## Encoder\_Position\_Detector/Encoder 360 u1f(0 <= u1 & u1 <= u3) u2 satif(u3 < u1 & u1 <= u2) → 1 Signal\_A theta\_p elseif { } Signal A theta\_p uff(0 <= u3 & u3 <= u1) u2 satif(u1 < u3 & u3 <= u2) **2** merge Signal\_B Signal B elseif { } **▶**3 N\_number of bit Index\_Z 360 Out\_Z Marker\_pulse Out Z C:\Personal\Internship\_2020\Encoder\_Position\_Detector.slx printed 24-Jan-2025 12:38 page 1/1