1 Variables

2 root

	var	symbol	documentation	type	units	tokens	eqs
13	$F_{N,A}$	`F`	directed graph incidence matrix	network		[]	
1	t_N	`t`	time	frame	s	[]	
3	to_N	`to`	starting time	frame	s	[]	1
4	te_N	`te`	end time	frame	s	[]	2
2	$value$	`value`	numerical value	constant		[]	

3 System

	var	symbol	documentation	type	units	tokens	eqs
5	x_N	`x`	state - length	state	m	[]	
11	${\pi^a}_N$	`pi_a`	effort a	state	m	[]	7
12	${\pi^b}_N$	`pi_b`	effort b	state	m	[]	8
14	${\hat{x}^a}_N$	`fx_a`	flow of x mechanism a	state	ms^{-1}	[]	9
15	${\hat{x}^b}_N$	`fx_b`	flow of x mechanism b	state	ms^{-1}	[]	10
16	$\dot{x}_N$	`dx`	differential state	state	ms^{-1}	[]	11
7	K_N	`K`	frequency a	constant	s^{-1}	[]	3
8	L_N	`L`	frequency b	constant	s^{-1}	[]	4
9	M	`M`	gain a	constant		[]	5
10	N	`N`	gain b	constant		[]	6

4 Properties

	var	symbol	documentation	type	units	tokens	eqs

5 Control

	var	symbol	documentation	type	units	tokens	eqs

6 System–Properties

	var	symbol	documentation	type	units	tokens	eqs

7 Properties–System

	var	symbol	documentation	type	units	tokens	eqs

8 System–Control

	var	symbol	documentation	type	units	tokens	eqs

9 Control–System

	var	symbol	documentation	type	units	tokens	eqs

10 Properties–Control

	var	symbol	documentation	type	units	tokens	eqs

11 Control–Properties

	var	symbol	documentation	type	units	tokens	eqs

12 Equations

12.1 Model equations

no	equation	documentation	layer
1	$to_N := Set(t_N, value)$	starting time	root
2	$te_N := Set(t_N, value)$	end time	root
3	$K_N := Set((t_N)^{-1}, value)$	frequency a	System
4	$L_N := Set((t_N)^{-1}, value)$	frequency b	System
5	$M := Set(value, value)$	gain a	System
6	$N := Set(value, value)$	gain b	System
7	${\pi^a}_N := M \,.\, x_N$	effort a	System
8	${\pi^b}_N := N \,.\, x_N$	effort b	System
9	${\hat{x}^a}_N := F_{N,A} \overset{A}{\star} \left(K_N \,.\, F_{N,A} \overset{N}{\star} {\pi^a}_N\right)$	flow of x mechanism a	System
10	${\hat{x}^b}_N := F_{N,A} \overset{A}{\star} \left(L_N \,.\, F_{N,A} \overset{N}{\star} {\pi^b}_N\right)$	flow of x mechanism b	System
11	$\dot{x}_N := {\hat{x}^a}_N + {\hat{x}^b}_N$	differential state	System