

**MACHINE** StableLassaleGeneric

**REFINES** Generic

**SEES** StableLassaleCtx

**VARIABLES**

t  
x.p  
x.s

**INVARIANTS**

$V\_o\_Sol\_Deriv: x.p(Rzero) \in K \Rightarrow x.p; V \in D1(Closed2Closed(Rzero, t), RReal)$

**EVENTS**

**Initialisation**

**begin**

act1:  $t := Rzero$   
act3:  $x.s \in STATES$   
act2:  $x.p \in D1(\{Rzero\}, S)$

**end**

**Event** Transition  $\langle ordinary \rangle \triangleq$

**extends** Transition

**any**

*s*

**where**

grd1:  $s \in \mathbb{P}_1(STATES)$

**then**

act1:  $x.s \in s$

**end**

**Event** Sense  $\langle ordinary \rangle \triangleq$

**extends** Sense

**any**

*s*

*p*

**where**

grd1:  $s \in \mathbb{P}_1(STATES)$   
grd2:  $p \in \mathbb{P}(STATES \times RReal \times S)$   
grd3:  $(x.s \mapsto t \mapsto x.p(t)) \in p$

**then**

act1:  $x.s \in s$

**end**

**Event** Behave  $\langle ordinary \rangle \triangleq$

**refines** Behave

**any**

tp

e

Inv

**where**

grd0:  $tp \in RRealPlus \wedge t \mapsto tp \in lt$   
grd1:  $e \in DE(S)$   
grd2:  $Solvable(Closed2Closed(t, tp), e)$   
grd3:  $Inv \subseteq RRealPlus \times S$   
grd4:  $(t \mapsto x.p(t)) \in Inv$

**then**

act1:  
 $t, x.p : | x.p' \in RReal \mapsto S \wedge t' = tp \wedge Closed2Closed(Rzero, t') \subseteq dom(x.p') \wedge$   
 $CBAPsolutionOf(t, t', x.p, x.p', e, Inv)$

**end**

**Event** Actuate  $\langle ordinary \rangle \triangleq$

**refines** Actuate

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any
  tp
  e
  s
where
  grd0:  $tp \in RRealPlus \wedge t \mapsto tp \in lt$ 
  grd1:  $e = ode(F, x\_p(Rzero), Rzero)$ 
  grd3:  $s \subseteq STATES$ 
  grd4:  $x\_s \in s$ 
  grd2:  $Solvable(Closed2Closed(t, tp), ode(F, x\_p(Rzero), Rzero))$ 
  grd6:  $(t \mapsto x\_p(t)) \in Closed2Closed(t, tp) \times S$ 
with
  Inv:  $Inv = Closed2Closed(t, tp) \times S$ 
then
  act1:
     $t, x\_p :| x\_p' \in RReal \mapsto S \wedge t' = tp \wedge Closed2Closed(Rzero, t') \subseteq dom(x\_p') \wedge$ 
     $CBAPsolutionOf(t, t', x\_p, x\_p', ode(F, x\_p(Rzero), Rzero), Closed2Closed(t, tp) \times S)$ 
     $Der(\{t\}, S, x\_p) = Der(\{t\}, S, x\_p')$ 
  end
END

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