

**MACHINE**

System\_M

**SEES**

System\_Ctx

Theorems

**VARIABLES**

t

plantV

**INVARIANTS**

inv1 : t ∈ TIME

inv2 : plantV ∈ Closed2Closed(Rzero, t) ↔ RReal

**EVENTS****INITIALISATION** ≐**STATUS**

ordinary

**BEGIN**

act1 : t=Rzero

act2 : plantV := {Rzero} plantV0}

**END****Progress** ≐**STATUS**

ordinary

**BEGIN**

act1 : t :| t' ∈ TIME ∧ (t ↦ t' ∈ lt ∧ minus(t'↦t) ↦ sigma ∈ geq)

**END****Plant** ≐**STATUS**

ordinary

**ANY**

e

plant1

**WHERE**

grd1 : e ∈ DE(RReal)

grd2 : Solvable(Closed2Closed(Rzero, t) \ dom(plantV), e)

plant1 ∈ Closed2Closed(Rzero, t) \ dom(plantV) → RReal ∧

grd3 : AppendSolutionBAP(e,

Closed2Closed(Rzero, t) \ dom(plantV),

Closed2Closed(Rzero, t) \ dom(plantV), plant1)

**THEN**

act1 : plantV = plantV ◁ plant1

**END****END**