ISSN: 2993-8643

Research Article

Engineering: Open Access

Potential Working Principle for a Static Charge and Static Magnetic Motor

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Submitted: 2023, Aug 23; **Accepted**: 2023, Sep 26; **Published**: 2023, Oct 05

Citation: Narasimhan, C. (2023). Potential Working Principle for a Static Charge and Static Magnetic Motor. *Eng OA*, *1*(3), 142-156.

Abstract

The document describes a potential (potential, it may never work) way to generate perpetual motion using static charge and static magnets. The magnets have to be manufactured in such a way to generate anisotropic magnetic field. The crux of the whole principle is whether anisotropic electric fields and anisotropic magnetic fields exists and whether that can be used to generate perpetual motion. In anisotropic fields, the energy you get out is greater than the energy you put in (that is the author's prediction. He might be wrong about it). ***The author does not have the ability nor the infrastructure to test the idea. He wishes someone will do it for him.*** *If the reader of this document thinks the idea is significant, please cite the author as a contributor of the idea.* ***The author would like to be included as a co-author in such a work.*** *The author would be surprised if it is a significant idea because so many people might have already thought about it and tried it.*

I. Introduction

The crux of the whole principle is whether anisotropic electric fields and anisotropic magnetic fields exists and whether that can be used to generate perpetual motion. In anisotropic fields, the energy you get out is greater than the energy you put in (that is the author's prediction. The author might be wrong about it).

1. Anisotropic electric field and perpetual motion

1.1 Two-sided charged disk

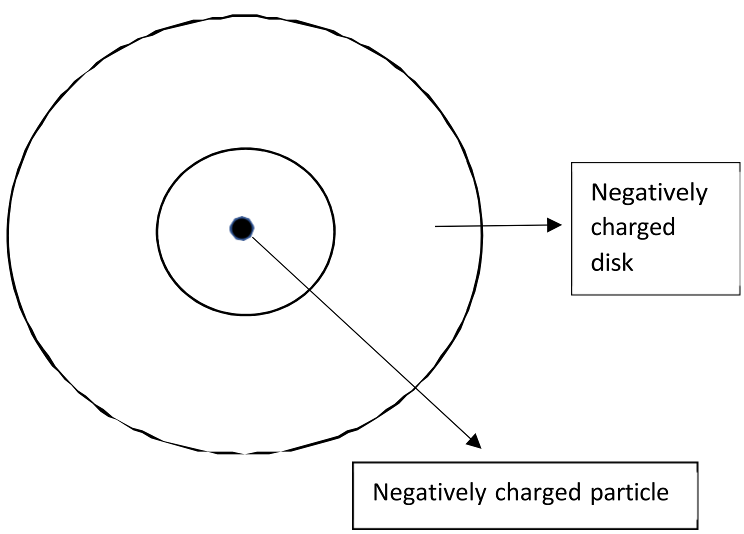

Figure 1: Negatively charged disk with a negatively charged particle at its center.

The negatively charged particle placed at the center of the disk will do one of the three things

1. Stay at the center of the disk.
2. Move out of the plane of the disk.
3. Move into the plane of the disk.

1. Stay at center of the disk

This happens when the initial position of the particle is in the exact plane of the disk.

2. Move out of the plane of the disk

This happens when the initial position of the particle is outside the plane.

3. Move into the plane of the disk

This happens when the initial position of the particle is inside the plane.

1.2 One side insulated disk

In this disk, an insulated layer is present in one of the sides.

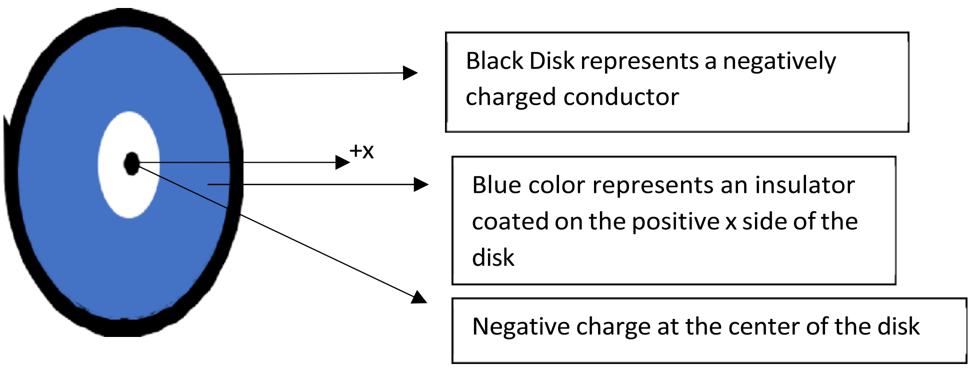

Figure 2: Negatively charged disk (Black in color) with a Negatively charged particle at the center and an insulated (Blue color) material on one side.

The author does not know what will happen exactly when one side of a charged metal disk is insulated with a non-conductor. He assumes that the field is going to be anisotropic. An experiment has to be performed to measure what actually happens. The author does not have the infrastructure nor the equipment to carry out such a test. He hypothesizes that the field will not be the same at a distance l along the x axis from the center of the disk in both positive and negative direction. For simplicity, he assumes the field to be zero along the positive x axis. The author acknowledges that he might be completely wrong in his prediction and hence the motor may never work.

Again, there are three possible scenarios

1. Negatively charged particle is at the center of the disk.
2. Negatively charged particle is at a positive position in the x axis.
3. Negatively charged particle is at a negative position in the x axis.

1. Negatively charged particle is at the center of the disk.

All forces from negative charge distribution on the disk will cancel out and the negative particle will be stationary.

2. Negatively charged particle is at a positive position in the x axis.

He assumes the electric field on the insulated side (positive x axis) to be zero and hence the particle will not move.

3. Negatively charged particle is at a negative position in the x axis.

The negatively charged particle will accelerate along the negative x axis.

1.3 A potential theory for a permanent motor

A basic thematic design of a static charged motor

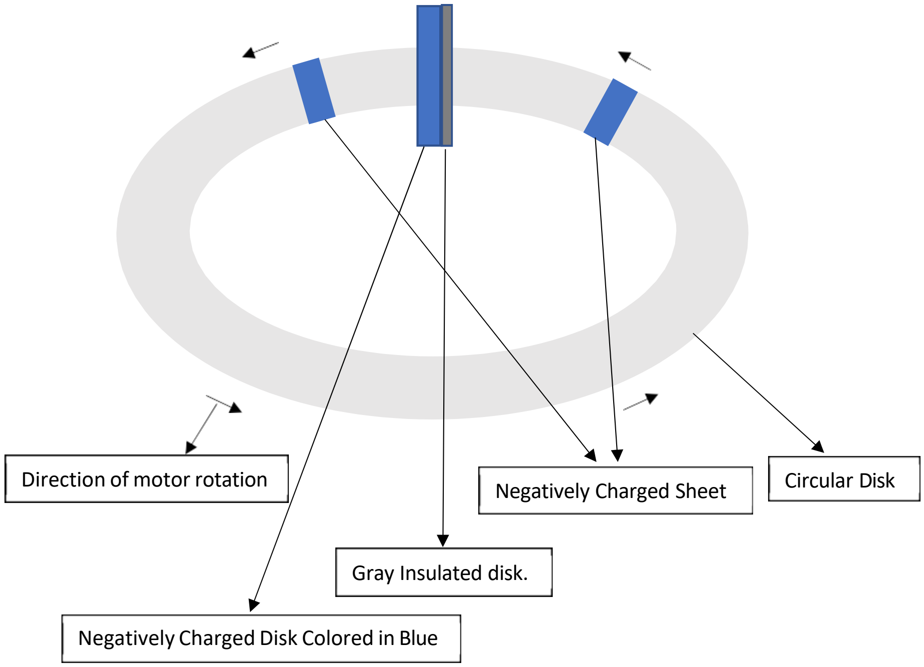

Figure 3: A conceptual diagram for a static electric motor. The author is well aware that the illustration can be made clearer. He believes that the diagram is good enough for the scientific community to understand the concept that is conveyed.

The concept presented here with anisotropic electric field can be hypothetically extended to an anisotropic magnetic field and hence a permanent magnetic motor. Again, the author does not know how to generate an anisotropic magnetic field. The author is way out of his expertise and does not know what compound to use to coat copper wires with that generate electro-magnetic field. The author is also not aware whether there is a compound that can generate an anisotropic electro-magnetic field.

The author is well aware that the design proposed is too simple and might not have eluded the thinking capabilities of scientific community at large. So, the author thinks there might be a flaw in the design proposed but he is not aware of it. If anyone can notice the flaw, please let the author know through the email address provided next to the title.

2. Potential working principle for Permanent Magnetic Motor

In the previous section, the author had stated a working principle for a static charge motor. Again, the author does not know whether it is going to work. The author is sorry for wasting the readers time if it does not work. The author would like to waste your time even more by asking you to send him the flaw in the design of the motor. Put yourself in his position, wouldn't you like to know what is the flaw in the design.

The author will state here that he is somewhat confident that static electric motor will work. He is not so confident that permanent magnetic motor will work.
The following section has new thoughts he has on the subject. If the reader has a tough time understanding why a permanent magnetic motor should work, read the section on why a static electric motor should work.

2.1 Equilibrium position for interaction between static hollow magnet and static cylindrical magnet:

Interaction between hollow magnet and polar magnet is shown in Figure 4 and Figure 5.

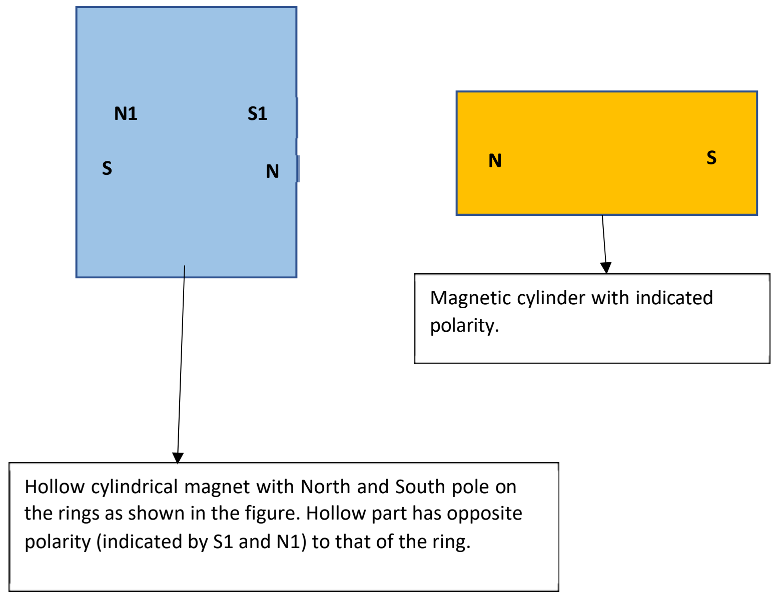

Figure 4: Polarity and Predicted polarity of hollow magnets.

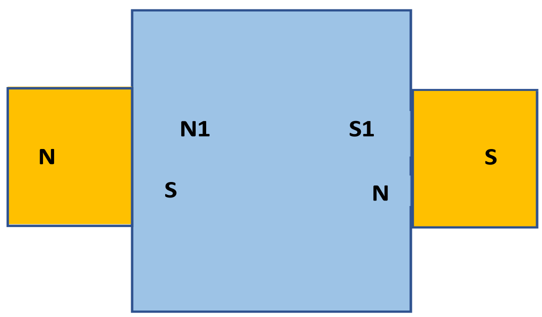

Figure 5: Predicted equilibrium (Lowest energy) position of hollow cylindrical and cylindrical magnets.

The author has seen youtube video where they talk about magnetic monopole.
Now, the author is going to describe potential ways to generate an anisotropic magnetic field. Then, assuming, generating anisotropic magnetic field is possible, the author is going to explain a potential way to generate energy without supply of energy.

2.2. Concept of anisotropic magnetic field: The author really does not know whether it is possible, only an experiment can confirm it. The author is somewhat confident that anisotropic electric field is possible. If the anisotropic magnetic field is not possible, the author thinks (The author is not sure because the author don't know how to generate permanent magnets) a permanent magnetic motor is not possible. The author has thought of few ways of generating anisotropic magnetic field:

Plastic Material or any non-magnetic material on one side:

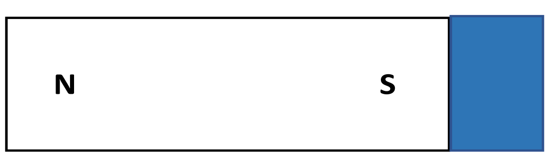

Figure 6: The magnet has non-magnetic material on one of its sides.

2.3. Possible ways (again, possible ways) to make anisotropic magnets

2.3.1 Magnet made from non-homogeneous material: Again, the author does not know whether this can be done. The author is way out of his expertise here. This should produce a magnet that has anisotropic magnetic field. Figure 6, Figure 7 and Figure 8 show potential ways of generating anisotropic magnetic field.

Non-Magnetic material is distributed in a unique way with in a magnet:

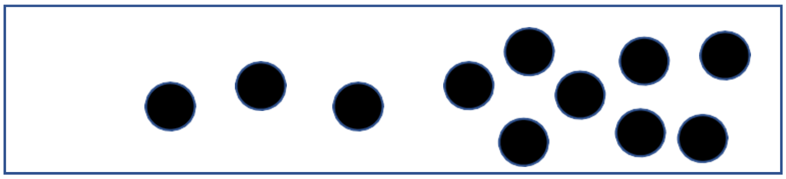

Figure 7: Assuming doping material with low magnetic potential exists, the above material should generate anisotropic magnetic field.

Non-Magnetic material is distributed in one side of the magnet:

Figure 8: Assuming doping material with low magnetic potential exists, the above material should generate anisotropic magnetic field.

2.3.2. Anisotropic Magnet made from electromagnetic coil: Now, the author does think this can be done.

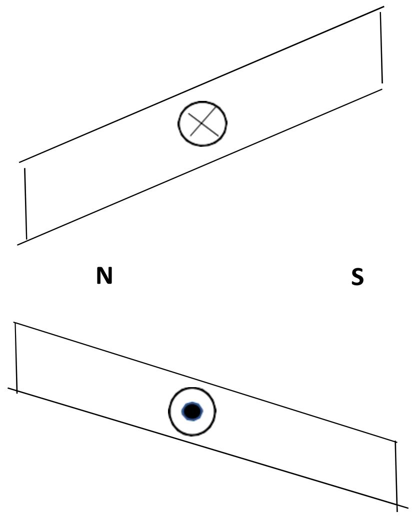

Figure 9: The above diagram shows a conic cross section of an electro magnet that can generate an anisotropic magnetic field. The into and out of marks dictate the direction of winding of the coil to generate an anisotropic magnetic field. Again, the author does not know whether it is going to work.

In an electro-magnetic motor, the electromagnet changes polarity losing energy. In the design of linear permanent magnetic accelerator, there is no polarity reversal. So magnetic energy is not lost.

2.3.3. Anisotropic Magnet made from varying the shape of magnetic material:

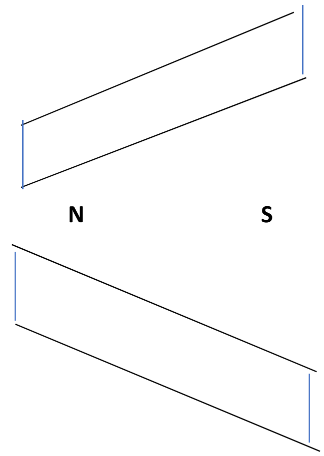

Figure 10: The author wants to suggest making a permanent magnet in the shape of a cone. So, the strength of north pole is different than the south pole.

2.3.4. Anisotropic Magnet made from varying the density of coil at a particular section:

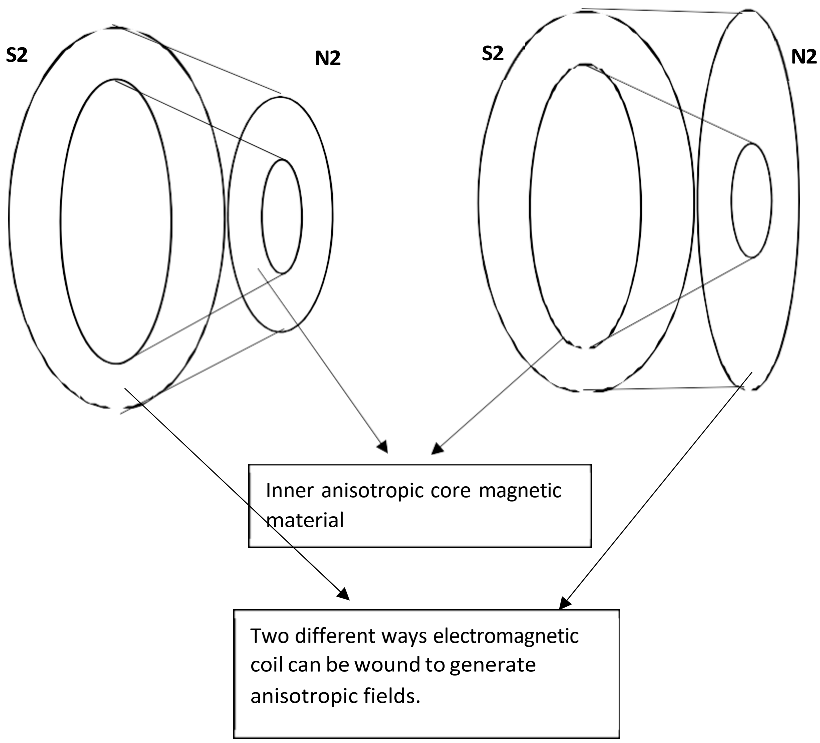

Figure 11: The author does not know how permanent magnets are created. The above diagram shows a potential prediction to make a permanent anisotropic conic magnet where the cross-section area creates anisotropy.

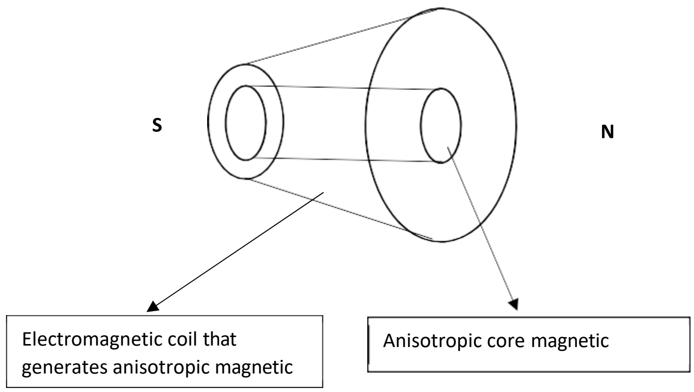

Figure 12: Predicted way to make cylindrical anisotropic magnet using electromagnetic coil. Figure 8 shows a predicted way to generate anisotropic magnetic field using a conic cross-sectional surface. In this figure, the author shows a predicted way to generate anisotropic cylindrical magnet.

Figures 3,4,5,6,7 and 8 illustrate the thought process culminating in the final design stated in Figure 12.

2.4. A potential model for linear permanent accelerator

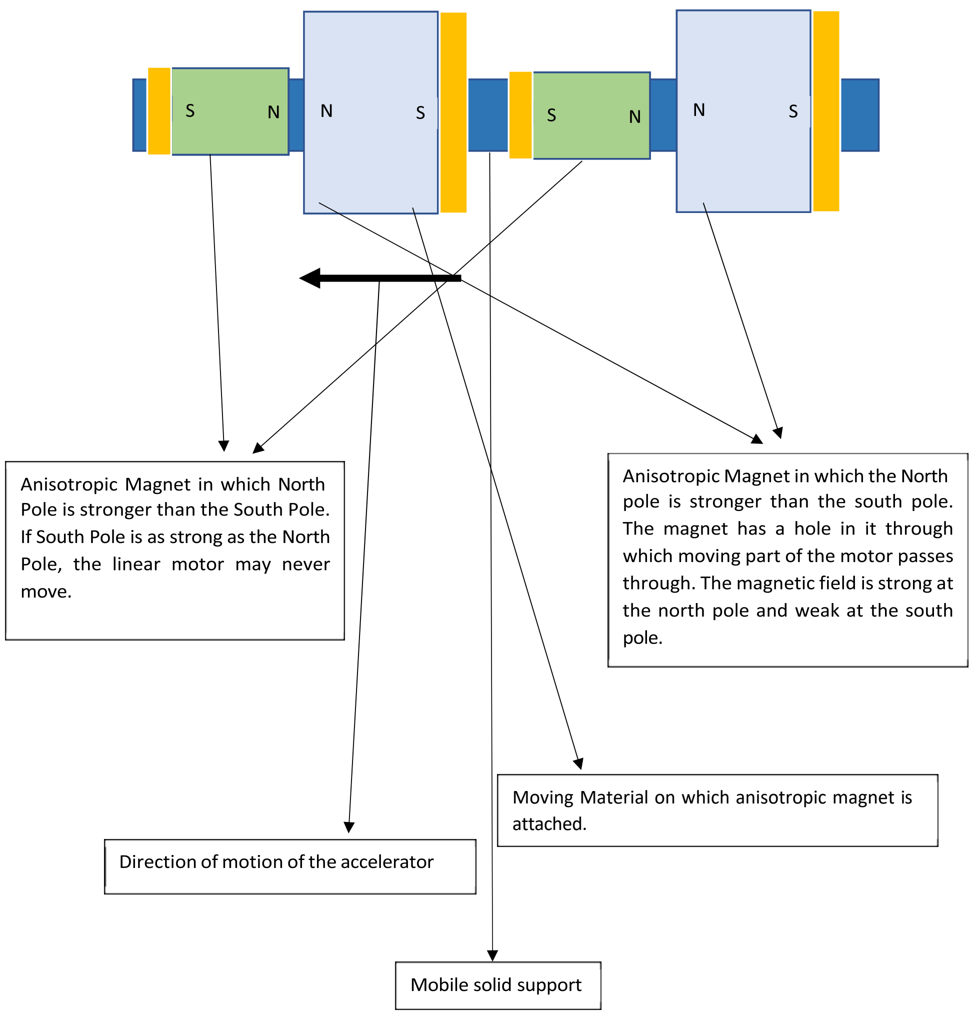

Figure 13: Prototype model of linear permanent magnetic accelerator. The model depicts an anisotropic magnet. But that may not work. Trying to use a magnet with: 1. Varying degree of doped elements, 2. Permanent hollow magnet in the shape of a cone, And 3. Electromagnet with the shape of a cone, may work (The author is not sure).

In an electro-magnetic motor, the electromagnet changes polarity losing energy. In the design of linear permanent magnetic accelerator, there is no polarity reversal. So magnetic energy is not lost.

2.4.1. Working Principle

Given an initial kinetic energy, the linear motor should continuously accelerate (Hopefully). At static position, non-moving north pole will bind to moving south pole in the hollow in such a way that moving south pole is closest to non-moving north pole and non-moving south pole is closest to moving north pole.

Because north-north repulsion is higher (hopefully) than north-south attraction and adjacent south-south repulsion, there will be continuous movement if the initial kinetic energy is high enough to overcome the barrier of attraction between non-moving north, moving south-attraction and non-moving south moving north-attraction. (Again, I would be very humble in saying that this might never work.)

2.5 Potential working principle for external energy free Permanent Magnetic Motor

The hypothesized (again hypothesized) working principle is same as a linear motor, but the moving part is circular.

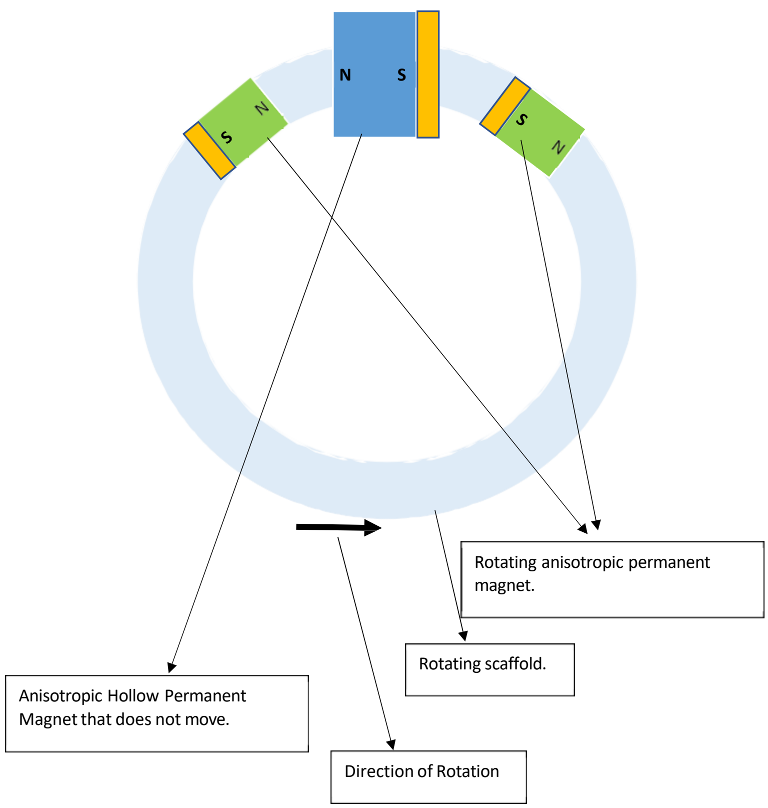

Figure 14: Prototype model of circular permanent magnetic accelerator. The model depicts an anisotropic magnet. But that may not work. Trying to use a magnet with: 1. varying degree of doped elements, 2. Permanent hollow magnet in the shape of a cone, And 3. Electromagnet with the shape of a cone, may work (The author is not sure).

Author's Prediction: The author is somewhat confident permanent Static Electric motor will work. The author is not so sure about permanent magnetic motor designs stated in sections 2.4 and 2.5 will work.

2.6. Predicting Motion of anisotropic magnets in isotropic and anisotropic magnetic fields

In the following section, the author presents a set of scenarios and potential outcome of such scenarios to validate the designs that has been proposed and to come up with new designs that can overcome the flaws that are in the proposed design.

2.6.1. Both magnets are Isotropic

Most simple arrangement is considered. Magnetism is produced by two loops, one small and another large, that produce an isotropic field. The author's prediction is that such an arrangement will not lead to a gain in velocity. Assuming initial velocity of the small loop is V, it will regain its velocity as it leaves the large loop. The whole process can be explained as follows: Magnetic forces acting on small loop can be modeled as forces acting on center C2. As C2 approaches C1, it will be decelerated and it will be accelerated as it leaves C1. Since it is an isotropic filed there won't be any gain in velocity.

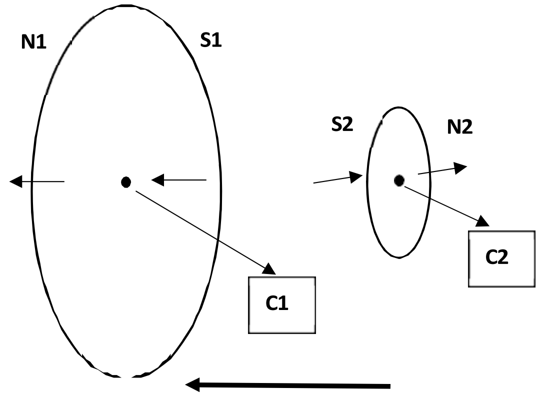

Figure 15: The above figure shows two loops that are permanent magnets that produce isotropic fields. The long arrow shows the direction of motion of the small loop while the large loop remains stationary. Assuming the small loop has a velocity V at minus infinity, it will slow down as it enters the large loop because the polarity is opposing. If the repulsive force is very strong the loop will bounce back. It might pass through the loop by slowing down and regaining velocity as it leaves the loop. So, the small loop will theoretically gain all its initial velocity. The final velocity will be same as initial velocity V.

2.6.2. Both magnets are anisotropic

Again, the author is not an experimentalist and he does not know how to make an anisotropic magnetic field from a ring. He guesses that, it can be done by coating opposite sides of a ring with materials that have different magnetic permeability. Another possibility is to make smaller hoop into a disk with low magnetic permeability on one side.

It is assumed that smaller magnetic material approaches the larger hoop with an initial velocity V. As C2 approaches C1, it will decelerate and accelerate, as it moves away from it. Since there is an anisotropic field, the repulsive force, as C2 leaves C1 will be greater than repulsive force as C2 approaches C1. So, there will be a net gain in velocity.

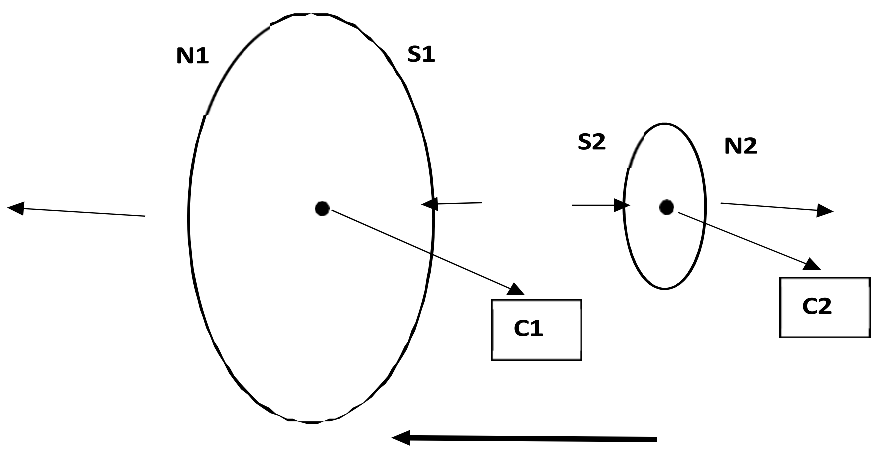

Figure 16: The above figure shows two loops that are permanent magnets that produce anisotropic fields. The long arrow shows the direction of motion of the small loop while the large loop remains stationary. In an anisotropic field the magnitude of force generated is different compared to a similar magnet. Longer arrows mean regions of high magnetic field strength. So N2>S2 and N1>S1. Assuming the small loop has a velocity V at minus infinity, it will slow down as it enters the large loop because the polarity is opposing. It might pass through the loop by slowing down and regaining velocity as it leaves the loop. For more detailed discussion on what can happen read discussions further below.

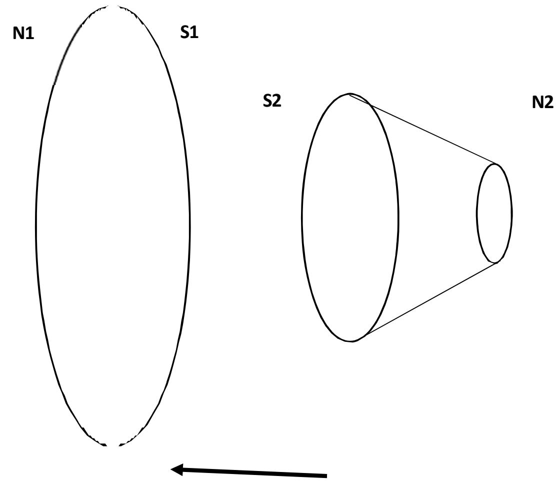

Figure 17: Another assembly that promotes the same concept conveyed in Figure 12. In this figure, anisotropy is generated using a conic section where the magnetic flux density in one side might be different from the magnetic flux density in another. This variation in flux density may or may not lead to a gain in velocity. For more discussion on the what can happen, read the following sections.

2.7 Mechanism for generating biased acceleration

There are four possible ways for interaction to occur between isotropic and anisotropic magnets.

1. Isotropic Hollow Magnet and Isotropic moving Magnet.
2. Isotropic Hollow Magnet and Anisotropic moving Magnet.
3. Anisotropic Hollow Magnet and isotropic moving Magnet.
4. Anisotropic Hollow Magnet and Anisotropic moving Magnet.

2.7.1. Isotropic hollow magnet and isotropic moving magnet:

This arrangement has already been discussed in Figure 15. It will not lead to gain of velocity.

2.7.2. Isotropic hollow magnet and anisotropic moving magnet:

2.7.2.1. The author proposes two possible scenarios and concludes that perpetual acceleration is not possible.

2.7.2.1.1. Only magnetic flux at the poles of anisotropic moving magnet contribute to interaction forces.
While calculating forces between two metals that have different charge, only charge distribution at the surface of the metals are considered. Similarly, an assumption can be made that only ends of the anisotropic magnet can contribute to forces arising from magnetic interaction (Is it a valid assumption? The author does not know. The author not even knows how permanent magnets are made). If the assumption is right, it would lead to a gain in velocity (see Figure 18).

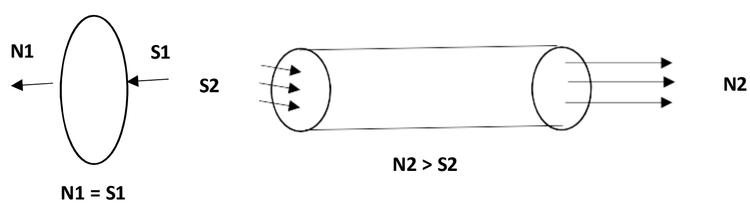

Figure 18: A permanent anisotropic magnet that produces an unbalanced magnetic field (The author does not know how to produce such a field. He suggests procedure stated in Figure 12 and other procedures stated in previous sections). Longer arrows represent regions with higher magnetic field strength. So N2 is greater than S2. The author foresees and evaluates two possible scenarios and his conclusion is that there will be no gain in velocity.

The reader can also take this as an opportunity to test their predictability to see what will be the outcome of a particular setup.
2.7.2.1.2. There will be no gain in velocity
The setup (Figure 18) can be simplified to four possible interactions. They are:
2.7.2.1.2.1. S1-S2 repulsion away from large loop to the right.
2.7.2.1.2.2. S1-N2 repulsion away from large loop to the right.
2.7.2.1.2.3. N1-S2 repulsion away from the loop to the left.
2.7.2.1.2.4. N1-N2 repulsion away from the loop ***to the left.***
S1-S2 repulsion and S1-N2 repulsion, decelerate the anisotropic magnet. N1-S2 repulsion and N1-N2 repulsion accelerate the anisotropic magnet. The author predicts (it is a prediction) that S1-S2 repulsive deceleration will cancel out N1-S2 acceleration and S1-N2 deceleration will cancel out N1-N2 acceleration. ***Thus, no gain in velocity will be produced as the anisotropic magnet moves through isotropic loop.***

2.7.2.1.3. There will be a gain in velocity
Again, the setup can be simplified into four possible interactions. They are:

2.7.2.1.3.1. S1-S2 repulsion away from the large loop to the right.
2.7.2.1.3.2. S1-N2 repulsion away from the large loop ***to the left.***
2.7.2.1.3.3. N1-S2 repulsion away from the large loop ***to the right.***
2.7.2.1.3.4. N1-N2 repulsion away from the large loop to the left.

Since S1-N2 repulsion and N1-N2 repulsion is greater than S1-S2 repulsion and N1-S2 repulsion, the anisotropic magnet will move to the left. ***Thus, gain in velocity will be produced when anisotropic magnet moves through isotropic loop.***

2.7.2.1.4. The stated conclusion in section 2.7.2.1.3. is incorrect. S1-N2 repulsion is to the right and not to the left. This is because direction of forces and the location of forces is the same for S1-S2 interaction and S1-N2 interaction, while the magnitude of these forces will be different. By the same reasoning, N1-S2 repulsion is to the left and not to the right. So, the anisotropic magnet will not gain any velocity.

2.7.2.2. Magnetic flux all along the anisotropic moving magnet contribute to interaction forces.
Suppose there are two spheres that have uniform charge distribution throughout their volume, how will you calculate the forces that arise from it? The author does not know how to compute or test such a force. While internal magnetic field effect is ignored or assumed not present in section 2.7.2.1, it is included in this analysis (see Figure 19).

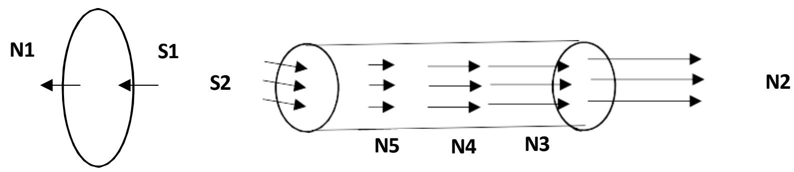

Figure 19: A permanent anisotropic magnet that produces an unbalanced magnetic field inside the magnet. Longer arrows represent regions with higher magnetic field strength. The interactions are similar to interactions stated in section 2.7.2.2. and he predicts that there will be no gain in velocity.

The long anisotropic magnets can be divided into small anisotropic ring magnets and analyzed. The conclusion is similar to conclusion in section 2.7.2.1.1 and section 2.7.2.1.2. There will be no gain in velocity.

2.7.3. Anisotropic Hollow Magnet and isotropic moving Magnet:

Anisotropic hollow magnet is fixed and isotropic magnet is moved into the anisotropic magnet with initial velocity V.
2.7.3.1. Polarities of anisotropic magnetic field and isotropic magnetic field are in same directions:

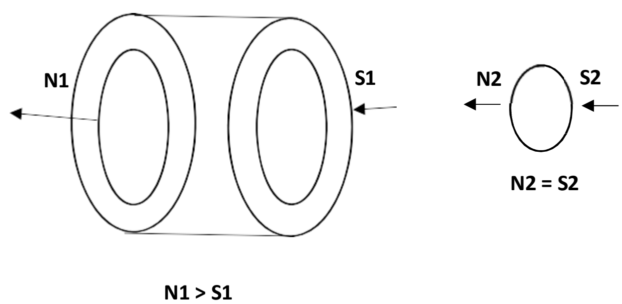

Figure 20: A permanent anisotropic hollow magnet that produces an unbalanced magnetic field where the north pole is stronger than the south pole. Longer arrows represent regions with higher magnetic field strength (N1>S1). The author predicts that there will be no gain in velocity as isotropic magnet moves through the loop.

For the nonmoving anisotropic magnet, it is assumed that north pole is stronger than the south pole (See Figure 20). The author predicts that plane of isotropic loop will align with left most plane of the anisotropic magnet in such a way that N2 is closest to N1.

2.7.3.2. Polarities of anisotropic magnetic field and isotropic magnetic field are in different directions:

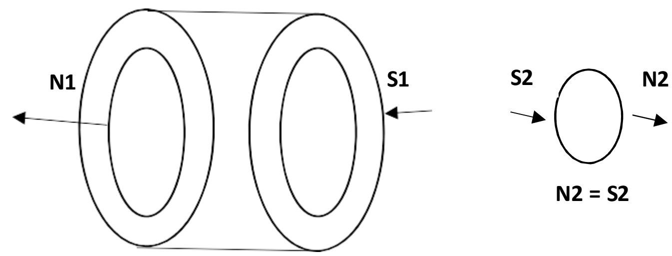

Figure 21: A permanent anisotropic hollow magnet that produces an unbalanced magnetic field where the north pole is stronger than the south pole. Longer arrows represent regions with higher magnetic field strength. The author predicts that there will be no gain in velocity.

The small loop will be repelled to the right as it moves from S1 to N1 (See Figure 21). As it leaves the anisotropic magnet, it will be repelled to the left. The author predicts that there will not be any gain in velocity as the small loop leaves the large loop. The small loop will be repelled to the left and to the right as it enters and leaves the large loop.

2.7.4. Anisotropic Hollow Magnet and anisotropic moving Magnet:

2.7.4.1. Polarities of stationary anisotropic magnetic field and moving anisotropic magnetic field are in same directions:

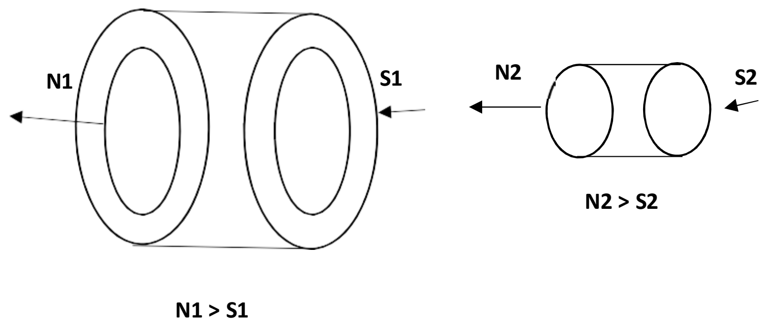

Figure 22: In the setup shown in the figure poles of anisotropic moving magnet is aligned with the poles of anisotropic hollow stationary magnet. The plane of the left end of the moving magnet will align with the plane of the left end of the hollow magnet.

The author predicts no gain in velocity as the small anisotropic magnet moves through the large anisotropic magnet (Figure 22). The magnetic field N2 will align with magnetic field N1. There is an equilibrium point where the magnets do not move at all.

2.7.4.2. Polarities of stationary anisotropic magnetic field and moving anisotropic magnetic field are in opposite directions:

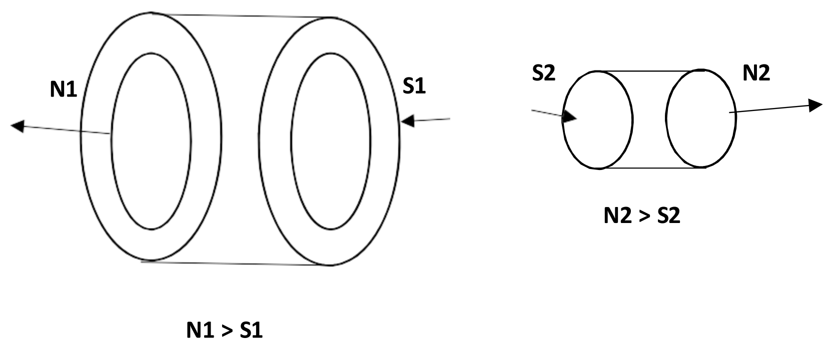

Figure 23: In the setup shown in the figure poles of anisotropic moving magnet is not aligned with the poles of anisotropic hollow stationary magnet. As the anisotropic moving magnet moves through and passes the anisotropic stationary magnet, it will be repelled to the right and after that it will be repelled to the left. There is no equilibrium point and there will be no gain in velocity.

The scenario is presented in Figure 23. The small anisotropic magnet will slow down as it moves through the large hollow anisotropic magnet. It will slow down the most as N2 approaches N1 from right to left. Then the small magnet will accelerate the most as N2 leaves N1. The author predicts no gain in velocity.

2.8. Accelerating anisotropic permanent magnetic motor

2.8.1. Coriolis torque motor using anisotropic permanent magnet:

Based on section 2.7, designs and ideas proposed in sections 2.4, 2.5 and 2.6 are incorrect.

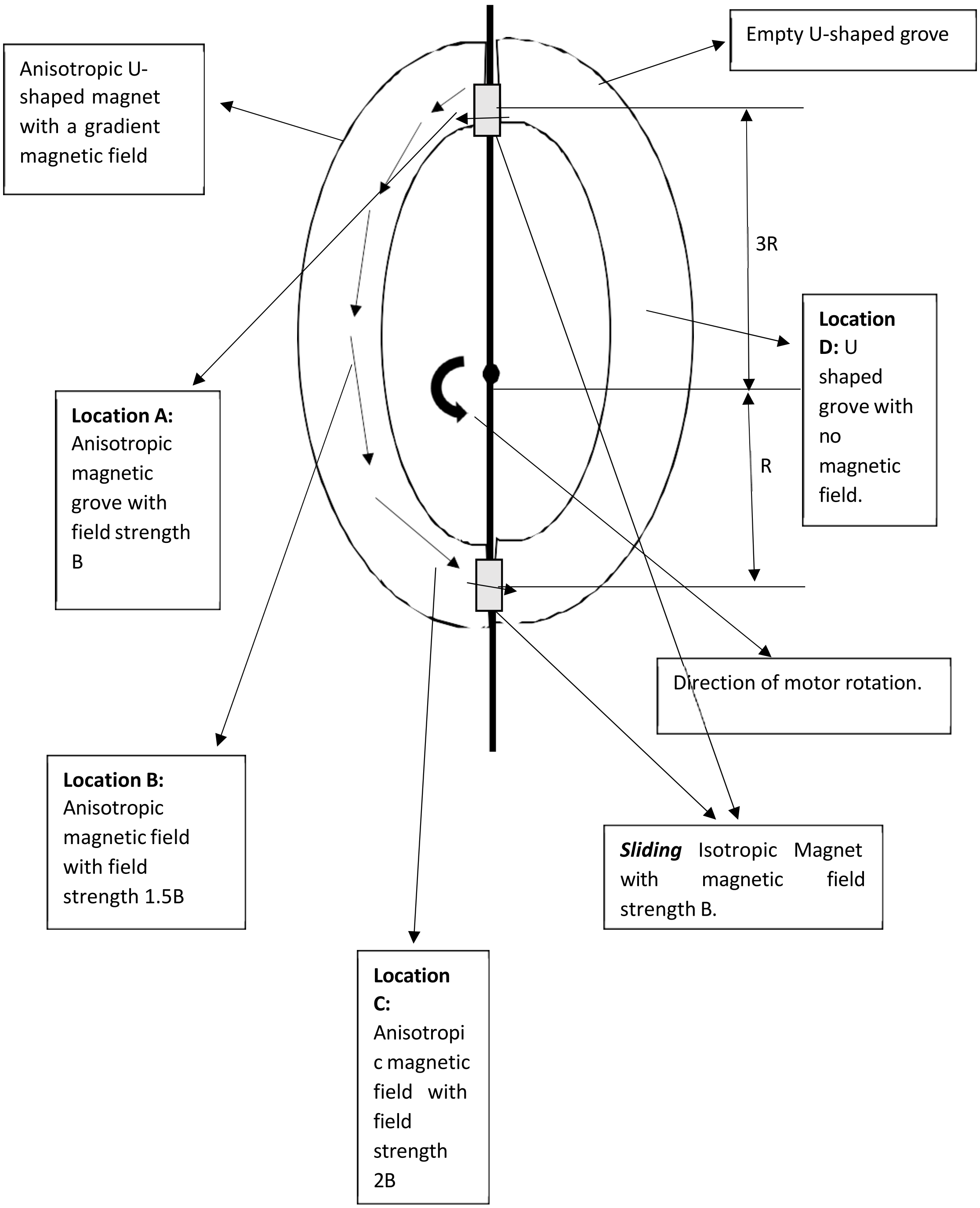

Figure 24: The above diagram illustrates a design that will generate torque without external source of energy. A more detailed description of how this system will generate perpetual motion is described in the paragraph below. Shortly, when the rod is oriented as shown in the figure, anticlockwise torque is given by the function f(B,B)×3R and clockwise torque is given by the function f(B,2B)×R. So net torque will be anticlockwise with the value (f(B,B)×3R- f(B,2B)×R).

Figure 24 illustrates a working principle for a perpetual torque generator without external energy. The crux of the idea uses four principles that happen simultaneously:

2.8.1.1. An increasing magnetic force as the isotropic magnet moves from location A to location C.

2.8.2.2. Decreasing Torque arm from 3R to R as the isotropic magnet moves from location A to location C.

2.8.3.3. Solving the problem of getting isotropic moving magnet out of equilibrium position at location C by adding another magnet that pushes the magnet in equilibrium out of location C.

2.8.4.4. Positive Torque difference as torque that is generated to enter Location A is greater than the negative torque needed to get the object out of Location C.

For the motor to work, it is necessary that (f(B,B)×3R- f(B,2B)×R) is positive. (Can such a function exist? The author thinks such a function exists and is possible. Even though this paper gives only a qualitative explanation, the author thinks that a quantitative explanation is possible.). Otherwise, the motor will be stuck at a position where the shaft is vertical.

Now, the author is going to discuss two scenarios:

1. When the rotating shaft is oriented along the line connecting location A and location C.

2. When the rotating shaft is oriented along the line connecting location B and location D.

1. The rotating shaft is oriented along the line connecting location A and location C: The first scenario can be further divided into two sub-scenarios: 1. When the moving isotropic magnet is a little inside the non-moving anisotropic magnet at location C: In this case, the force on the rotating shaft at location C is to the right. The total torque is additive. The formula for total torque is (f(B,B)×3R+ f(B,2B)×R). 2. When the moving isotropic magnet is a little outside the non-moving anisotropic magnet at location C: The formula for total torque is (f(B,B)×3R- f(B,2B)×R).

2. The rotating shaft is oriented along the line connecting location B and location D: In this orientation, there is no resistive torque and the motor rotates in a counter clockwise direction.

A potential drawback of the design is that the isotropic magnet can collide with the walls of anisotropic magnet. This can be prevented by adding wheels to the isotropic magnet. Another problem is friction generated as the isotropic magnet slides along the rotating shaft. This can also be prevented by adding a wheel that is in contact with the shaft.

2.8.2. Anisotropic permanent magnetic motor

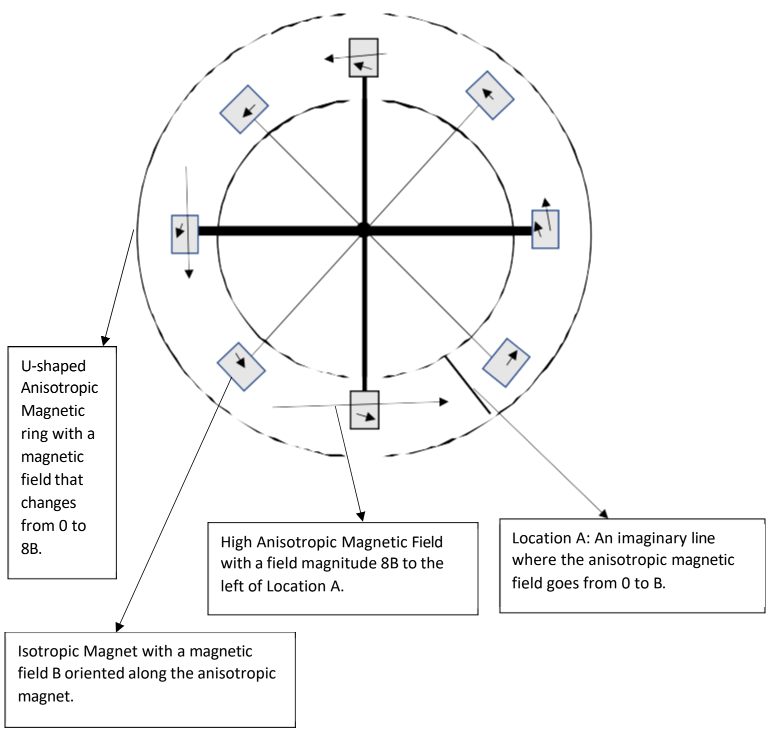

Figure 25: In the above diagram, anisotropic U-shaped magnet has a tangential gradient magnetic field that changes from 0 to 8B. There are 8 small isotropic magnets with magnetic field B that are aligned in the direction of anisotropic magnet. These 8 small magnets are connected to the axis of rotation by 8 radial shafts. All the eight shafts generate anti-clockwise torque at the positions depicted in the motor. There is an orientation of these shafts that will produce a negative torque in one of these isotropic magnets. This happens when one of the isotropic magnets is in location A and crosses the line where the magnetic field goes from 8B to 0. But the negative torque in one of the shafts is overcome by positive torque in the remaining 7 shafts.

The author wants to admit that he may or may not have thought about the particular design of motor out of his own effort. He had thought about a mechanism to get "Coriolis torque motor using anisotropic permanent magnet" working (design proposed in section 2.8.1.). He then went shopping for copper coil that can be used to make an electromagnet to test some of the ideas he had generated. He could not get to any shop that had a copper coil he was looking for. In one of the shops, the shop keeper showed a small toroid, an inch in diameter, that was attached to a circuit board. The author does not know why the shop keeper would show a coil that is part of the circuit board. The coil he showed can't be sold separately as an electromagnetic coil. The toroidal coil may or may not have led to the design proposed in this section 2.8.2. But the idea presented in this section combines a toroidal coil with motor design suggested in section 2.8.1. So, the author definitely wants to take partial credits for thinking of the motor and he may or may not deserve full credits for thinking of the design for the motor.

The design proposed in Figure 25 works based on the idea of anisotropic magnetic field and how such a magnetic field can be used to generate perpetual motion. There is an orientation of the radial shafts that produces worst case scenario for the design proposed. In that orientation, one of the radial shaft transitions form an anisotropic field strength of 8B to an anisotropic field strength of 0 at Location A. In such an orientation, there is a clockwise torque generated that can stall the motor. Stalling does not happen because there are lot more radial shafts generating anticlockwise torque. Thus, a method has been found to deal with the worst-case scenario. In all other scenarios not discussed above, there are anti-clockwise torques in all radial shafts. So, the author's conclusion is that the design proposed in Figure 25 will work.

Conclusion:

This article discusses ways to generate energy without need for external energy source. To the best of author's reasoning ability, the design stated in the article should work. If there is a logical flaw in the design, the author would like to know about it. The author thinks that such a criticism, along with the ideas proposed in this article, would make a good discussion question in scientific literature. The author would really apologize for wasting your time if the ideas stated in this work is already known to the world. The author does not know whether there is any other prior work that has built what has been stated in this article. If there is a system or procedure that provides recognition for reinventors, the author would appreciate any reward or recognition. If there is no such organization, the author would suggest setting up such a system that would recognize works of reinventors. The author has not suggested any references throughout the article. He would like to cite three works that was helpful in shaping himself [1-3].

Acknowledgment:

The author would be pleasantly surprised if the ideas stated in the paper works. The author would be even more surprised if he is the first person to state such ideas. If the ideas stated in the paper have been left hidden for reinvention purposes, the author would like reinvention credits. If a system is not set up for reinventors, he would recommend setting up a system. He is looking for active collaborators to carry out various ideas stated in this paper, irrespective of whether the idea is new or old.

Justification:

The author got a correspondence from journal stating that references are missing. He has not read any papers of relevance that he thinks is crucial for the work stated in this article. There might be people who would ask the justification or the cost for reinventing the wheel (So, the author thinks that this work might be a reinvention.). The author saw a cartoon about someone reinventing the wheel. Most of the people in the world would only get a chance to reinvent what has been done. He would like to apologize for any inconvenience caused.

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