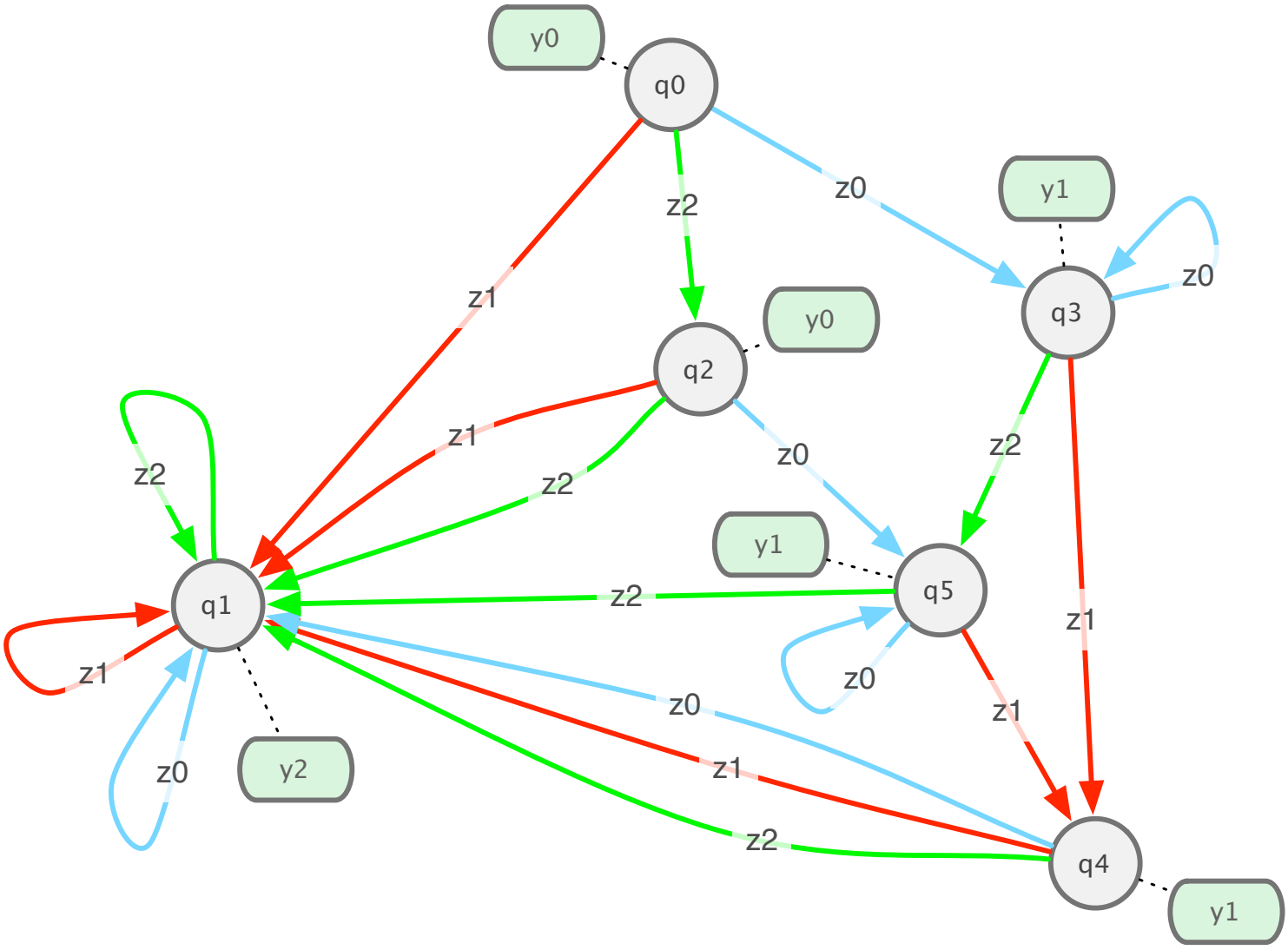

y0
q0
z0
y1
z2
z1
z0
q3
y0
q2
z1
z2
z0
z2
z2
y1
q5
q1
z2
z1
z0
z1
z0
z0
y2
z1
z2
q4
y1

DOSBox 0.74, Cpu speed: 3000 cycles, Frameskip 0, Program: AUTOMAT

Dane Edycja Symulacja Analiza

Definicia automatu

$G = {}^{0}(q_0{}^{1}(z_0q_3, z_1q_1, z_2q_2)^{1}, q_1{}^{1}(z_0q_1, z_1q_1, z_2q_1)^{1}, q_2{}^{1}(z_0q_5, z_1q_1, z_2q_1)^{1}, q_3{}^{1}(z_0q_3, z_1q_4, z_2q_5)^{1}, q_4{}^{1}(z_0q_1, z_1q_1, z_2q_1)^{1}, q_5{}^{1}(z_0q_5, z_1q_4, z_2q_1)^{1})^{0}$

$X = \{z_0, z_1, z_2\}$

$Q = \{q_0, q_1, q_2, q_3, q_4, q_5\}$

$Y = \{y_0, y_1, y_2\}$

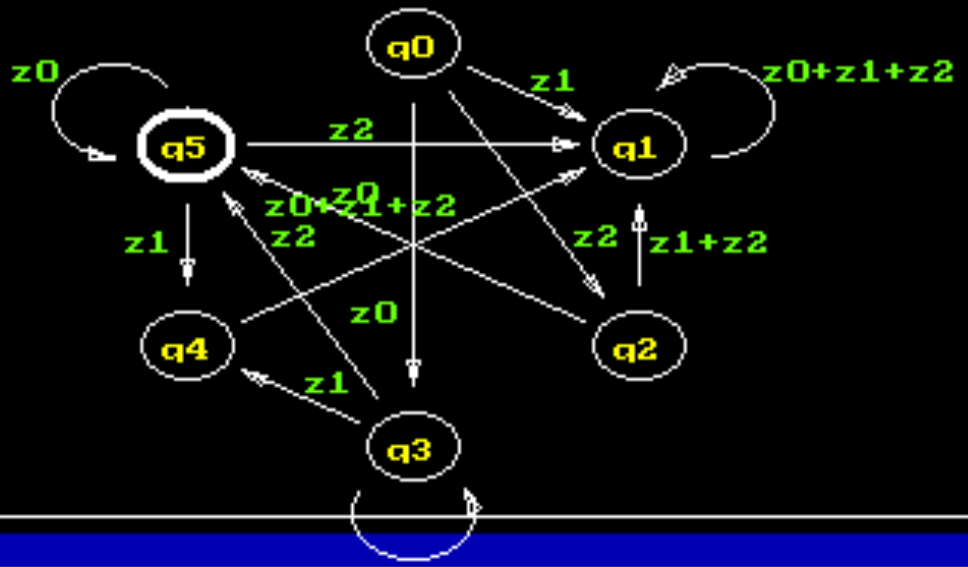
F.w. :

Q	q_0	q_1	q_2	q_3	q_4	q_5
Y	y_0	y_2	y_0	y_1	y_1	y_1

Graf automatu

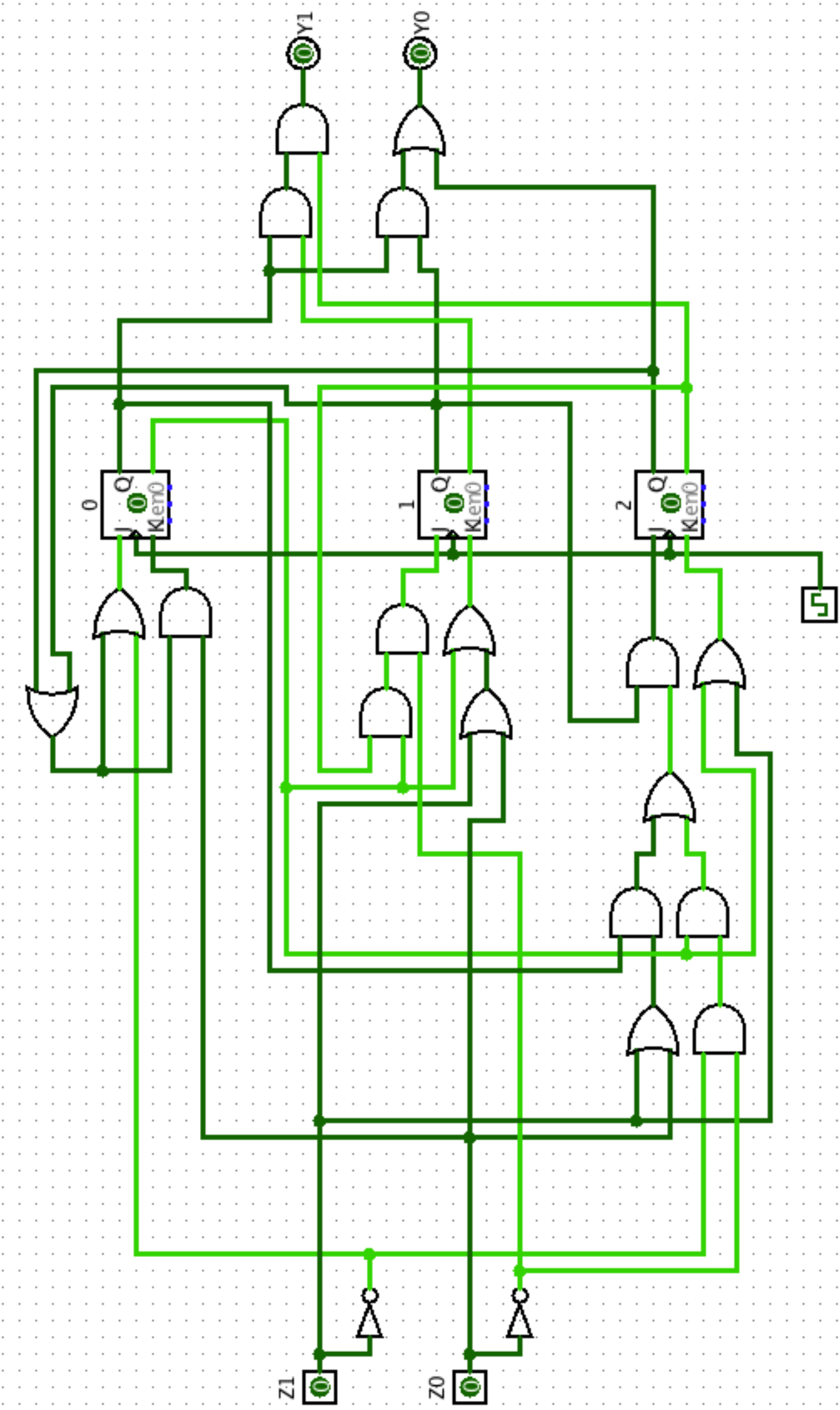
Q → q5

Y → y1



Symulacja

Q[t] x[t] Q[t+1] Y[t+1]


Y1
Y0
0
Q
J
K
en
0
1
Q
J
K
en
0
2
Q
J
K
en
0
5
Z1
Z0