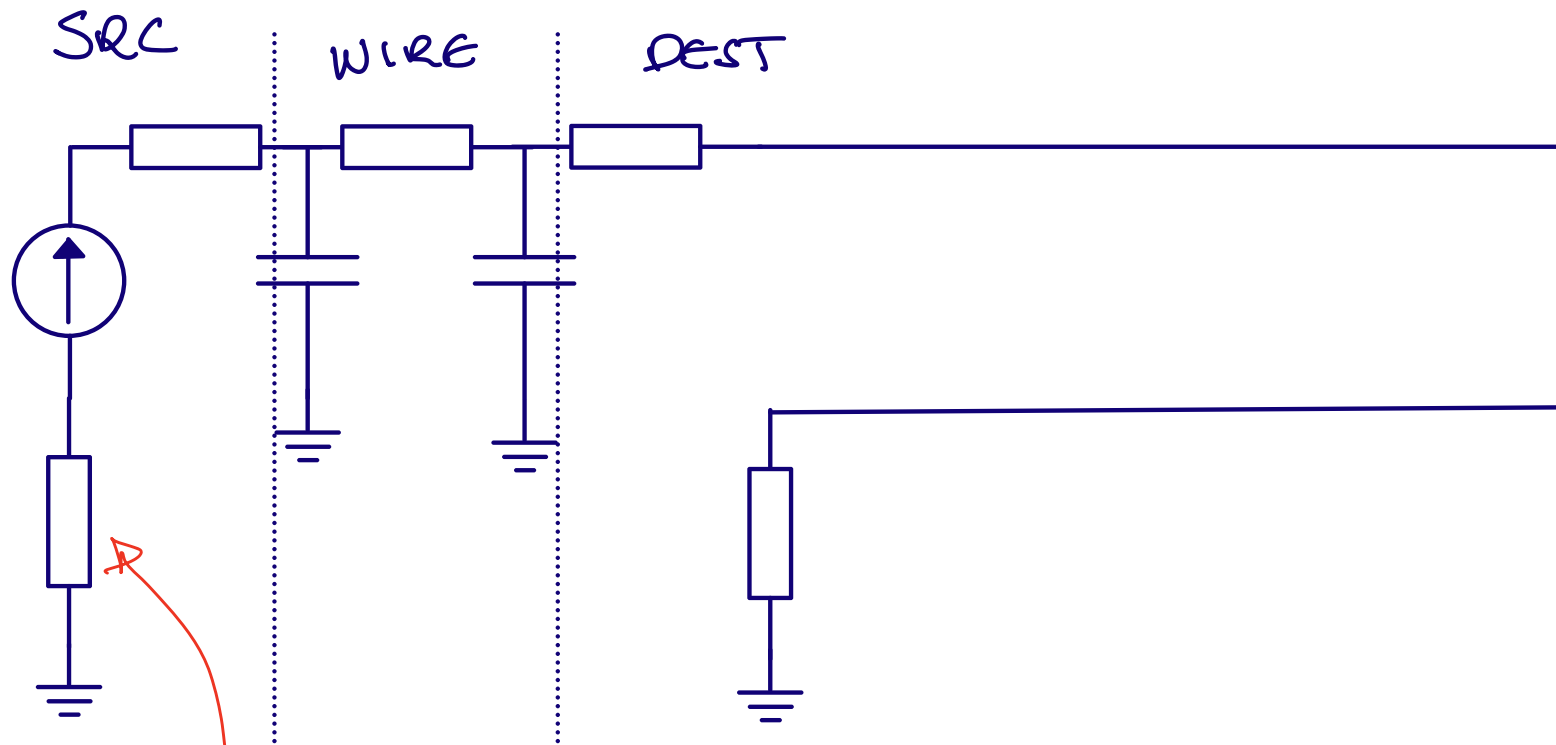


$$I = \frac{V_a}{R}$$



$$Z(t, V, f, T, P)$$