

$H(s,u,w,p)$

S: states

U: inputs

W: external inputs

P: parameters

Node table

1. Name(p)
2. State(s)
3. ERP_cur(s)
4. ERP_def(p)
5. RRP_cur(s)
6. RRP_def(p)
7. Rest_cur(s)
8. Rest_def(p)
9. Node_in(s)
10. ERP_int(p)
11. Node_out(s)
12. Node_cat(p)

Path table

1. Name(p)
2. State(s)
3. Node_ind1(p)
4. Node_ind2(p)
5. Amp(p)*
6. Velocity(p)*
7. Type(p)*
8. Forw_cur(s)
9. Forw_def(p)
10. Back_cur(s)
11. Back_def(p)
12. Length(p)*
13. Slope(p)*

*not used

Pacemaker parameters

1. Name(p)
2. State(s)
3. Timer_cur(s)
4. Timer_def(p)

5. (1)AP(w); (2)VP(w); (3)AS(s); (4)VS(s);