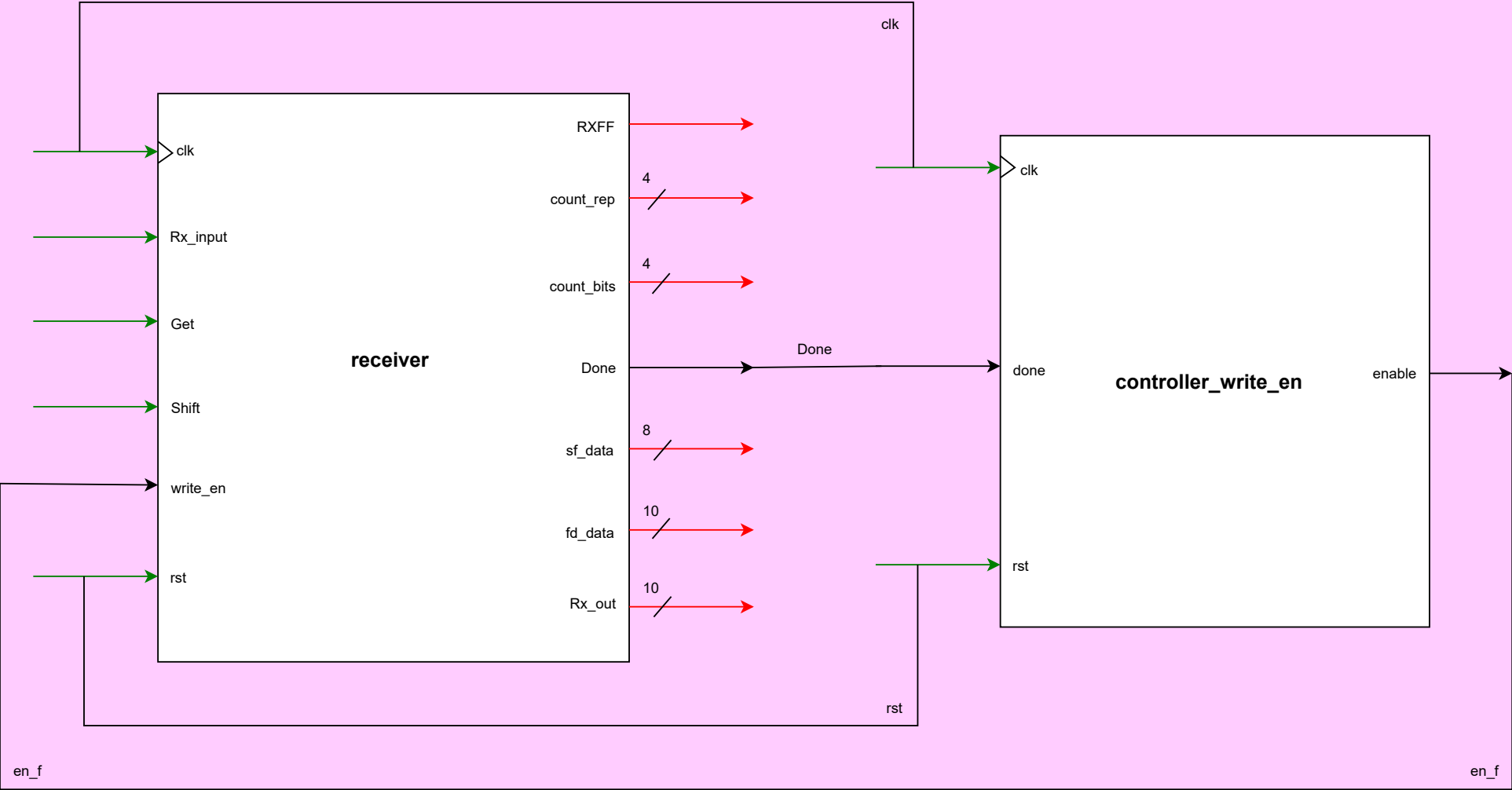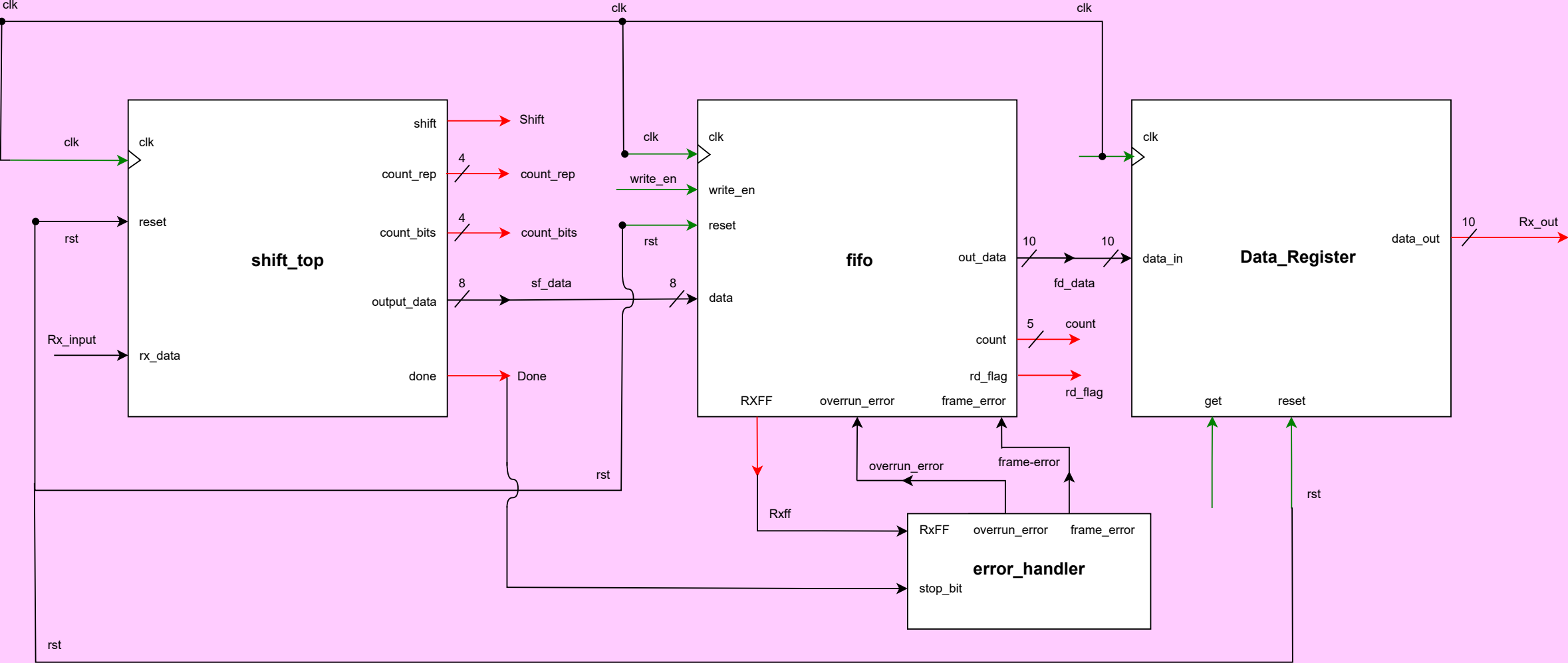# receiver_top
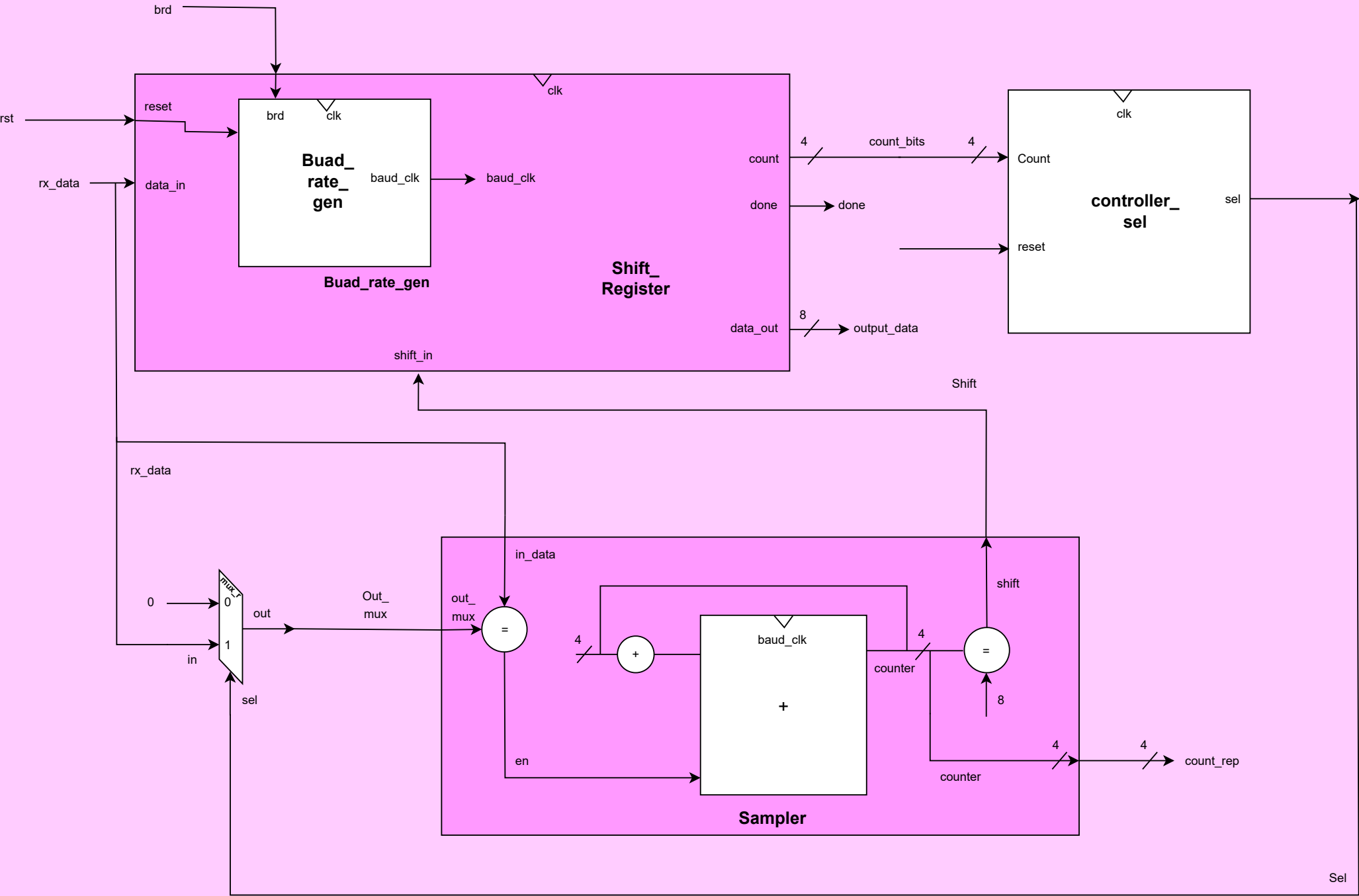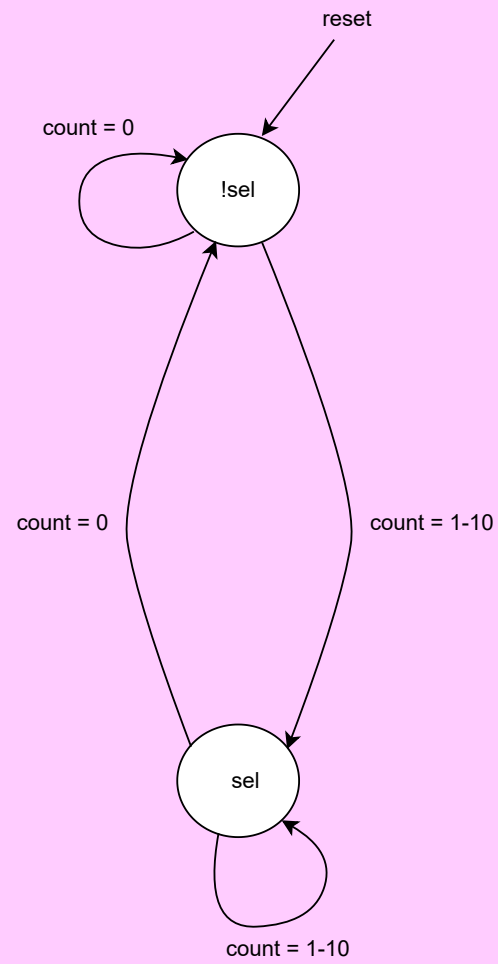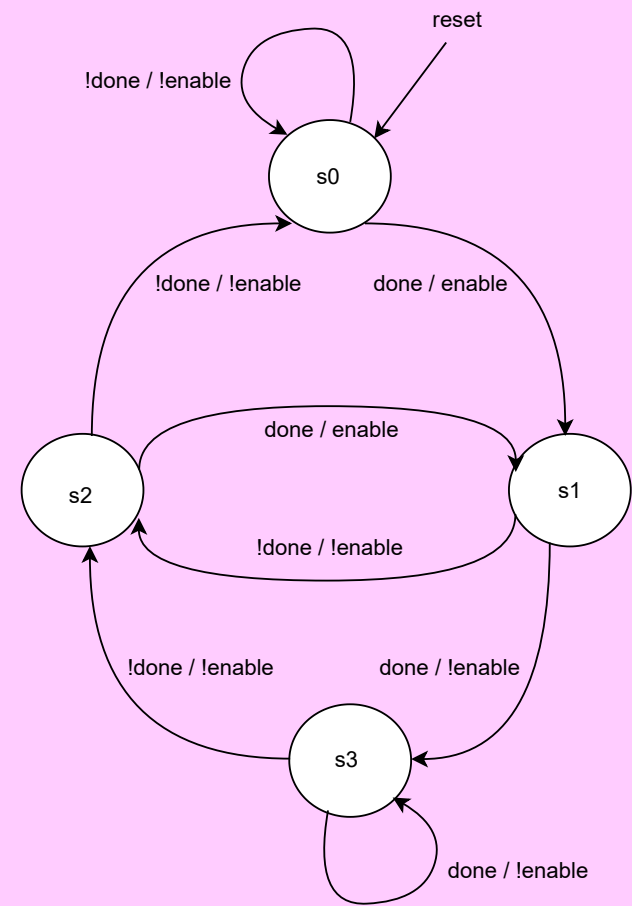
receiver

shift_top

FSM

controller_sel

controller_fout