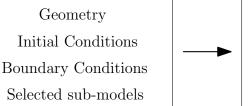
## Simulator



Input Deck

Other Controllable Inputs

Conservation Equations  $b(\mathbf{u}, \mathbf{x}_c, \{\mathcal{M}_i(\mathbf{x}_c, \mathbf{x}_m, \mathbf{u})\}) = 0$ 

TH System Code

Closure Laws, sub-models, etc.  $\{\mathcal{M}_i(\mathbf{x}_c, \mathbf{x}_m, \mathbf{u}); i > 0\}$ 

