Law Physics Quantum (LPQ)

Legal and contractual matters of using this software:

Dear user, welcome to your favorite website. Thank you for choosing this website as your personal advisor in science (physics, mechanics, mathematics).

In this scientific software, if you want to move a moving particle on a path with the speed of light and this type of movement has permanent motion relative to a fixed point (origin of coordinates), you can use this software for free (subject to Use the following criteria on your personal computer. This software is the basic software for preparing your personal software.

Criteria:

The user is obliged to use the LPQ[1] software through the website http://www.p3m.ir and through the link on this site when he is busy with his research and issues on his personal computer.

By choosing a point in space with the coordinates $A\left|\begin{matrix}x\\y\\z\end{matrix}\right.$ by the user, the output of the computer is 6 angles as cosine.

Compliance with all international property rights.

Any use of scientific, cultural, game, entertainment, entertainment, etc. software is allowed only on your personal computer for free.

Using the software for any commercialization and sale and even copying is prohibited and in case of non-compliance; Legal prosecution.

The user is responsible for applying the relevant formulas and the LPQ site has no responsibility in this regard and is only responsible for the formulas provided.

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Image of moving velocity on (x) axis = Vx

Image of moving velocity on axis (y) = Vy

Image of moving velocity on axis (z) = Vz

Angle ($\overline{oA}$) to the axis (ox) = (αx)

Angle ($\overline{oA}$) to the axis (oy) = (αy)

Angle ($\overline{oA}$) to the axis (oz) = (αz)

Angle (oA)‾ to the plane (oxy) = (αxy)

Angle (oA)‾ to the plane (oxz) = (αxz)

Angle (oA)‾ to the plane (oyz) = (αyz)

Basic information before this software

We know that the angles related to quantum mathematics are researched and used based on the angles of the sphere.

[1] Low Physics Quantum (LPQ)

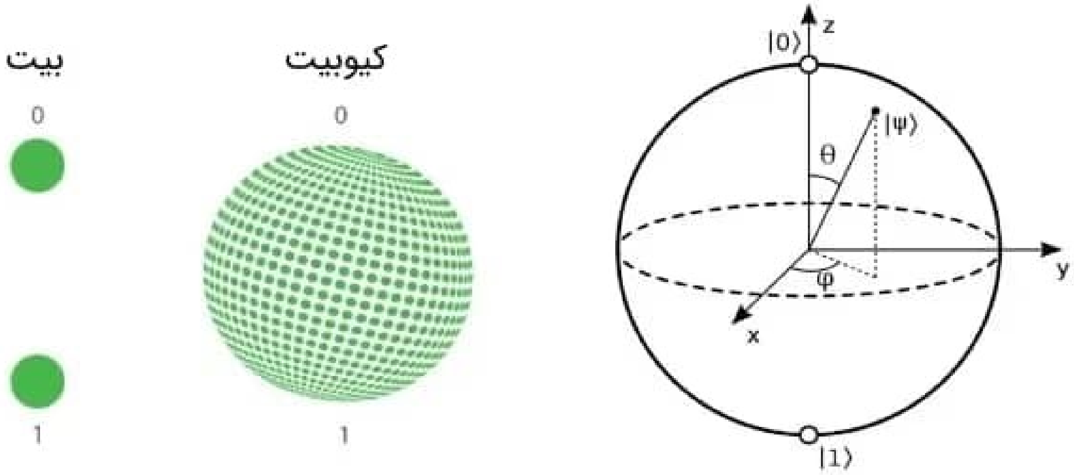
Bloch Sphere

For an intuitive understanding of the state of a qubit, it can be convenient to represent it on a Bloch sphere. In fact, a qubit can occupy any place on the surface of the Bloch sphere at the same time. While a classical bit has only two values 0 and 1 on the poles of the Bloch sphere.

By defining the coefficients α and β in the following form, the state of a qubit can be displayed on the Bloch sphere. We remind you that before measuring the system, the location of the qubit can be anywhere on the surface of the Bloch sphere. In fact, by measuring, i.e. determining the coefficients, the exact location and position of the qubit can be determined.

$\alpha=\cos(\theta2)$ $\alpha=\cos(\theta2)$

$\beta=ei\varphi\sin(\theta2)$ $\beta=ei\varphi\sin(\theta2)$



Now it seems that the answer to the question mentioned in the introduction of the text can be given according to the above explanations and the green sphere in the above figure. Yes, you guessed it, parallel processing and more speed!

The laws of quantum physics

(Laws of subatomic motions)

Review:

The common chapter of the three classical theories, quantum mechanics and general relativity can be proved in three chapters separately, and then the relationship between the three chapters can be presented.

Proving the classical theory: Proving the trigonometry of a point in space or proving the hexadecimal relations assuming (x,y,z)

Proof of the relevant formulas in terms of speed.

A: Constant speed

B: variable speed

Quantum theory: integration of three classical theories, general relativity and stable dynamics (the fifth dimension)

Introduction:

A theory that can explain all laws and phenomena in the world can include quantum gravity.

The integration of quantum mechanics and general relativity cannot be justified with today's science and knowledge, but in order to fully explain quantum gravity, it is necessary to present a new theory that is the intersection of 3 classical theories, quantum mechanics and general relativity.

Proof of classical theory:

Proof of six angles in space in terms of (x,y,z) relative to the point (o). More explanations in this field are proven in the trigonometry section of www.p3m.ir website.

The summary of the six formulas is as follows:

1) $\cos(\alpha x)=\frac{x}{\sqrt{x^2+y^2+z^2}}$
2) $\cos(\alpha y)=\frac{y}{\sqrt{x^2+y^2+z^2}}$
3) $\cos(\alpha z)=\frac{z}{\sqrt{x^2+y^2+z^2}}$
4) $\cos(\alpha xy)=\frac{\sqrt{x^2+y^2}}{\sqrt{x^2+y^2+z^2}}$
5) $\cos(\alpha xz)=\frac{\sqrt{x^2+z^2}}{\sqrt{x^2+y^2+z^2}}$
6) $\cos(\alpha yz)=\frac{\sqrt{y^2+z^2}}{\sqrt{x^2+y^2+z^2}}$

Proof of speed formulas:

A: Constant speed: on a constant path on the curve $(\overrightarrow{Vx^2} + \overrightarrow{Vy^2} + \overrightarrow{Vz^2} = C^2)$

The above relationship is related to the spatial shape of the sphere. It is also true in the line equation

B: Variable speed: due to variable speed, we should note that the changes of all three speed parameters depend on the question asked. that's mean :

$$x = F(t) \Rightarrow \frac{dx}{dt} = V_x = F'(t)$$

$$y = G(t) \Rightarrow \frac{dy}{dt} = V_y = G'(t)$$

$$z = H(t) \Rightarrow \frac{dz}{dt} = V_z = H'(t)$$

General solution for solving variable velocity in 3D space (oxyz)

The proof of the variable speed formula is as follows:

We know that the distance of the point (A) in space to the point (o) of the coordinate origin is equal to $\overline{oA} = \sqrt{x^2 + y^2 + z^2}$This relationship is true for all curves in space.

To calculate the speed on the line $(\overline{oA})$, it is sufficient to take the differential relation from the sides and divide the sides of the relation by (dt).

$$\frac{d(\overline{oA})}{dt} = \overrightarrow{V(oA)} = \frac{(2.x.{}^{dx}/_{dt} + 2.y.{}^{dy}/_{dt} + 2.z.{}^{dz}/_{dt})}{2.\sqrt{x^2 + y^2 + z^2}} = \frac{(x.Vx + y.Vy + z.Vz)}{\sqrt{x^2 + y^2 + z^2}}$$

$$\boldsymbol{\overrightarrow{V(oA)}} = \frac{\boldsymbol{(x.Vx + y.Vy + z.Vz)}}{\boldsymbol{\sqrt{x^2 + y^2 + z^2}}}$$

The speed relationship is true for all curves.

Now we depict the speed relationship in space on three axes (ox), (oy), (oz) and three coordinate planes (oxy), (oxz), (oyz).

Velocity image on axis (ox)

$$\vec{V}(\alpha x) = \overrightarrow{V(oA)}.\cos(\alpha x)$$

1- $\vec{V}(\alpha x) = \frac{(x.Vx+y.Vy+z.Vz)}{\sqrt{(x^2+y^2+z^2)}} \cdot \frac{x}{\sqrt{(x^2+y^2+z^2)}} = \frac{x.(x.Vx+y.Vy+z.Vz)}{(x^2+y^2+z^2)}$ $\qquad \boldsymbol{\vec{V}(\alpha x)} = \frac{\boldsymbol{x.(x.Vx+y.Vy+z.Vz)}}{\boldsymbol{(x^2+y^2+z^2)}}$

2- $\vec{V}(\alpha y) = \frac{y.(x.Vx+y.Vy+z.Vz)}{(x^2+y^2+z^2)}$ velocity image on axis (oy)

3- $\vec{V}(\alpha z) = \frac{z.(x.Vx+y.Vy+z.Vz)}{(x^2+y^2+z^2)}$ $\boldsymbol{\vec{V}(\alpha z) = \overrightarrow{V(oA)}.\cos(\alpha xy)}$ velocity image on axis(oz)

4- $\vec{V}(oxy) = \frac{(x.Vx+y.Vy+z.Vz)}{\sqrt{x^2+y^2+z^2}} \cdot \frac{\sqrt{x^2+y^2}}{\sqrt{x^2+y^2+z^2}} = \frac{(x.Vx+y.Vy+z.Vz)(\sqrt{x^2+y^2})}{(x^2+y^2+z^2)}$ velocity image on (oxy) screen

5- $\vec{V}(oxz) = \frac{(x.Vx+y.Vy+z.Vz)(\sqrt{x^2+z^2})}{(x^2+y^2+z^2)}$ velocity image on (oxz) screen

6- $\vec{V}(oyz) = \frac{(x.Vx+y.Vy+z.Vz)(\sqrt{y^2+z^2})}{(x^2+y^2+z^2)}$ velocity image on (oyz) screen

$$\frac{\vec{V}(\alpha y)}{\vec{V}(\alpha x)}=\frac{y}{x} \ , \ \frac{\vec{V}(\alpha z)}{\vec{V}(\alpha x)}=\frac{z}{x} \ , \ \frac{\vec{V}(\alpha z)}{\vec{V}(\alpha y)}=\frac{z}{y}$$

Linear equations:

$\frac{z}{x}=\frac{z}{y}.\frac{y}{x} \Rightarrow tan\theta = tan\lambda \, . tan\sigma$

$$tan\,\boldsymbol{\theta} = tan\,\boldsymbol{\lambda}\,.\,tan\,\boldsymbol{\sigma}$$

Dynamic trigonometry in space

In order to pose the problem, five of the above six parameters are required as the assumption of the problem. One of the following three rows:

1- (x , y , z , Vx , Vy)
2- (x , y , z , Vx , Vz)
3- (x , y , z , Vy , Vz)

The above relationships are true in all forms of space engineering. It is not true only in the shape of the sphere's spatial geometry. Because the velocity vector in space is perpendicular to the radius of the sphere ($\overline{oA}$) and the image of the velocity vector in space on the radius of the sphere ($\overline{oA}$) is zero. $\overrightarrow{\boldsymbol{V(oA)}} = \mathbf{0}$

Therefore, the above relations are true under the direction of Korea.

$$\frac{\boldsymbol{Vz}}{\boldsymbol{z}}=\frac{\boldsymbol{Vy}}{\boldsymbol{y}}=\frac{\boldsymbol{Vx}}{\boldsymbol{x}}$$

Proving the laws of quantum physics:

Before proving the laws of quantum physics, it is first necessary to check the distances between the points on the curve on computers (super technology) and then proceed to present the relevant formula and method.

In order to draw a curve by computer, the closer the points on the curve are, the more accurately the curve is drawn. In advanced computers (supercomputers) with variable speed, computer implementation to draw the opposite shape does not cover some points. Like points b, c, e, f, h, i. To solve this problem, it is necessary to define the formula of stable dynamics (fifth dimension) for the computer.

In the formula of stable dynamics (the fifth dimension) we have two types of lines at any moment.

The first line (($\overline{o\,o'}$) point (o) origin of coordinates, point (o') origin of moving coordinates.

The second line ($\overline{o\,'A}$) is the point (A), the point on the curve.

With the coordinates of three points (o, o', A), two lines can be defined for the computer at any moment.

In the plane (oxy) $A\begin{vmatrix} x \\ y \end{vmatrix}$, $o'\begin{vmatrix} \alpha \\ \beta \end{vmatrix}$, $o\begin{vmatrix} 0 \\ 0 \end{vmatrix}$

$$\alpha = \frac{Vy.(x.Vy + y.Vx)}{(Vx^2 + Vy^2)} \quad , \quad \beta = \frac{Vx.(x.Vy + y.Vx)}{(Vx^2 + Vy^2)}$$

Having (α, β), we build a dual-core (CPU) in the computer hardware. A kernel corresponding to the line($\overline{o\,o'}$) and a kernel corresponding to the line ($\overline{o\,'A}$) in the (oxy) plane. By making a dual-core CPU in the above method, any speed will be possible to cover the points (b, c, e, f, h, i) and therefore the error will be zero in the linear method. If it is important to cover the points in the three-dimensional space (oxyz), it is necessary to have the coordinates of the points (o, o', A) in the plane (oxz).

$A\begin{vmatrix} x \\ z \end{vmatrix}$ $o'\begin{vmatrix} \alpha \\ \gamma \end{vmatrix}$ $o\begin{vmatrix} 0 \\ 0 \end{vmatrix}$

β and γ are presented in the above formulas.

Proof of the formulas (α, β, γ) based on the proof of stable dynamics (fifth dimension)

[Proof of stable dynamics (fifth dimension) is available at www.p3m.ir.]

Summary of stable dynamics formula (fifth dimension):

In the triangle we have $\left(\overset{\triangle}{o\,o\,'A}\right)$.

on page (oxy)

$\overrightarrow{\boldsymbol{V(oA)}}.(\overline{o\,o'}) = \vec{V}y.\overline{oH} + \vec{V}x.\overline{oH} \Rightarrow$ $\boldsymbol{o\,o' = \frac{\overrightarrow{Vy}.x + y.\overrightarrow{Vx}}{\sqrt{Vx^2 + Vy^2}}}$

In the triangle we have $\left(\overset{\triangle}{o\,o\,'D}\right)$.

$$\overline{oD} = \alpha = \overline{oo'}.cos\left(\frac{\pi}{2} - \theta\right)$$

$$\overline{oD} = \beta = \overline{oo'}.sin\,(\frac{\pi}{2} - \theta)$$

$$\begin{cases} \overline{oD} = \alpha \\ \overline{o'A} = \beta \end{cases}$$

$$\overline{oD} = \overline{oo'}\,.sin\,\theta = \frac{\overrightarrow{Vy}.x + y.\overrightarrow{Vx}}{\sqrt{Vx^2 + Vy^2}} . \frac{\overrightarrow{Vy}}{\sqrt{Vx^2 + Vy^2}}$$

$$\boldsymbol{\overline{oD} = \alpha = \frac{(Vy.x + y.Vx).\overrightarrow{Vy}}{(Vx^2 + Vy^2)}}$$

$$\overline{oD} = \beta = \overline{oo'}\,.cos\,\theta = \frac{(Vy.x + y.Vx).\overrightarrow{Vx}}{(Vx^2 + Vy^2)}$$

γ and α in plane (oxz):

$$\gamma = \frac{(Vz.x + z.Vx).\overrightarrow{Vx}}{(Vx^2 + Vz^2)}$$

With (α, β, γ) and the coordinates of the point $A\left|\begin{matrix} x \\ y \\ z \end{matrix}\right.$, the origin of the moving coordinates, the point (o') can be calculated by computer. That is, $o'\left|\begin{matrix} (x-\alpha) \\ (y-\beta) \\ (z-\gamma) \end{matrix}\right.$

$$\begin{cases} \sin\theta = \dfrac{\tan\theta}{\sqrt{1+\tan\theta^2}} \\ \cos\theta = \dfrac{1}{\sqrt{1+\tan\theta^2}} \\ \tan\theta = \dfrac{Vy}{Vx} \\ tan\ L = \dfrac{y}{x} \end{cases}$$

Contents related to the help section

Training Software:

Dear user, you can use this software for your personal research. This software is based on quantum basic mathematics.

Types of trigonometry:

In order to use all types of trigonometry, it is enough to specify the coordinates of a point in space for the software.

Example: $A\left|\begin{matrix} 2 \\ 3 \\ 5 \end{matrix}\right.$ and then select Enter key ↵. You will immediately have six angles (types of trigonometry) at your disposal. These angles are shown as cosines

The radius of the sphere will be equal to (R):

$$R = \sqrt{(2)^2 + (3)^2 + (5)^2} = \sqrt{\mathbf{38}}$$

Constant speed of light in space:

Practice:

If we want to track the speed of point $A\left|\begin{matrix} 2 \\ 3 \\ 5 \end{matrix}\right.$ in spherical space with the speed of light (observance of the following is mandatory)

1- $(V^2x+V^2y+V^2z = C^2)$
2- Calculation of angular velocity on the space sphere $W_T = \frac{C}{\sqrt{38}}$
3- *Calculation* of angular velocity images on three coordinate planes. In this case, the spatial angular velocity will be equal to all angular velocities of the coordinate planes. that's mean : $W_T = \frac{C}{\sqrt{38}} = W_{(oxy)} = W_{(oxz)} = W_{(oyz)}$
4- *The* image of the giant spatial circle will be an ellipse in three coordinate planes.
5- By observing the above, it is possible to obtain the moving coordinates of the light on the ellipses at any moment.
6- *If* it shows zero points, these 4 points in the ellipse correspond to the coordinates of the points is $\left(\begin{vmatrix} a \\ 0 \end{vmatrix}, \begin{vmatrix} 0 \\ b \end{vmatrix}, \begin{vmatrix} -a \\ 0 \end{vmatrix}, \begin{vmatrix} 0 \\ -b \end{vmatrix}\right)$.

Quantum calculations in the framework (silicon microprocessors):

1. Radius of the space circle of hydrogen electron orbit (R=1.2) Angstroms (Å)

is.

2. The speed of the hydrogen electron on the orbit is (4000 km/sec).
3. The image of the velocity vector on the radius of the sphere is zero $[\overrightarrow{V(oA)} = 0]$

Ideal conditions and efficiency in quantum computing

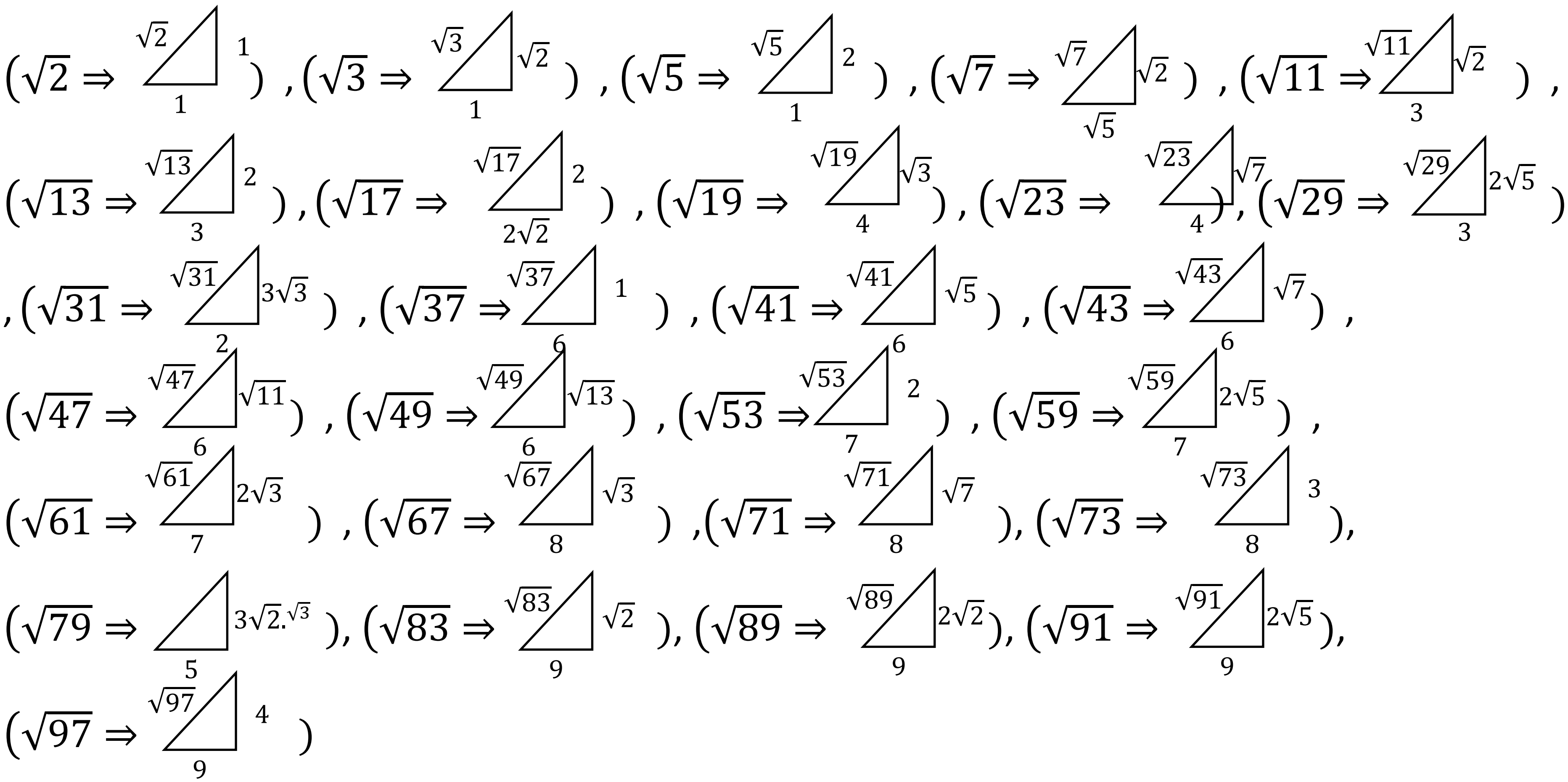
Assumption of the ideal problem in quantum computing:

- 1 mm is equal to 107 Å
- Electron orbit radius ➲ R= 1 Å
- Constant speed of light ➲ C=300,000 km/sec
- For accurate calculations, it is necessary to assume the number (π) ➲ $\pi = \frac{22}{7}$ .The math numbers made up a fraction ($\frac{a}{b}$). There's a solution to the problems on www.p3m.ir different kinds of triangles are solved as problems.
- To calculate the angular velocity, it can be written ➲ $W_T = \frac{C}{\sqrt{38}} = \frac{3*10^{18}}{\sqrt{38}}$

Then get the coordinates of the points on the ellipses.

$\sqrt{2}$, $\sqrt{3}$, $\sqrt{5}$, $\sqrt{7}$, $\sqrt{11}$, $\sqrt{13}$, $\sqrt{17}$, $\sqrt{19}$, $\sqrt{23}$, $\sqrt{29}$, $\sqrt{31}$, $\sqrt{37}$,

$\sqrt{41}$, $\sqrt{43}$, $\sqrt{47}$, $\sqrt{49}$, $\sqrt{53}$, $\sqrt{59}$, $\sqrt{61}$, $\sqrt{67}$, $\sqrt{71}$, $\sqrt{73}$, $\sqrt{79}$, $\sqrt{83}$, $\sqrt{89}$, $\sqrt{91}$, $\sqrt{97}$



Dear researcher and scientist user

It is suggested to use the drawing method as above for more accurate calculations.

1) In the above method, it is (tan α = $\frac{a}{b}$). The numerical example is solved.
2) Any type of number that is obtained as a fraction from the calculation of six types of cosines can be defined by the above drawing method for the computer.
3) The selected numbers above are prime numbers (example).
4) Prime numbers are numbers that are divisible by one and the number itself.
5) Selected prime numbers from 1 to 100 are selected.
6) Numbers higher than 100 can be defined for the computer in the above way. That is, the computer draws any number based on the drawing number ($\sqrt{2}$, $\sqrt{3}$, $\sqrt{5}$, $\sqrt{7}$). Drawing numbers have two options:

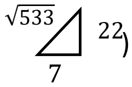
    A: It is drawn directly based on the numbers ($\sqrt{2}$, $\sqrt{3}$, $\sqrt{5}$, $\sqrt{7}$).) and can be seen in the above example.

    B: Based indirectly on numbers $\left(\sqrt{11}, \sqrt{13}, \sqrt{17}, \sqrt{19}, \sqrt{23}, \ldots\right)$ that the computer will automatically reach the first option in several steps.

Result:

Define the numbers ($\sqrt{2}$, $\sqrt{3}$, $\sqrt{5}$, $\sqrt{7}$) for the computer and ask the output computer to display the desired number (the chord of a right triangle) and its components, one side of a right angle is one of the numbers ($\sqrt{2}$, $\sqrt{3}$, $\sqrt{5}$, $\sqrt{7}$) and the other side of the right angle is an integer (the example is quite clear)

Therefore, according to the drawing of fractional numbers such as (a/b), the error will be zero and the other numbers presented will not be in decimal form. like a number

$(\pi = \frac{22}{7} \rightarrow$ 

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Choosing 3 coordinate axes in different sciences: (ox), (oy), (oz)

1) The choice of 3 coordinate axes in space is ($\overline{\mathrm{ox}}$), ($\overline{\mathrm{oy}}$), ($\overline{\mathrm{oz}}$)
2) Choosing 3 coordinate axes in physics: we must equate 3 coordinate axes. That is, in physics, 3 coordinate axes (C.G.S), (M.K.S), (F.P.S) are considered as basic axes in some devices. That is, there is a Length axis, a Mass axis and a Time axis. Therefore, we equate 3 axes with 3 axes ($\overline{\mathrm{ox}}$), ($\overline{\mathrm{oy}}$), ($\overline{\mathrm{oz}}$). Then we use six trigonometric relations in physics.
3) Choosing 3 coordinate axes in thermodynamics: we must set 3 coordinate axes equal to 3 coordinate axes (Pressure, Volume, Temperature). Then we use 6 trigonometric relations in thermodynamics.
4) Choosing 3 coordinate axes in electronics, mechatronics, computer, we must set the 3 coordinate axes equal to the 3 coordinate axes (Current Intensity, Voltage, Resistance). Then we use 6 trigonometric relations in electronics, mechatronics, computer.

These 3 axes and six trigonometric relationships are true in all cases of Euclidean mathematics.

In other sciences, if 3 axes are considered as indicators, they can be equated and used in the above way.