kinematic setup

$t_{\mathrm{src}} = 0$ A A $t_{\mathrm{snk}} = X_t$

$p_z = k$

$t_{\mathrm{src}} = 0$ B Γ A $t_{\mathrm{snk}} = T$

$p_z = 0$

$t_J = Y_t$

$q_z = k$