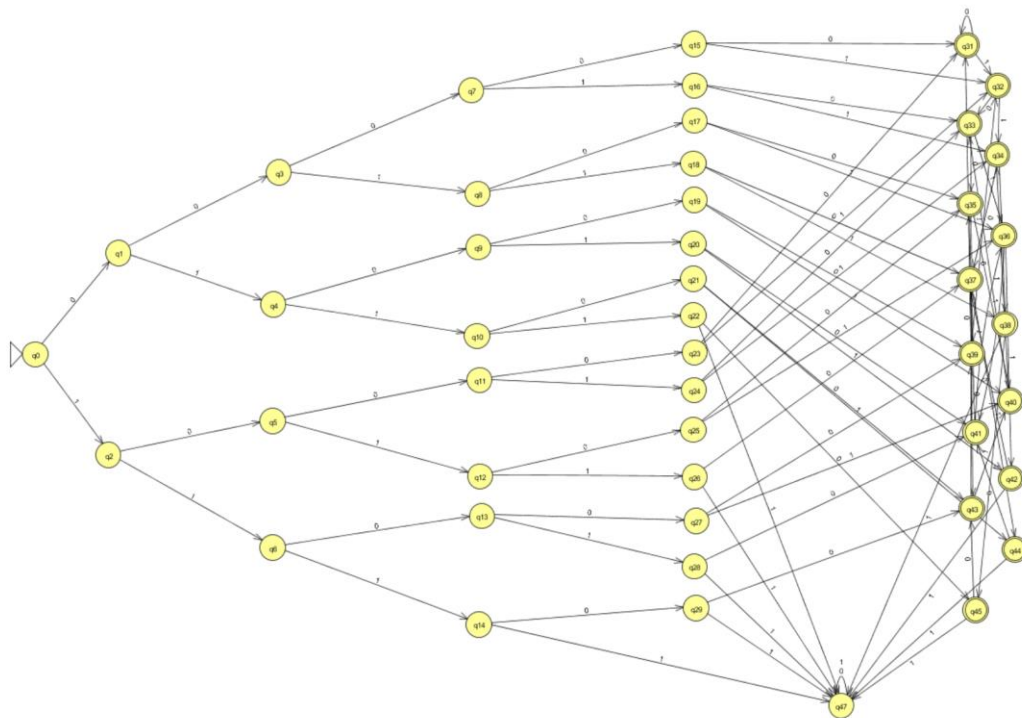


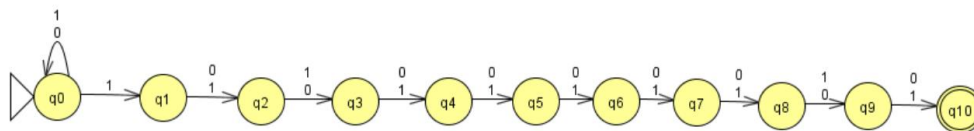
1.

2.2.5:

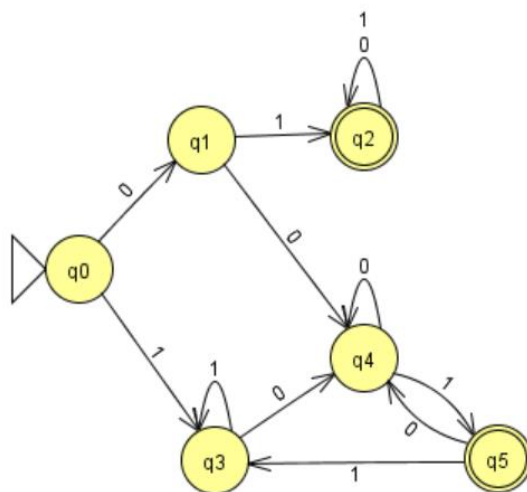
a:



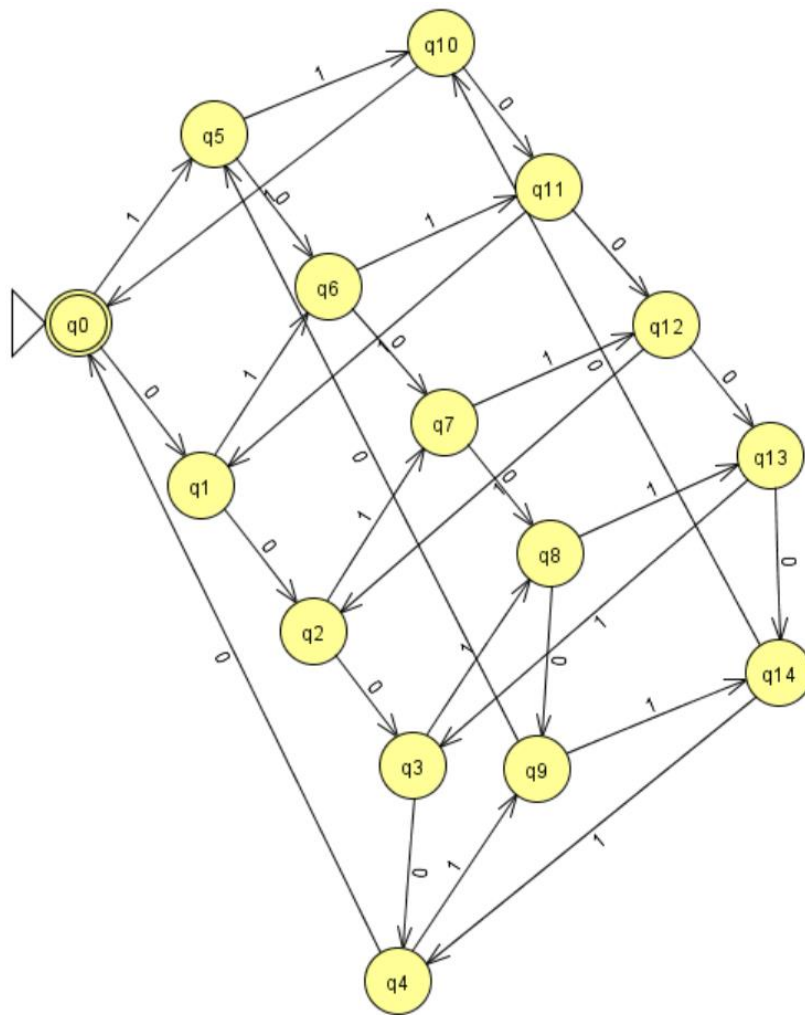
b:



c:

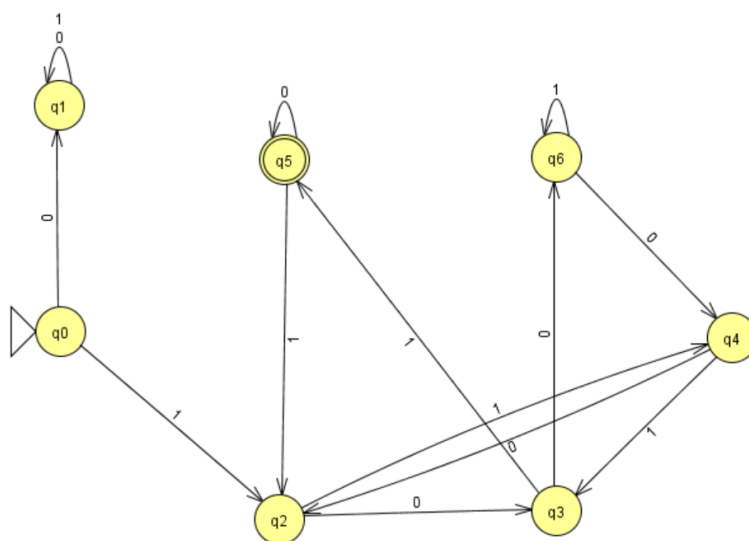


d:

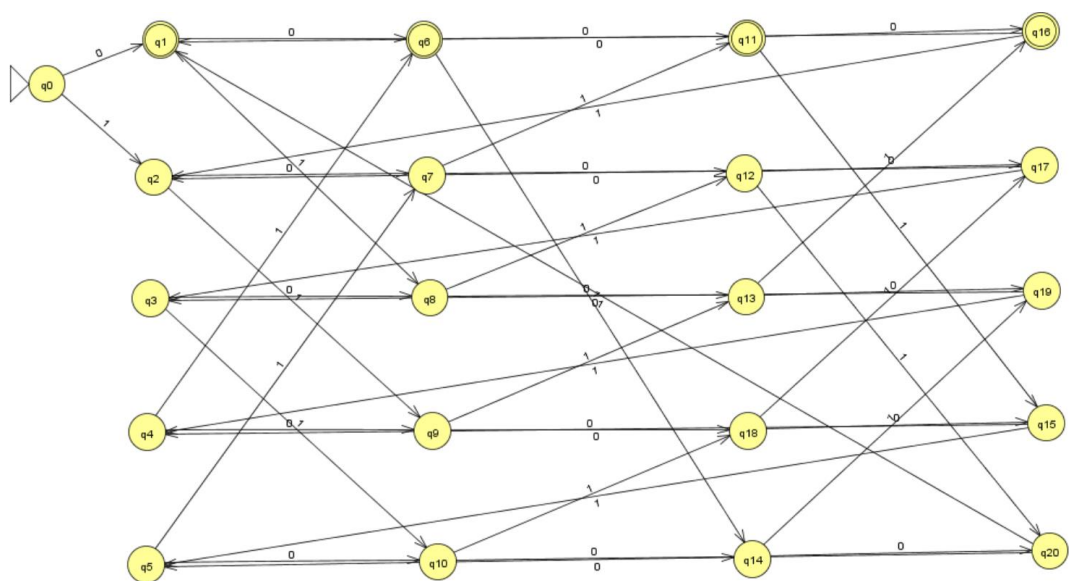


2.2.6:

a:



b:



2.2.9:

2.2.9

a)

$$\begin{aligned}\hat{\delta}(q_0, w) &= \delta(\hat{\delta}(q_0, w-a), a) \\ &= \delta(\delta(\hat{\delta}(q_0, w-a-b), b), a) \\ &\dots \\ &= \delta(\delta(\dots(\delta(q_0, z), y), x) \dots, a)\end{aligned}$$

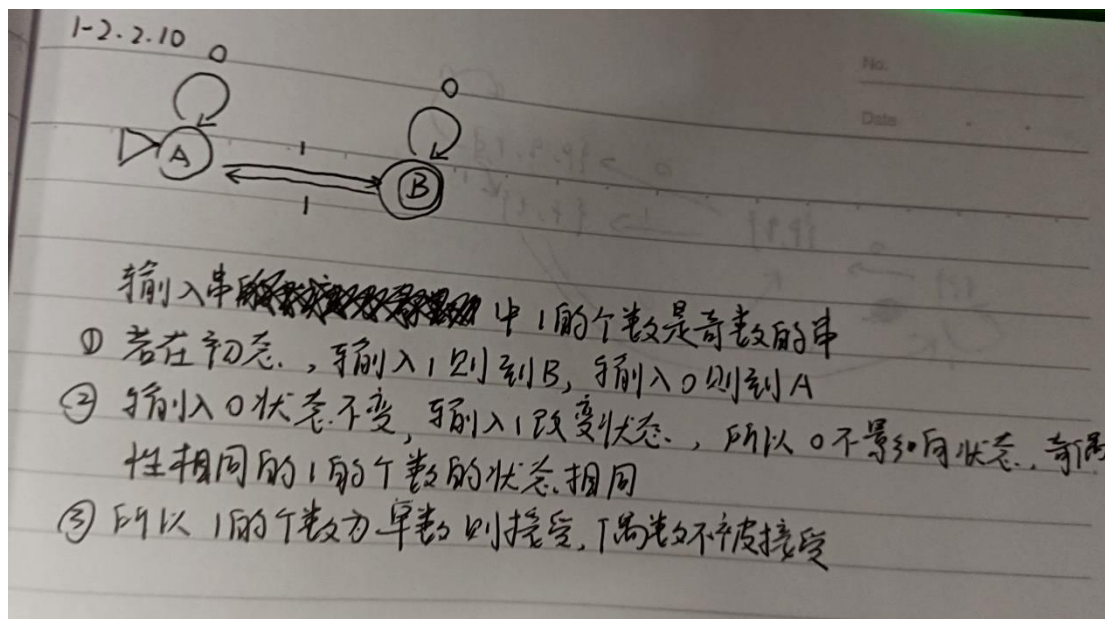
同理 $\hat{\delta}(q_f, w)$ 可写成相同形式

$$\begin{aligned}\therefore \hat{\delta}(q_0, w) &= \hat{\delta}(q_f, a) \\ \therefore \hat{\delta}(q_0, w) &= \hat{\delta}(q_f, w) \\ \text{故得证}\end{aligned}$$

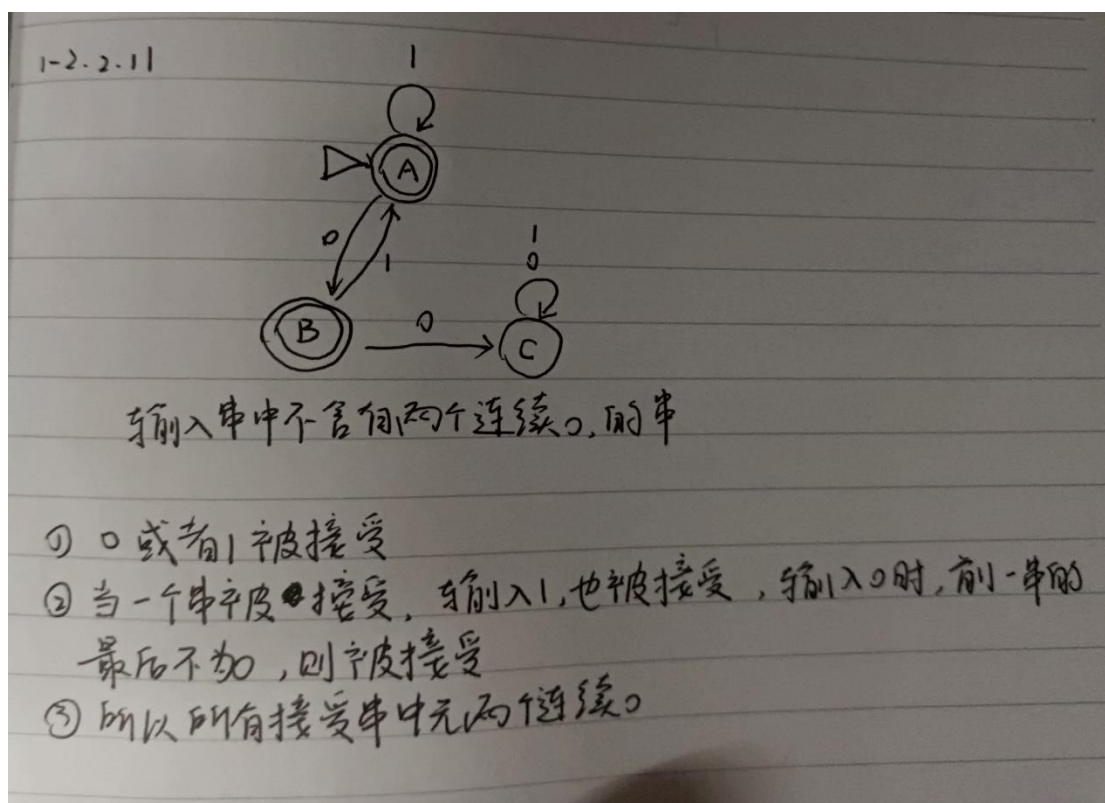
b) $\because x \in L(A)$

$$\begin{aligned}\therefore \hat{\delta}(q_0, x) &= q_f \\ \therefore \hat{\delta}(q_f, x) &= q_f \\ \hat{\delta}(q_f, x^k) &= \hat{\delta}(\hat{\delta}(q_f, x^{k-1}), x) = \dots \hat{\delta}(\hat{\delta}(\dots \hat{\delta}(q_f, x), x, \dots, x)) \\ &= q_f \\ \text{故得证}\end{aligned}$$

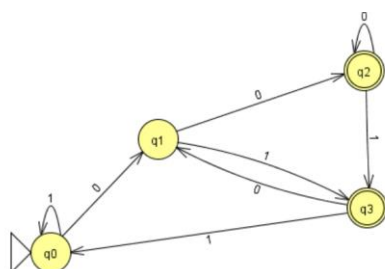
2.2.10:



2.2.11:

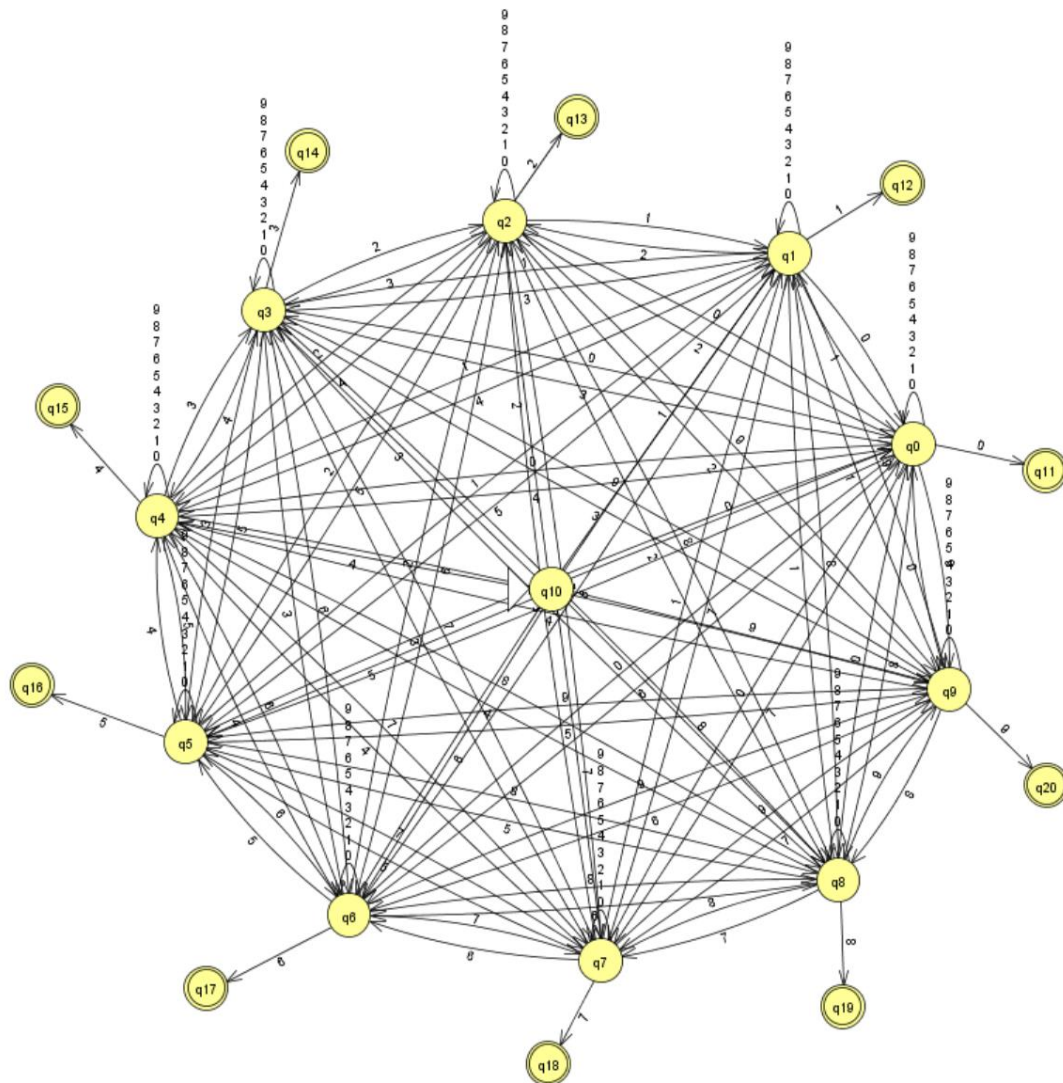


2.3.3:



2.3.4:

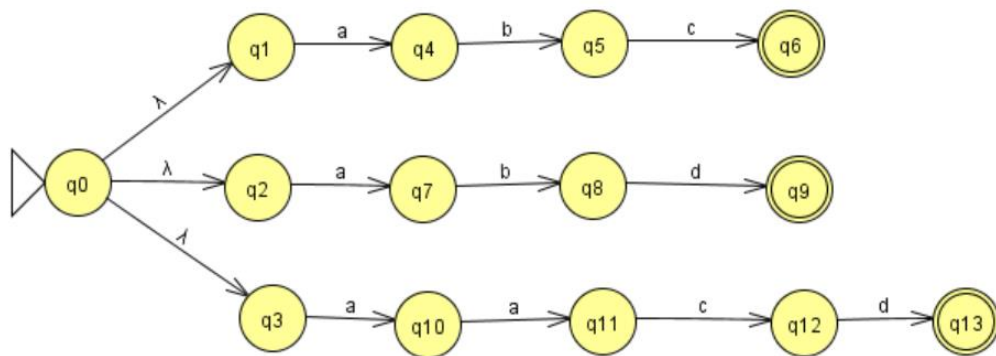
a:



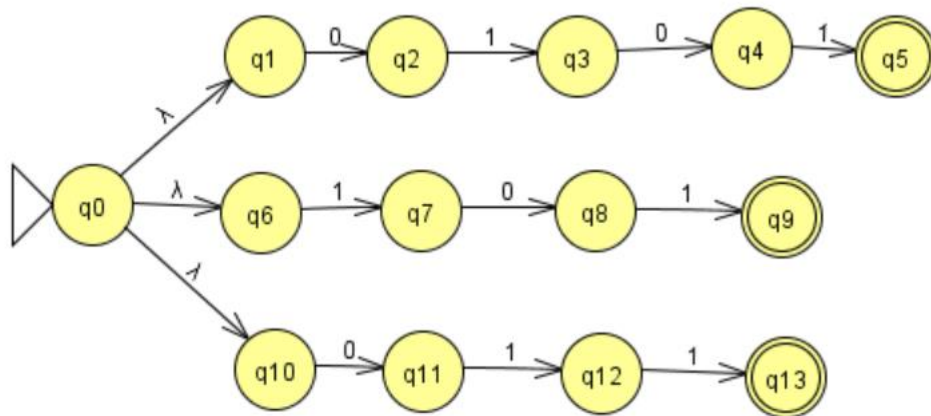
b:

2.4.1:

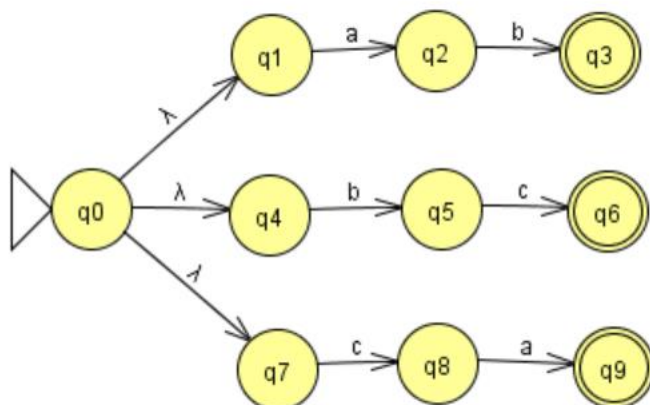
a:



b:

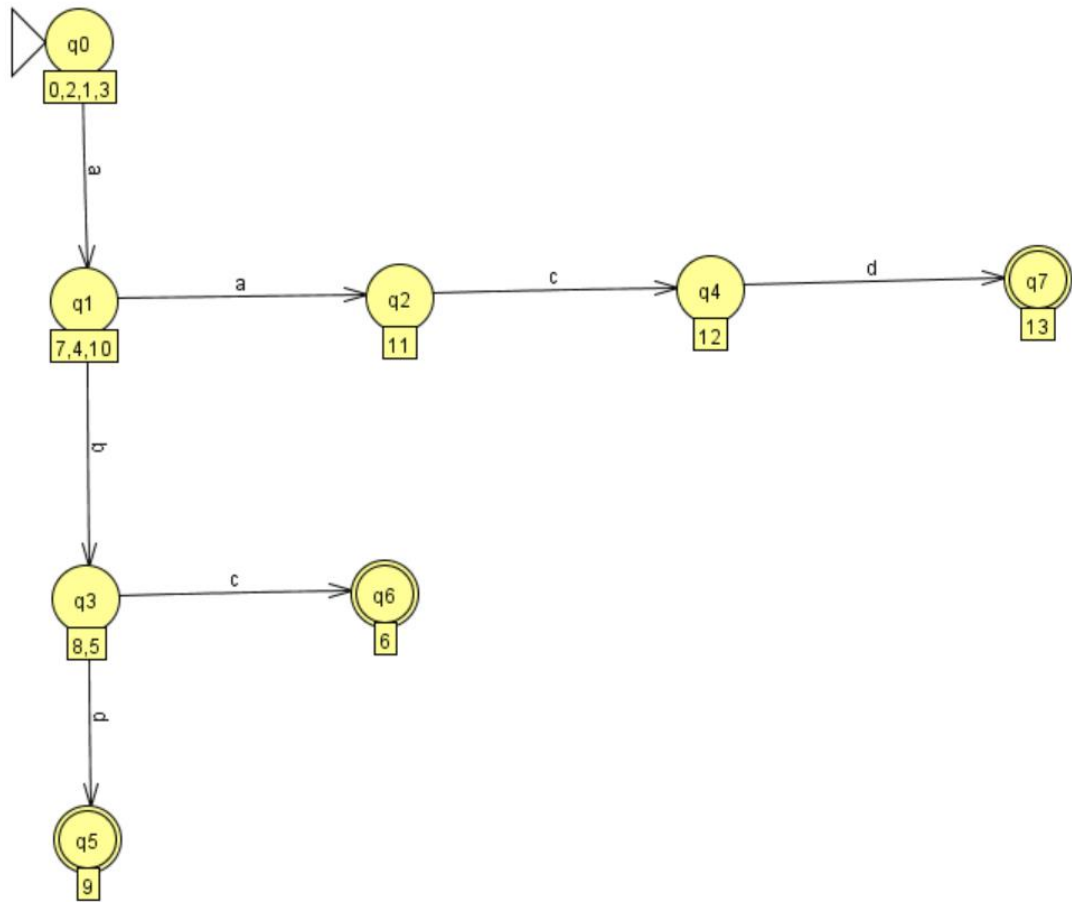


c:

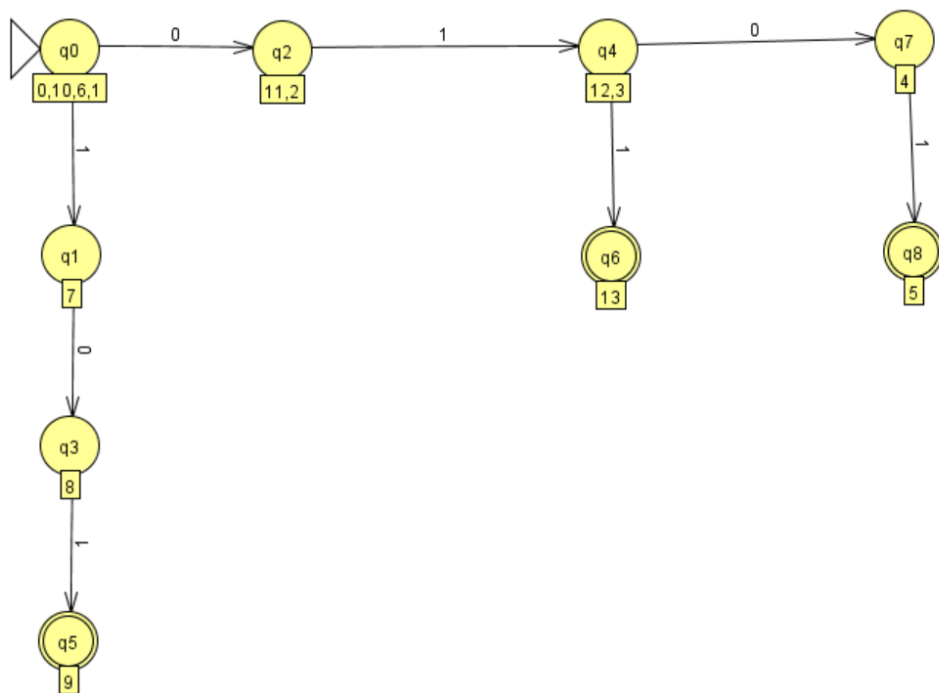


2.4.2:

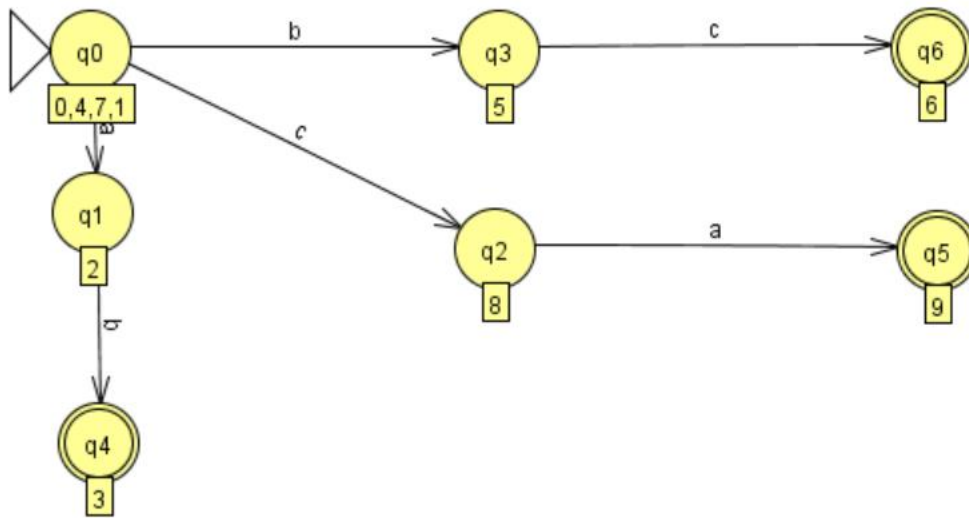
a:



b:

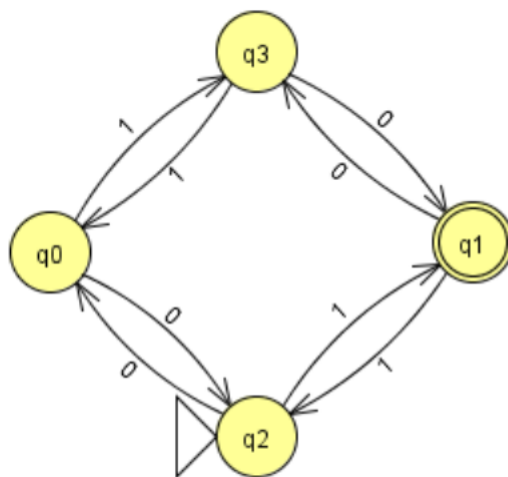


c:

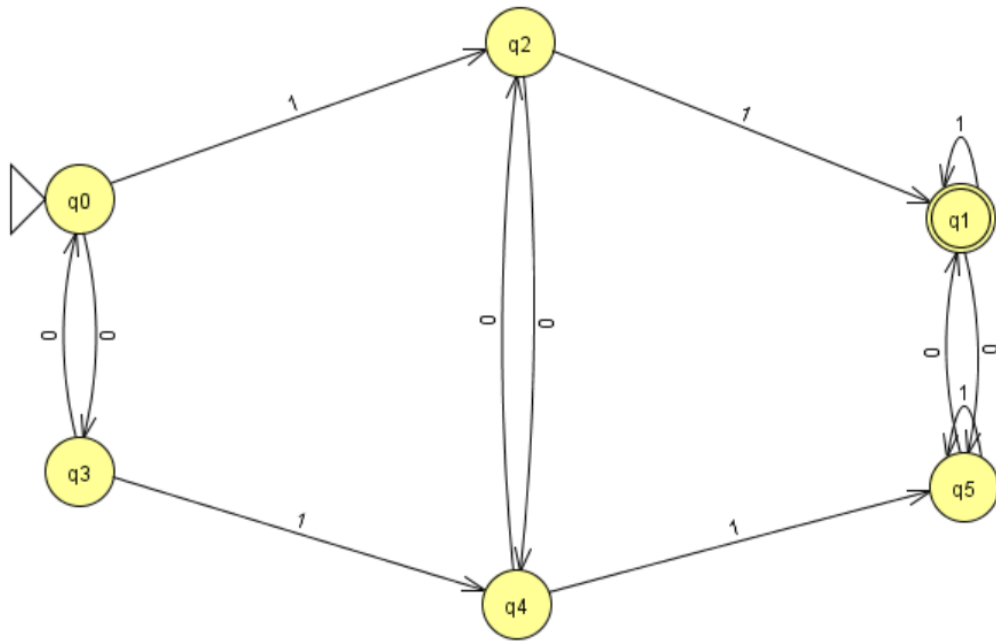


2.

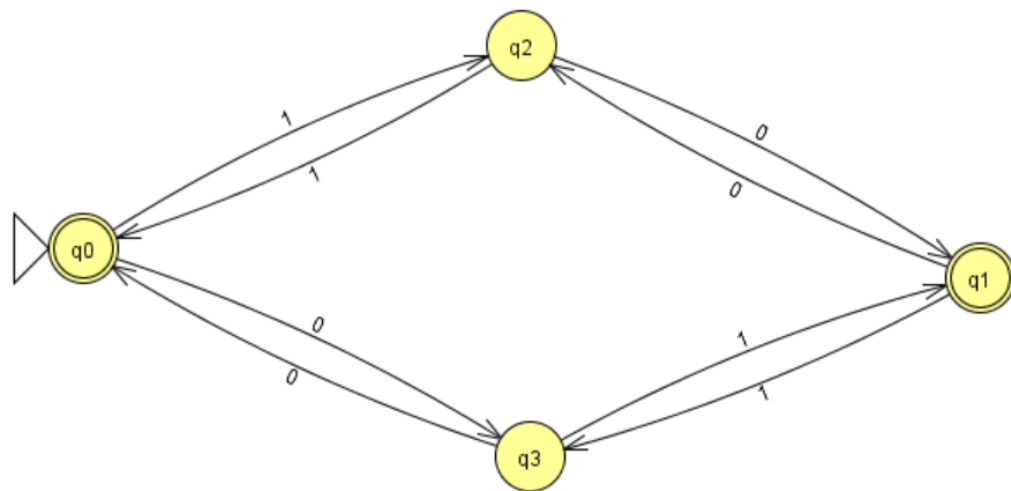
(1)



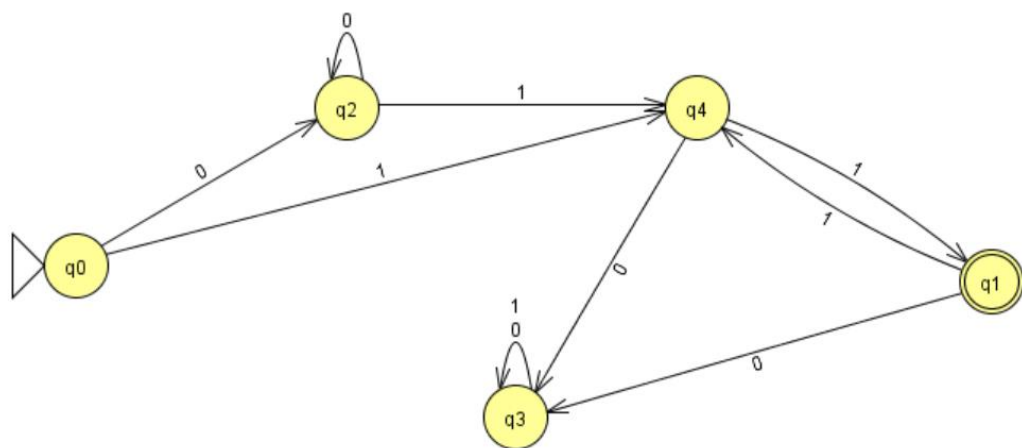
(2)



(3)



(4)



3.

