```
recognizer1__feasible  THM

⊢  ∀T,A:Type, P:(A→T→𝔹), k:Knd, i,r,x:Id.
   A
   ⇒
   T ⇒ ¬x = r ⇒ d-feasible(λloc.⊕(recognizer1(loc;T;A;P;k;i;r;x)))
  by ProveFeasibleSupport [i]
END
```