



1	2	3

Time modeling: $A(t_0)$ is state at the moment t_0 and t' is the next moment after t

$$\exists: A(t_0) \left\{ \begin{array}{l} \forall t: T(t) \{ \exists t': T(t'), N(t, t') \\ \Phi \\ \Psi \end{array} \right.$$

$F \rightarrow \text{XG}$

The goal of control cannot be defined