\end{align*}
$$

where

$$
\boldsymbol{X}=(x, y, z), \quad \boldsymbol{X}^{\prime}=\left(x^{\prime}, y^{\prime}, z^{\prime}\right), \quad \boldsymbol{U}=\left(u^{1}, u^{2}, u^{3}\right)
$$

[^0]
[^0]:    *) The ciphers in the square brackets refer to the Bibliography attached to the end of this paper.

