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%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%
% Define the bodies present in the model %%%%%%%%%
%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%
Body: 1          % id of this body
Mass: 1          % mass of body
Jbar: 0.4        % mass moment of inertia
xZero: 1.5       % initial X position
yZero: 0         % initial Y position
phiZero: 0       % initial orientation (this is pi/2)
xDotZero: 0.0    % initial velX
yDotZero: 9.42477796 % initial velY; this is 3*pi
phiDotZero: 6.28318531 % initial velPhi
%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%
Body: 2          % id of this body
Mass: 1.5        % mass of body
Jbar: 1          % mass moment of inertia
xZero: 5         % initial X position
yZero: 0         % initial Y position
phiZero: 0       % initial orientation (this is pi/2)
xDotZero: 0.0    % initial velX
yDotZero: 4.71238898 % initial velY; this is 1.5*pi
phiDotZero: 6.28318531 % initial velPhi
%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%
% Define the constraints of the model %%%%%%%%%
%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%
AbsoluteX: 1     % id of this constraint
Body: 1          % id of participating body
xPprime: -1.5    % x of point P on moving body, expressed in LRF
yPprime: 0       % y of point P on moving body, expressed in LRF
xPground: 0      % x of point P on ground
yPground: 0      % y of point P on ground
CmotionFunction: NONE % provides expression for C(t)
%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%
AbsoluteY: 2     % id of this constraint
Body: 1          % id of participating body
xPprime: -1.5    % x of point P on moving body, expressed in LRF
yPprime: 0       % y of point P on moving body, expressed in LRF
xPground: 0      % x of point P on ground
yPground: 0      % y of point P on ground
CmotionFunction: NONE % provides expression for C(t)

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