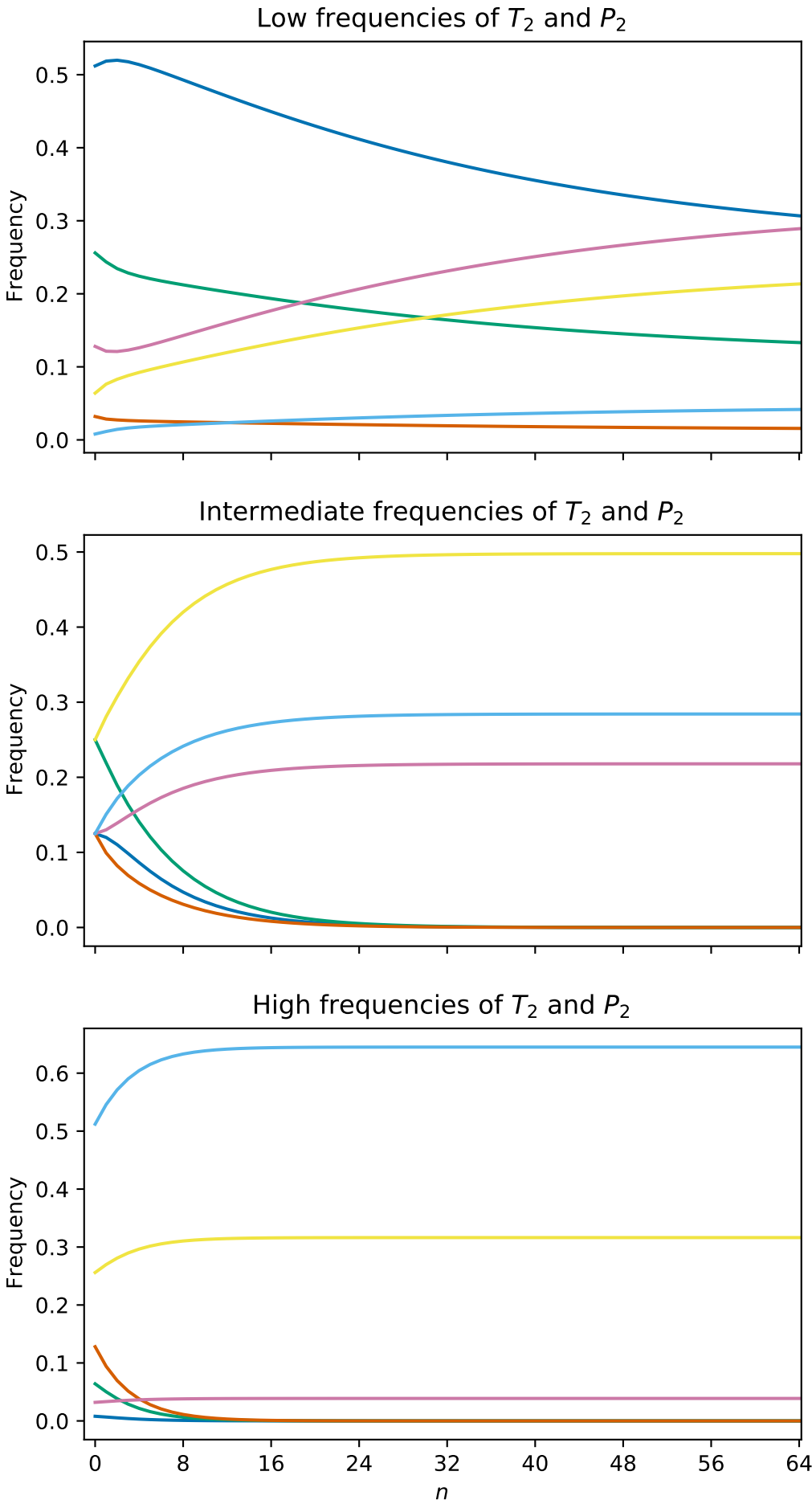


Dynamics of the model with parameters  
 $b_3 = 1, b_2 = 0.5, b_1 = 0.5, b_0 = 0, s = 0.4, h = 1, a = 3.$



- $P_1P_1T_1$
- $P_1P_2T_1$
- $P_2P_2T_1$
- $P_1P_1T_2$
- $P_1P_2T_2$
- $P_2P_2T_2$