H(s,u,w,p)

S: states

U: inputs

W: external inputs

P: parameters

# Node table

1. Name(p)
2. State(s)={1,…,3}
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);