```
1 st1     + here we are, now +*Δyou stand there#+so we go   +like this,+
a st1     >>gz Staff 2-------------------------+gz Pat
b st1     +steps back--------+points to St2 nods+
c st1     >>holds Pat's arm,,,,,,,,,,,,,,,,,,,,,,+lets go,,,+opens arm +
d st2     >>gz St1,              *stands still->
e pat     >>gz St1, steps fwd--Δstops->
f fig                                          #Figure 9
```


Figure 9. Staff 1 holds Pat's arm in a shepherding move

```
2         +Δ (1.3)                #and Δ then      Δ like this,+
a st1     +links R arm w Pat # walks twd Staff 2--------+releases arm
b pat      Δlinks R arm w Staff 1,Δ circles Δ releases arm from Staff 1
c fig                     #Figure 10
```
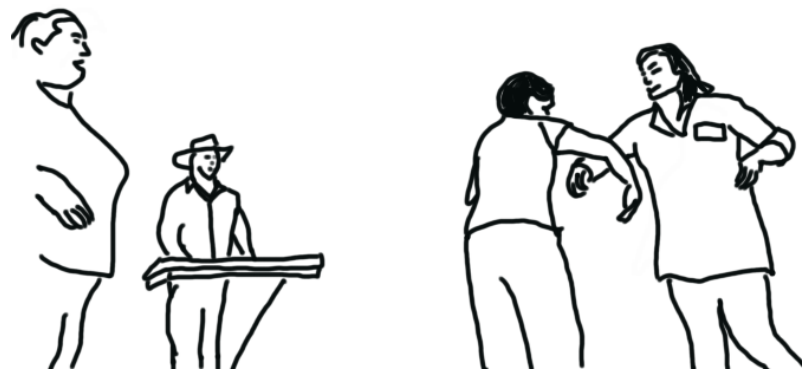

Figure 10. Staff 1 and Pat link arms on "we go like this"

```
3         (0.3)+*                    (0.3)+*#
a st1        +extends L arm twd Staff 2,+links L arm w Staff 2
b st2         *extends L arm twd Staff 1-*links L arm w Staff 1
c fig                                      #Figure 11
```


Figure 11. Staff 2 and Staff 1 link arms

```
4         (0.3)*                 (0.1)*+   (0.3)*(0.1)+#
a st2        *steps around Staff 1 *,extends*R arm twd Pat->>
b St1                                +gz Staff 2    +#tha:ats it,
c fig                                      #Figure 10
```


Figure 12. Staff 1 Indexes the achieved coordination, "that's it."