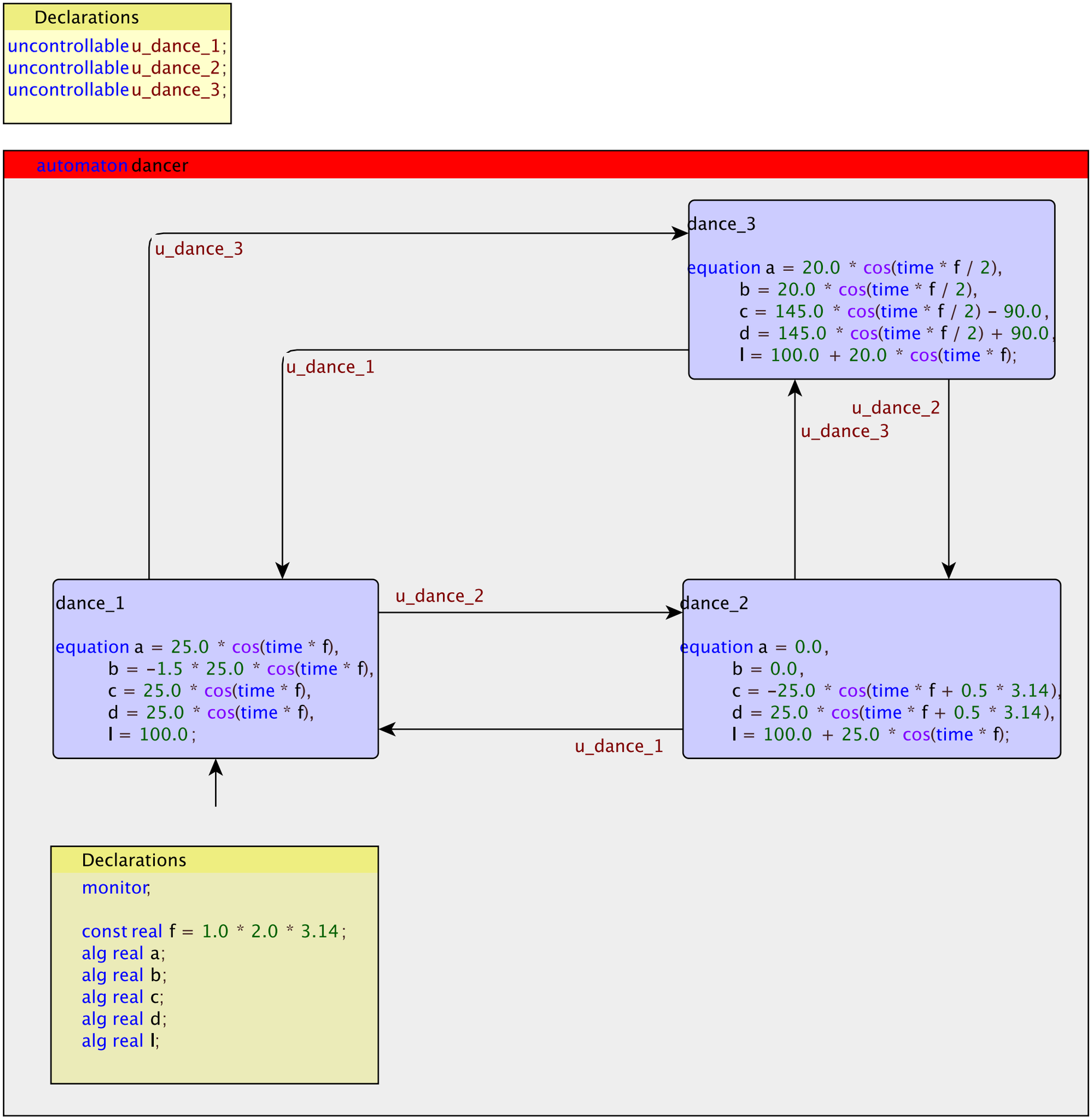
Declarations
uncontrollable u_dance_1;
uncontrollable u_dance_2;
uncontrollable u_dance_3;
automaton dancer
u_dance_3
dance_3
equation a = 20.0 * cos(time * f / 2),
b = 20.0 * cos(time * f / 2),
c = 145.0 * cos(time * f / 2) - 90.0,
d = 145.0 * cos(time * f / 2) + 90.0,
l = 100.0 + 20.0 * cos(time * f);
u_dance_1
u_dance_2
u_dance_3
dance_1
equation a = 25.0 * cos(time * f),
b = -1.5 * 25.0 * cos(time * f),
c = 25.0 * cos(time * f),
d = 25.0 * cos(time * f),
l = 100.0;
u_dance_2
dance_2
equation a = 0.0,
b = 0.0,
c = -25.0 * cos(time * f + 0.5 * 3.14),
d = 25.0 * cos(time * f + 0.5 * 3.14),
l = 100.0 + 25.0 * cos(time * f);
u_dance_1
Declarations
monitor;
const real f = 1.0 * 2.0 * 3.14;
alg real a;
alg real b;
alg real c;
alg real d;
alg real l;