

# Definición formal

$\text{AutoPeli} = (Q, \Sigma, \delta, q_0, F)$

$Q = \{q_0, q_1, q_2, \dots, q_{54}, q_{55}, q_{R1}, q_{R2}, \dots, q_{R59}, q_{R60}\}$

$q_0 = q_0$

$\Sigma = \{f, v, an, c, ac, t, r\}$

$F = \{q_{R1}, q_{R2}, \dots, q_{R59}, q_{R60}\}$

$\delta(q_0, an) = q_1$

$\delta(q_0, c) = q_{11}$

$\delta(q_0, ac) = q_{21}$

$\delta(q_0, t) = q_{36}$

$\delta(q_0, r) = q_{46}$

$\delta(q_1, v) = q_2$

$\delta(q_1, f) = q_3$

$\delta(q_2, v) = q_{R1}$

$\delta(q_2, f) = q_{R2}$

$\delta(q_3, v) = q_4$

$\delta(q_3, f) = q_5$

$\delta(q_4, v) = q_{R3}$

$\delta(q_4, f) = q_{R4}$

$\delta(q_{50}, f) = q_{52}$

$\delta(q_{51}, v) = q_{R54}$

$\delta(q_{51}, f) = q_{R55}$

$\delta(q_{52}, v) = q_{53}$

$\delta(q_{52}, f) = q_{54}$

$\delta(q_{53}, v) = q_{R56}$

$\delta(q_{53}, f) = q_{R57}$

$\delta(q_{54}, v) = q_{55}$

$\delta(q_{54}, f) = q_{R60}$

$\delta(q_{55}, v) = q_{R58}$

$\delta(q_{55}, f) = q_{R59}$

...

# DIAGRAMA DE TRANCISIONES

