

Dynamic System Property: *atis* Goalness

(*Dynamic system properties* are those properties that are part of the theory and describe patterns in time as change occurs within a system or between a system and its negasystem.)

Goalness, $G(\mathfrak{S})$, =_{df} a system end state determined *a priori*.

$$G(\mathfrak{S}) =_{df} \mathcal{S} \mid \sigma(\mathcal{L}\mathcal{W}_{t_1}) \Vdash \mathcal{S}_{t_1}, \mathcal{S}_{t_2}, \mathcal{S}_{t_3}, \dots, \mathcal{S}_{t_n} = \mathcal{S}$$

Goalness is an end state such that; a system state-transition function defined on the leadership subsystem at time t_1 yields a sequence of system states from time t_1 to t_n , and the state at time t_n is the end state.

The operation: ‘ $\sigma(\mathcal{L}\mathcal{W}_{t_1}) \Vdash \mathcal{S}_{t_1}, \mathcal{S}_{t_2}, \mathcal{S}_{t_3}, \dots, \mathcal{S}_{t_n}$ ’, is defined by an APT&C value of the state at each time as derived from $\mathcal{L}\mathcal{W}_{t_1}$. That is, each state is the result of a system state-transition determined by the leadership subsystem.