

$$\{t^*, y^*, a^*, x^*, z^*\} = \{\tau, \eta, \alpha, \xi, \zeta\};$$

$$\{\tau^*, \eta^*, \alpha^*, \xi^*, \zeta^*\} = \{t, y, a, x, z\};$$

$$(u_{i_})^* ::= (u^*)_i;$$