

$$\mathbf{Q}_t = \begin{matrix} & \text{H} & \text{S1} & \text{S2} & \text{DOC} & \text{DS} \\ \begin{matrix} \text{H} \\ \text{S1} \\ \text{S2} \\ \text{DOC} \\ \text{DS} \end{matrix} & \begin{pmatrix} -(\mathbf{r\_HS1}_t + \mathbf{r\_HD}_t) & \mathbf{r\_HS1}_t & 0 & \mathbf{r\_HD}_t & 0 \\ \mathbf{r\_S1H}_t & -(\mathbf{r\_S1H}_t + \mathbf{r\_S1S2}_t + \mathbf{hr\_S1}_t \cdot \mathbf{r\_HD}_t) & \mathbf{r\_S1S2}_t & \mathbf{r\_HD}_t & \mathbf{hr\_S1}_t \cdot \mathbf{r\_HD}_t - \mathbf{r\_HD}_t \\ 0 & 0 & -(\mathbf{hr\_S2} \cdot \mathbf{r\_HD}_t) & \mathbf{r\_HD}_t & \mathbf{hr\_S2}_t \cdot \mathbf{r\_HD}_t - \mathbf{r\_HD}_t \\ 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 \end{pmatrix} \end{matrix}$$

$$\mathbf{Q}_t = \begin{matrix} & \text{H} & \text{S1} & \text{S2} & \text{D} & \text{trDS} \\ \begin{matrix} \text{H} \\ \text{S1} \\ \text{S2} \\ \text{D} \\ \text{trDS} \end{matrix} & \begin{pmatrix} -(\mathbf{r\_HS1}_t + \mathbf{r\_HD}_t) & \mathbf{r\_HS1}_t & 0 & \mathbf{r\_HD}_t & \vdots & 0 \\ \mathbf{r\_S1H}_t & -(\mathbf{r\_S1H}_t + \mathbf{r\_S1S2}_t + \mathbf{hr\_S1}_t \cdot \mathbf{r\_HD}_t) & \mathbf{r\_S1S2}_t & \mathbf{hr\_S1}_t \cdot \mathbf{r\_HD}_t & \vdots & \mathbf{hr\_S1}_t \cdot \mathbf{r\_HD}_t - \mathbf{r\_HD}_t \\ 0 & 0 & -(\mathbf{hr\_S2}_t \cdot \mathbf{r\_HD}_t) & \mathbf{hr\_S2}_t \cdot \mathbf{r\_HD}_t & \vdots & \mathbf{hr\_S2}_t \cdot \mathbf{r\_HD}_t - \mathbf{r\_HD}_t \\ 0 & 0 & 0 & 0 & 0 & 0 \\ \cdots & 0 & 0 & 0 & 0 & 0 \end{pmatrix} \end{matrix}$$