



<b>plan</b>	<b>0</b>	<b>1</b>	<b>2</b>	<b>3</b>
$a_0$	(0,0)	(1,0)	(2,0)	(3,0)
$a_1$	(0,0)	(1,0)	(2,0)	(3,0)

Table 1: Changed as abstract systems these classical equations of motion see diagram to t

## 1.1 SubSection

$$spct_{i,j} = \begin{cases} 1, & \neg af(a_j, g_i) \wedge \neg gf(g_i) \\ 0, & af(a_j, g_i) \wedge \neg gf(g_i) \\ 0, & \neg af(a_j, g_i) \wedge gf(g_i) \end{cases} \quad (3)$$

## 2 Section

### 2.1 SubSection