

Chapter 10

Angular Momentum

$$L_z Y_{lm} = m\hbar Y_{lm} \quad (1)$$

$$L^2 Y_{lm} = \underbrace{l(l+1)\hbar^2}_{\lambda} Y_{lm}$$

Note that ang. mom. has the dim. of \hbar .

$m, l(l+1)$: real numbers

The peculiar way of writing the eigenvalue of L^2 will prove its convenience later.

$$\text{Now } \begin{cases} x = r \sin\theta \cos\varphi \\ y = r \sin\theta \sin\varphi \\ z = r \cos\theta \end{cases} \quad (2)$$

$$\begin{cases} dx = \frac{\partial x}{\partial r} dr + \frac{\partial x}{\partial \theta} d\theta + \frac{\partial x}{\partial \varphi} d\varphi \\ dy = \frac{\partial y}{\partial r} dr + \frac{\partial y}{\partial \theta} d\theta + \frac{\partial y}{\partial \varphi} d\varphi \\ dz = \frac{\partial z}{\partial r} dr + \frac{\partial z}{\partial \theta} d\theta + \frac{\partial z}{\partial \varphi} d\varphi \end{cases}$$

$$\rightarrow \begin{cases} dx = \sin\theta \cos\varphi dr + r \cos\theta \cos\varphi d\theta - r \sin\theta \sin\varphi d\varphi \\ dy = \sin\theta \sin\varphi dr + r \cos\theta \sin\varphi d\theta + r \sin\theta \cos\varphi d\varphi \\ dz = \cos\theta dr - r \sin\theta d\theta \end{cases} \quad (3)$$

$$\rightarrow \begin{cases} dr = \sin\theta \cos\varphi dx + \sin\theta \sin\varphi dy + r d\theta \\ d\theta = \frac{1}{r} (\cos\theta \cos\varphi dx + \cos\theta \sin\varphi dy - \sin\theta dz) \\ d\varphi = \frac{1}{r \sin\theta} (-\sin\varphi dx + \cos\varphi dy) \end{cases} \quad (4)$$

$$\begin{aligned} (a) \rightarrow \frac{\partial}{\partial x} &= \frac{\partial r}{\partial x} \frac{\partial}{\partial r} + \frac{\partial \theta}{\partial x} \frac{\partial}{\partial \theta} + \frac{\partial \varphi}{\partial x} \frac{\partial}{\partial \varphi} \\ &= \sin\theta \cos\varphi \frac{\partial}{\partial r} + \frac{1}{r} \cos\theta \cos\varphi \frac{\partial}{\partial \theta} - \frac{\sin\varphi}{r \sin\theta} \frac{\partial}{\partial \varphi} \end{aligned}$$

Remark: Note that:
 $\frac{\partial y}{\partial x} = \frac{\partial z}{\partial x} = \dots = 0$
 They are indep.

Similarly:

$$\begin{aligned} \frac{\partial}{\partial y} &= \sin\theta \sin\varphi \frac{\partial}{\partial r} + \frac{1}{r} \cos\theta \sin\varphi \frac{\partial}{\partial \theta} + \frac{\cos\varphi}{r \sin\theta} \frac{\partial}{\partial \varphi} \\ \frac{\partial}{\partial z} &= \cos\theta \frac{\partial}{\partial r} - \frac{\sin\theta}{r} \frac{\partial}{\partial \theta} \end{aligned} \quad (5)$$

$$\rightarrow L_z = \frac{\hbar}{i} \left(x \frac{\partial}{\partial y} - y \frac{\partial}{\partial x} \right) = \frac{\hbar}{i} \frac{\partial}{\partial \varphi} \quad (6)$$

We introduce, $L_{\pm} = L_x \pm iL_y$ (7)

$$\begin{aligned} L_{\pm} &= \frac{\hbar}{i} \left[\left(y \frac{\partial}{\partial z} - z \frac{\partial}{\partial y} \right) \pm i \left(z \frac{\partial}{\partial x} - x \frac{\partial}{\partial z} \right) \right] \\ &= \frac{\hbar}{i} \left[\pm iz \left(\frac{\partial}{\partial x} \pm i \frac{\partial}{\partial y} \right) \mp i(x \pm iy) \frac{\partial}{\partial z} \right] \\ &= \pm \hbar r \cos\theta \left(\sin\theta e^{\pm i\varphi} \frac{\partial}{\partial r} + \frac{1}{r} \cos\theta e^{\pm i\varphi} \frac{\partial}{\partial \theta} \pm \frac{i e^{\pm i\varphi}}{r \sin\theta} \frac{\partial}{\partial \varphi} \right) \\ &= \mp \hbar r \sin\theta e^{\pm i\varphi} \left(\cos\theta \frac{\partial}{\partial r} - \frac{\sin\theta}{r} \frac{\partial}{\partial \theta} \right) \end{aligned}$$

$$L_{\pm} = \hbar e^{\pm i\varphi} \left(\pm \frac{\partial}{\partial \theta} + i \cot \theta \frac{\partial}{\partial \varphi} \right) \quad (8)$$

Now, since, $L_+ L_- = (L_x + iL_y)(L_x - iL_y) = L_x^2 + L_y^2 - i[L_x, L_y]$

$$L^2 = L_z^2 + L_+ L_- + i[L_x, L_y] = L_+ L_- + L_z^2 - \hbar L_z \quad (9)$$

second order diff. op. involving θ and φ .

There remains the task of solving the diff. equ. (1)

Alternative approach;

$$\nabla = \hat{r} \frac{\partial}{\partial r} + \hat{\varphi} \frac{1}{r \sin \theta} \frac{\partial}{\partial \varphi} + \hat{\theta} \frac{1}{r} \frac{\partial}{\partial \theta} \quad (10)$$

$$\begin{cases} \hat{r} = \sin \theta \cos \varphi \hat{i} + \sin \theta \sin \varphi \hat{j} + \cos \theta \hat{k} \\ \hat{\varphi} = -\sin \varphi \hat{i} + \cos \varphi \hat{j} \\ \hat{\theta} = \cos \theta \cos \varphi \hat{i} + \cos \theta \sin \varphi \hat{j} - \sin \theta \hat{k} \end{cases} \quad (11)$$

$$L = r \times p = (r \hat{r}) \times \left(\frac{\hbar}{i} \nabla \right) = \frac{\hbar}{i} \left(\hat{\varphi} \frac{\partial}{\partial \theta} - \hat{\theta} \frac{1}{\sin \theta} \frac{\partial}{\partial \varphi} \right) \quad (12)$$

$$\begin{cases} L_x = \frac{\hbar}{i} \left(-\sin \varphi \frac{\partial}{\partial \theta} - \cos \varphi \cot \theta \frac{\partial}{\partial \varphi} \right) \\ L_y = \frac{\hbar}{i} \left(\cos \varphi \frac{\partial}{\partial \theta} - \sin \varphi \cot \theta \frac{\partial}{\partial \varphi} \right) \\ L_z = \frac{\hbar}{i} \frac{\partial}{\partial \varphi} \end{cases} \quad (13)$$

$$L^2 = L_x^2 + L_y^2 + L_z^2 = -\hbar^2 \left[\frac{1}{\sin^2 \theta} \frac{\partial^2}{\partial \varphi^2} + \frac{1}{\sin \theta} \frac{\partial}{\partial \theta} \left(\sin \theta \frac{\partial}{\partial \theta} \right) \right] \quad (14)$$

$$(11) \rightarrow \left[\frac{1}{\sin^2 \theta} \frac{\partial^2}{\partial \varphi^2} + \frac{1}{\sin \theta} \frac{\partial}{\partial \theta} \left(\sin \theta \frac{\partial}{\partial \theta} \right) \right] Y(\theta, \varphi) = -\lambda Y(\theta, \varphi) \quad (15)$$

$$Y(\theta, \varphi) = \Phi(\varphi) \Theta(\theta) \quad (16) \quad \downarrow \uparrow$$

$$(16) \text{ in } (15) \rightarrow \underbrace{-\frac{1}{\Phi} \frac{d^2 \Phi}{d\varphi^2}}_{\text{const} = m^2} = \frac{\sin^2 \theta}{\Theta} \underbrace{\left[\frac{1}{\sin \theta} \frac{d}{d\theta} \left(\sin \theta \frac{d}{d\theta} \right) + \lambda \right]}_{\text{const} = m^2} \Theta \quad (17)$$

const = real, as will soon be seen by virtue of boundary conds.

$$\frac{d^2 \Phi}{d\varphi^2} + m^2 \Phi = 0 \quad (18)$$

$$\frac{1}{\sin \theta} \frac{d}{d\theta} \left(\sin \theta \frac{d}{d\theta} \right) \Theta - \frac{m^2}{\sin^2 \theta} \Theta + \lambda \Theta = 0 \quad (19)$$

Fundamental Postulate of Q.M.:

The wave func. for a particle without spin must have definite value at every point in space.

→ The wave func. must be singly-valued func. of the particles position.

$$\text{In particular: } \Phi(\varphi) = \Phi(\varphi + 2\pi) \quad (20)$$

$$(18) \rightarrow \Psi(\varphi) = e^{im\varphi} \quad (21)$$

The normalization: $\int_0^{2\pi} d\varphi |\Psi(\varphi)|^2 = 1 \rightarrow \Psi(\varphi) = \frac{1}{\sqrt{2\pi}} e^{im\varphi}$

$$(19) \rightarrow m = 0, \pm 1, \pm 2, \dots \quad (22)$$

Now, by a change of variables,

$$\xi = \cos\theta, \quad F(\xi) = \Theta(\theta) \quad (23)$$

$$\left. \begin{array}{l} \text{Remark:} \\ \frac{d}{d\xi} = -\frac{d}{\sin\theta d\theta} \\ \rightarrow \sin\theta \frac{d}{d\xi} = -(1-\xi^2)^{-1/2} \frac{d}{d\xi} \end{array} \right\}$$

$$(19) \rightarrow \frac{d}{d\xi} \left[(1-\xi^2) \frac{dF}{d\xi} \right] - \frac{m^2}{1-\xi^2} F + \lambda F = 0 \quad (24)$$

$$\text{For } m=0 \rightarrow \frac{d}{d\xi} \left[(1-\xi^2) \frac{dF}{d\xi} \right] + \lambda F = 0 \quad (25)$$

Legendre diff. equ.

Equ (25) does not change its form when $\xi \rightarrow -\xi$

\rightarrow The sols. are $\left\{ \begin{array}{l} \text{either odd} \\ \text{or even} \end{array} \right.$ fncs. of ξ .

$$\text{Since } \xi \rightarrow -\xi \Rightarrow \theta \rightarrow \pi - \theta$$

\rightarrow These fncs are symmetric or antisymmetric w.r.t. xy-plane.

$$F(\xi) = \sum_{k=0}^{\infty} a_k \xi^k \quad (26) \text{ regular sol.}$$

$$(26) \text{ in } (25) \rightarrow a_{k+2} = \frac{k(k+1) - \lambda}{(k+1)(k+2)} a_k \quad (27)$$

For even sol. $a_0 \neq 0$
 " odd = $a_1 \neq 0$ (28)

$$(27) \rightarrow \begin{cases} a_{-2} = 0 & \text{for even case} \\ a_{-1} = 0 & = \text{odd} \end{cases} \quad (29) \quad \left(\text{due to } \frac{1}{(k+1)(k+2)} \text{ factor} \right)$$

This is in agreement with the assumption that F is regular at $\xi = 0$.

$$\text{If } k \rightarrow \infty \rightarrow \frac{a_{k+2}}{a_k} \rightarrow \frac{k}{(k+2)} \quad (30)$$

(26) behaves like $\sum \frac{1}{n}$ for $\begin{cases} \text{even } n \\ \text{odd } n \end{cases}$ and

$$F(\xi) = \sum_{k=0}^{\infty} a_k \xi^k \rightarrow \infty \text{ at } \xi = \pm 1, \text{ i.e. } \theta = 0, \pi$$

For the same reason we exclude the second linearly indep. sol. of (25). It has logarithmic singularities at $\xi = \pm 1$

Such singular func., although solutions of the diff. equ. for almost all values of ξ , are not acceptable eigenfunc. of L^2 .

We conclude \rightarrow The power series must terminate at some finite value $k=l$, where l is nonnegative integer, and all higher powers vanish.

$$(27) \rightarrow \lambda = l(l+1) \quad (31)$$

Alternative approach:

The eigenfns. of the Hermitian ops. are orthonormal, if the eigenvalues are different.

With a proper normalization we will write:

$$\langle Y_{l'm'} | Y_{lm} \rangle = \delta_{ll'} \delta_{mm'} \quad (32)$$

$$\begin{aligned} \langle Y_{lm} | L^2 | Y_{lm} \rangle &= \langle Y_{lm} | (L_x^2 + L_y^2 + L_z^2) | Y_{lm} \rangle \quad (33) \\ &= \underbrace{\langle L_x Y_{lm} | L_x Y_{lm} \rangle}_{\geq 0} + \underbrace{\langle L_y Y_{lm} | L_y Y_{lm} \rangle}_{\geq 0} + \underbrace{m^2 \hbar^2}_{\geq 0} \geq 0 \end{aligned}$$

$$(33) \rightarrow l(l+1)\hbar^2 \geq 0 \quad (34)$$

We already saw that;

$$L^2 = L_+ L_- + L_z^2 - \hbar L_z \quad (35)$$

In the same way

$$L^2 = L_- L_+ + L_z^2 + \hbar L_z \quad (36)$$

$$\rightarrow [L_+, L_-] = 2\hbar L_z \quad (37)$$

$$[L_+, L_z] = [L_x + iL_y, L_z] = -i\hbar L_y - \hbar L_x = -\hbar L_+ \quad (38)$$

and

$$[L_-, L_z] = \hbar L_- \quad (39)$$

$$\text{Since } [\bar{L}^2, \bar{L}] = 0 \rightarrow \begin{cases} [\bar{L}^2, L_{\pm}] = 0 \\ [\bar{L}^2, L_z] = \end{cases} \quad (40)$$

$$\rightarrow \underbrace{L^2 L_{\pm} Y_{lm}} = L_{\pm} L^2 Y_{lm} = \underbrace{l(l+1)\hbar^2}_{\uparrow} \underbrace{L_{\pm} Y_{lm}} \quad (41)$$

On the other hand;

$$\begin{aligned} L_z \underbrace{L_{+} Y_{lm}} &= (L_x L_z + \hbar L_x) Y_{lm} = m\hbar L_{+} Y_{lm} + \hbar L_{+} Y_{lm} \\ &= \hbar \underbrace{(m+1)}_{\uparrow} \underbrace{L_{+} Y_{lm}} \end{aligned} \quad (42)$$

$$\text{Similarly; } L_z \underbrace{L_{-} Y_{lm}} = \hbar \underbrace{(m-1)}_{\uparrow} \underbrace{L_{-} Y_{lm}} \quad (43)$$

$$\rightarrow L_{\pm} Y_{lm} = C_{\pm}(l, m) Y_{l, m \pm 1} \quad (44)$$

$$\text{Also, } L_{\pm}^{\dagger} = (L_x \pm iL_y)^{\dagger} = L_x \mp iL_y = L_{\mp} \quad (45)$$

$$\text{Since, } \langle L_{\pm} Y_{lm} | L_{\pm} Y_{lm} \rangle \geq 0 \quad (46)$$

$$(46), (45) \rightarrow \langle Y_{lm} | L_{\mp} L_{\pm} Y_{lm} \rangle \geq 0 \quad (47)$$

$$(35)(36)(47) \rightarrow \langle Y_{lm} | (L^2 - L_z^2 \pm \hbar L_z) | Y_{lm} \rangle \geq 0 \quad (48)$$

$$(48) \rightarrow \begin{cases} l(l+1) \geq m^2 + m \\ l(l+1) \geq m^2 - m \end{cases} \quad (49)$$

$$\text{Since } l(l+1) \geq 0 \rightarrow \begin{cases} l \geq 0 \\ \text{or} \\ l \leq -1 \end{cases} \quad (50)$$

We choose $l \geq 0$. If we were to find $l \leq -1$, we would merely define $L = -l - 1$ and replace the old l , with the new positive L .
 Nothing would change, since $L(L+1) = l(l+1)$.

$$(49) \rightarrow -l \leq m < l \quad (51)$$

Let $m_- : m_{\min} \quad (m_- = -l)$,

$$\rightarrow L_- Y_{lm_-} = 0 \quad (52)$$

Results:

- $l(l+1) > m(m+1) \rightarrow l \geq m$
- $l(l+1) > m(m-1)$ For $m = -l$
- $\rightarrow l(l+1) > l(l+1)$
- For $m = -l+1 \rightarrow l(l+1) > l(l-1)$
- For $m = -l-1 \rightarrow l(l+1) > l(l+2)$

Now;

$$\langle Y_{lm_-} | L^2 | Y_{lm_-} \rangle = \langle Y_{lm_-} | (L_+ L_- + L_z^2 - \hbar L_z) | Y_{lm_-} \rangle$$

$$\rightarrow l(l+1)\hbar^2 = 0 + m_-^2 \hbar^2 - m_- \hbar^2 \quad (53)$$

Similarly;

$$L_+ Y_{lm_+} = 0 \quad (54)$$

$$\langle Y_{lm_+} | L^2 | Y_{lm_+} \rangle = \langle Y_{lm_+} | (L_- L_+ + L_z^2 + \hbar L_z) | Y_{lm_+} \rangle$$

$$\rightarrow l(l+1)\hbar^2 = 0 + m_+^2 \hbar^2 + m_+ \hbar^2 \quad (55)$$

$$(53)(55) \rightarrow \begin{cases} l(l+1) = m_- (m_- - 1) \\ l(l+1) = m_+ (m_+ + 1) \end{cases} \quad (56)$$

$$m_- (m_- - 1) = m_+ (m_+ + 1) \rightarrow m_- = -m_+ \quad (57)$$

$$\rightarrow \begin{cases} m_- = -l \\ m_+ = +l \end{cases} \quad (58)$$

$$m = \underbrace{-l, -l+1, \dots, l-1, l}_{2l+1 \text{ steps}} \quad (59)$$

Now, $C_{\pm}(l, m) = ?$

$$\begin{aligned} (64) \rightarrow |C_{\pm}(l, m)|^2 \langle Y_{l, m \pm 1} | Y_{l, m \pm 1} \rangle &= \langle L_{\pm} Y_{lm} | L_{\pm} Y_{lm} \rangle \\ &= \langle Y_{lm} | L_{\mp} L_{\pm} Y_{lm} \rangle = \langle Y_{lm} | (L^2 - L_z^2 \mp \hbar L_z) | Y_{lm} \rangle \\ &= \hbar^2 [l(l+1) - m(m \pm 1)] \end{aligned} \quad (60)$$

$$C_{\pm}(l, m) = \hbar \sqrt{l(l+1) - m(m \pm 1)} \quad (61)$$

note that:

$$\begin{cases} |Y_{l, m \pm 1}\rangle = L_{\pm} |Y_{lm}\rangle \\ \rightarrow \langle Y_{l, m \pm 1} | = \langle Y_{lm} | L_{\mp} \end{cases}$$

The eigenfunc:

$$Y_{lm}(\theta, \varphi) = \Theta_{lm}(\theta) e^{im\varphi} \quad (62)$$

$$\begin{aligned} (54) \rightarrow \hbar e^{i\varphi} \left(\frac{\partial}{\partial \theta} + i \cot \theta \frac{\partial}{\partial \varphi} \right) \Theta_{ll}(\theta) e^{il\varphi} &= \\ = \hbar e^{i(l+1)\varphi} \left(\frac{\partial}{\partial \theta} - l \cot \theta \right) \Theta_{ll}(\theta) &= 0 \end{aligned} \quad (63)$$

Sol. $\rightarrow \Theta_{ll}(\theta) = (\sin \theta)^l \quad (64)$

(up to normalization)

An arbitrary state is obtained by the lowering procedure;

$$Y_{lm}(\theta, \varphi) = C (L_-)^{l-m} \left[(\sin \theta)^l e^{il\varphi} \right] \quad (65)$$

Consider first;

$$\begin{aligned} L_- Y_{lm}(\theta, \varphi) &= \hbar e^{-i\varphi} \left(-\frac{\partial}{\partial \theta} + i \cot \theta \frac{\partial}{\partial \varphi} \right) \left[(\sin \theta)^l e^{il\varphi} \right] \\ &= \hbar e^{i(l-1)\varphi} \left(-\frac{\partial}{\partial \theta} - l \cot \theta \right) (\sin \theta)^l \quad (66) \end{aligned}$$

Since $\left(\frac{d}{d\theta} + l \cot \theta \right) f(\theta) = \frac{1}{(\sin \theta)^l} \frac{d}{d\theta} \left[(\sin \theta)^l f(\theta) \right]$ (67)

$$\rightarrow Y_{l, l-1}(\theta, \varphi) = C' \frac{e^{i(l-1)\varphi}}{(\sin \theta)^l} \left(-\frac{d}{d\theta} \right) \left[(\sin \theta)^l (\sin \theta)^l \right] \quad (68)$$

$$Y_{l, l-2}(\theta, \varphi) = C'' L_- Y_{l, l-1}(\theta, \varphi) \quad (69)$$

$$\begin{aligned} Y_{l, l-2}(\theta, \varphi) &= C'' \frac{e^{i(l-2)\varphi}}{(\sin \theta)^{l-1}} \left(-\frac{d}{d\theta} \right) \left[(\sin \theta)^{l-1} \frac{1}{(\sin \theta)^l} \left(-\frac{d}{d\theta} \right) (\sin \theta)^{2l} \right] \\ &= C'' (-1)^2 \frac{e^{i(l-2)\varphi}}{(\sin \theta)^{l-2}} \frac{d}{d\theta} \left[\frac{1}{\sin \theta} \frac{d}{d\theta} (\sin \theta)^{2l} \right] \quad (70) \end{aligned}$$

In terms of,

$$u = \cos \theta, \quad \frac{1}{\sin \theta} \frac{d}{d\theta} = \frac{d}{du}$$

$$(68) \rightarrow Y_{l, l-1} = C' \frac{e^{i(l-1)\varphi}}{(\sin \theta)^{l-1}} \frac{d}{du} \left[(1-u^2)^l \right] \quad (71)$$

$$(70) \rightarrow Y_{l, l-2} = C'' \frac{e^{i(l-2)\varphi}}{(\sin \theta)^{l-2}} \frac{d^2}{du^2} \left[(1-u^2)^l \right] \quad (72)$$

The general form:

$$Y_{lm} = C \frac{e^{im\varphi}}{(2\theta)^m} \left(\frac{d}{du}\right)^{l-m} [(1-u^2)^l] \quad (73)$$

Normalization; $\int d\Omega = \int_0^{2\pi} d\varphi \int_0^\pi \sin\theta d\theta$ (74)

$$\langle Y_{lm} | Y_{lm} \rangle = 1 = \int_0^{2\pi} d\varphi \int_{-1}^1 du |C|^2 \left[\frac{1}{(1-u^2)^{m/2}} \left(\frac{d}{du}\right)^{l-m} (1-u^2)^l \right]^2 \quad (75)$$

The integration is tedious.

$$Y_{lm}(\theta, \varphi) = (-1)^m \sqrt{\frac{2l+1}{4\pi} \frac{(l-m)!}{(l+m)!}} P_l^m(\cos\theta) e^{im\varphi} \quad (76)$$

For $m > 0$ $Y_{l,-m} = (-1)^m Y_{lm}^*$ (77)

The associated Legendre polynomials are given by ($m \geq 0$)

$$P_l^m(u) = (-1)^{l+m} \frac{(l+m)!}{(l-m)!} \frac{(1-u^2)^{-m/2}}{2^l l!} \left(\frac{d}{du}\right)^{l-m} (1-u^2)^l \quad (78)$$

$$P_l^{-m}(u) = (-1)^m \frac{(l-m)!}{(l+m)!} P_l^m(u) \quad (79)$$

Ex. - Consider a classical rotator, rotating in the $x-y$ plane.

$$\rightarrow E = \frac{L_z^2}{2I} \quad (83) \quad I: \text{moment of inertia}$$

$$\rightarrow H = \frac{L_z^2}{2I} \quad (84)$$

$$\rightarrow E_m = \frac{\hbar^2 m^2}{2I} \quad (85) \quad (\text{with the eigenfunc. } e^{\pm im\varphi})$$

Since $[L_z, H] = 0 \rightarrow$ there is degeneracy

$e^{+im\varphi}$ and $e^{-im\varphi}$ have the same energy.

Now consider N -particle rigidly fixed on a circle with equal angles $\alpha = \frac{2\pi}{N}$ between neighboring particles.



If the particles are identical, then the sol. of the energy eigenvalue eqn.

$$H \Psi_E(\varphi) = E \Psi_E(\varphi) \quad (86)$$

will again be $e^{\pm i\lambda\varphi} \quad (87)$

The physical system is unaltered under a rot. of $\beta = k \frac{2\pi}{N}$ and the sols. should reflect this. (k : integer)

$$\rightarrow \lambda = Nk \quad (88) \quad k: \text{an integer}$$

$$E = \frac{\hbar^2 (Nk)^2}{2I}$$

$$Y_{0,0} = \frac{1}{\sqrt{4\pi}}$$

$$Y_{1,1} = -\sqrt{\frac{3}{8\pi}} e^{i\varphi} \sin\theta$$

$$Y_{1,0} = \sqrt{\frac{3}{4\pi}} \cos\theta$$

$$Y_{2,2} = \sqrt{\frac{15}{32\pi}} e^{2i\varphi} \sin^2\theta$$

(80)

$$Y_{2,1} = -\sqrt{\frac{15}{8\pi}} e^{i\varphi} \sin\theta \cos\theta$$

$$Y_{2,0} = \sqrt{\frac{15}{16\pi}} (3\cos^2\theta - 1)$$

Now;

$$-\frac{\hbar^2}{2\mu} \left[\frac{1}{r^2} \left(r \frac{\partial}{\partial r} \right) \left(r \frac{\partial}{\partial r} \right) + \frac{1}{r} \frac{\partial}{\partial r} - \frac{L^2}{\hbar^2 r^2} \right] U_E(\vec{r}) + V(r) U_E(\vec{r}) = E U_E(\vec{r}) \quad (81)$$

$$\rightarrow -\frac{\hbar^2}{2\mu} \left[\frac{1}{r} \frac{d}{dr} \left(r \frac{d}{dr} \right) + \frac{1}{r} \frac{d}{dr} - \frac{l(l+1)}{r^2} \right] R_{Elm}(r) + V(r) R_{Elm}(r) = E R_{Elm}(r)$$

We see that there is no dependence on m in the eqn. - (82)

Thus, for a given l there will always be $(2l+1)$ -fold degeneracy (with $V(\vec{r}) = V(r)$) -