1 Variables

2 root

	var	symbol	documentation	type	units	tokens	eqs
5	$F_{N,A}$	F	incidence matrix of directed graph	network		[]	
1	t_N	t	time	frame	s	[]	
3	to_N	to	initial time	frame	s	[]	1
4	te_N	te	end time	frame	s	[]	2
2	$value$	value	numerical value	constant		[]	

3 System

	var	symbol	documentation	type	units	tokens	eqs
17	$\hat{x}^a{}_N$	fx_a	flow of x with mechanism a	transport	ms^{-1}	[]	12
18	$\hat{x}^b{}_N$	fx_b	flow of x with mechanism b	transport	ms^{-1}	[]	13
6	x_N	x	state	state	m	[]	15
15	$\pi^a{}_N$	pi_a	effort a	state	m	[]	10
16	$\pi^b{}_N$	pi_b	effort b	state	m	[]	11
19	$\dot{x}_N$	dx	differential state	state	ms^{-1}	[]	14
10	ν	nu	frequency	constant	s^{-1}	[]	
11	K	K	frequency a	constant	s^{-1}	[]	6
12	L	L	frequency b	constant	s^{-1}	[]	7
13	M	M	a transport constant	constant		[]	8
14	N	N	a transport constant	constant		[]	9

4 Properties

	var	symbol	documentation	type	units	tokens	eqs

5 Control

	var	symbol	documentation	type	units	tokens	eqs

6 System–Properties

	var	symbol	documentation	type	units	tokens	eqs

7 Properties–System

	var	symbol	documentation	type	units	tokens	eqs

8 System–Control

	var	symbol	documentation	type	units	tokens	eqs

9 Control–System

	var	symbol	documentation	type	units	tokens	eqs

10 Properties–Control

	var	symbol	documentation	type	units	tokens	eqs

11   Control–Properties

	var	symbol	documentation	type	units	tokens	eqs

12 Equations

12.1 Model equations

no	equation	documentation	layer
1	$to_N := Set(t_N, value)$	initial time	root
2	$te_N := Set(t_N, value)$	end time	root
6	$K := Set(\nu, value)$	frequency a	System
7	$L := Set(\nu, value)$	frequency b	System
8	$M := Set(value, value)$	a transprort constant	System
9	$N := Set(value, value)$	a transport constant	System
10	$\pi^a{}_N := M \cdot x_N$	effort a	System
11	$\pi^b{}_N := N \cdot x_N$	effort b	System
12	$\hat{x}^a{}_N := F_{N,A} \overset{A}{\star} \left(K \cdot F_{N,A} \overset{N}{\star} \pi^a{}_N \right)$	flow of x with mechanism a	System
13	$\hat{x}^b{}_N := F_{N,A} \overset{A}{\star} \left(K \cdot F_{N,A} \overset{N}{\star} \pi^b{}_N \right)$	flow of x with mechanism b	System
14	$\dot{x}_N := \hat{x}^a{}_N + \hat{x}^b{}_N$	differential state	System
15	$x_N := \int_{to_N}^{te_N} \dot{x}_N \ d\,t_N$	state	System