

Şimdiki D.

$Q_A(t)$	$Q_B(t)$	$Q_A(t+1)$	$Q_B(t+1)$	J_A	K_A	J_B	K_B	z
0	0	0	0	0	x	0	x	0
0	1	1	0	1	x	x	1	0
1	0	1	1	x	0	1	x	0
1	1	0	0	x	1	x	1	1

0	0	0	1	0	x	1	x	0
0	1	0	1	0	x	x	0	0
1	0	1	1	x	0	1	x	0
1	1	0	1	x	1	x	0	0

$$J_A = \bar{x} Q_B$$

x	$Q_A Q_B$	00	01	11	10
0	0	0	1	x	x
1	0	0	0	x	x

$$J_B = x + Q_A$$

x	$Q_A Q_B$	00	01	11	10
0	0	0	x	x	1
1	0	1	x	x	1

$K_A = Q_B$

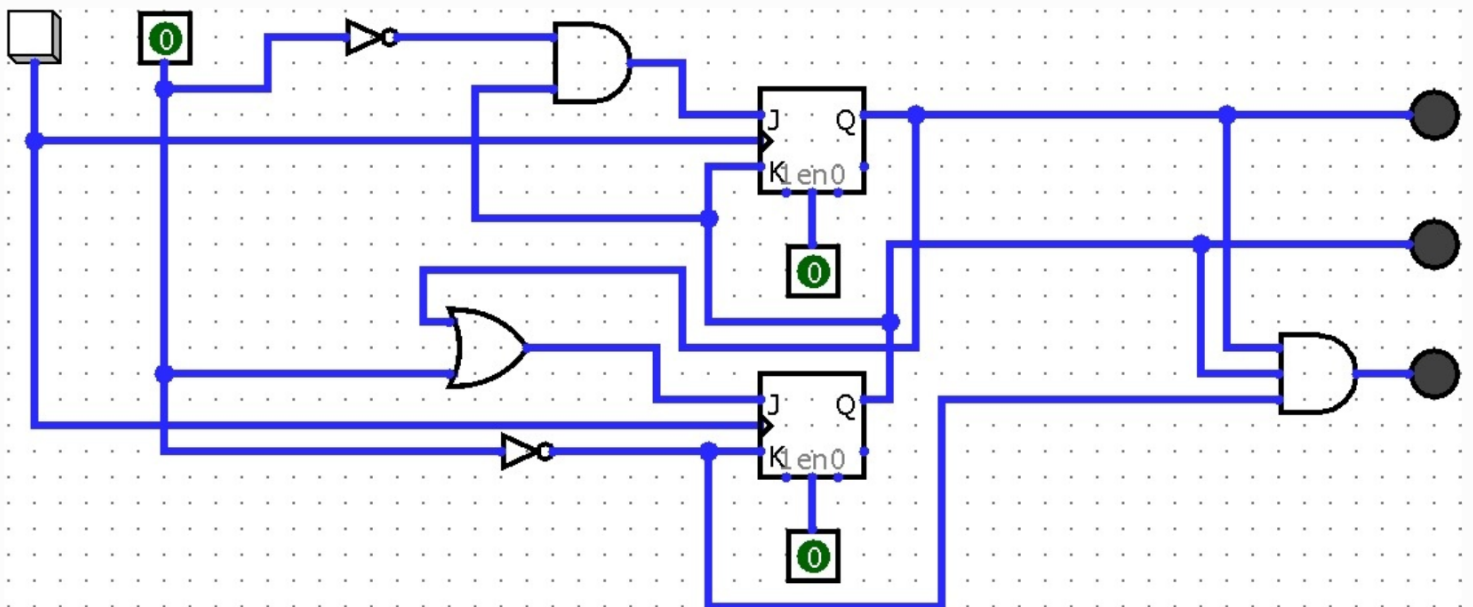
x	$Q_A Q_B$	00	01	11	10
0	0	x	x	1	0
1	0	x	x	1	0

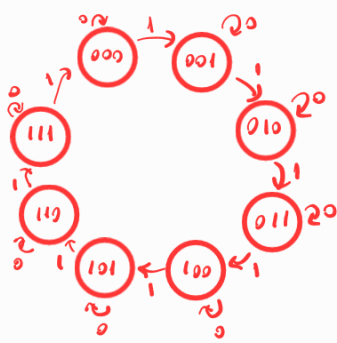
$K_D = \bar{x}$

x	$Q_A Q_B$	00	01	11	10
0	0	x	1	1	x
1	0	x	0	0	x

$z = \bar{x} Q_A Q_B$

x	$Q_A Q_B$	00	01	11	10
0	0	0	0	1	0
1	0	0	0	0	0





$t=0$

$t=1$

Q_A	Q_B	Q_C	$Q_A(t+1)$	$Q_B(t+1)$	$Q_C(t+1)$	T_A	T_B	T_C
0	0	0	0	0	0	0	0	0
0	0	1	0	0	1	0	0	0
0	1	0	0	1	0	0	0	0
0	1	1	0	1	1	0	0	0
1	0	0	1	0	0	0	0	0
1	0	1	1	0	1	0	0	0
1	1	0	1	1	0	0	0	0
1	1	1	1	1	1	0	0	0
0	0	0	0	0	1	0	0	1
0	0	1	0	1	0	0	1	1
0	1	0	0	1	1	0	0	1
0	1	1	1	0	0	1	1	1
1	0	0	1	0	1	0	0	1
1	0	1	1	1	0	0	1	1
1	1	0	1	1	1	0	0	1
1	1	1	0	0	0	1	1	1

$T_A = x Q_B Q_C$

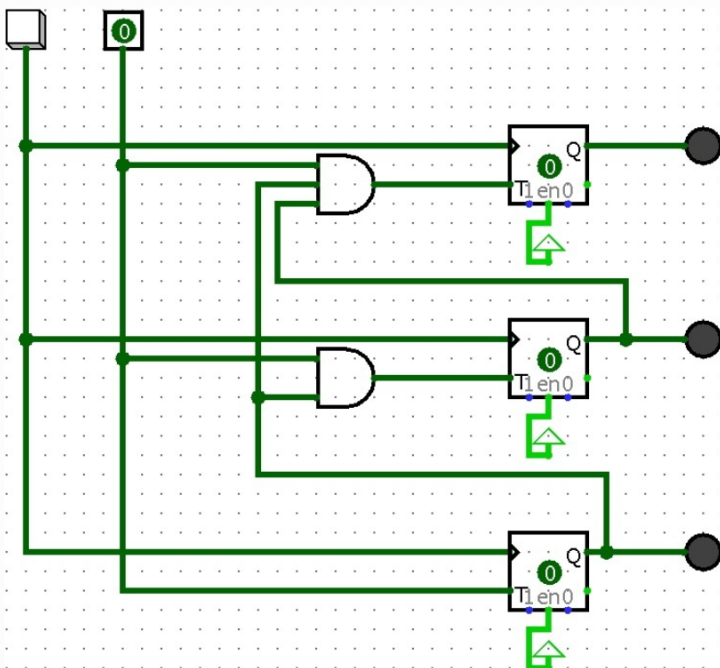
$x Q_C$	00	01	11	10
00	0	0	0	0
01	0	0	0	0
10	0	0	0	0
11	0	1	1	0

$T_B = x Q_C$

$x Q_C$	00	01	11	10
00	0	0	0	0
01	0	0	0	0
10	0	0	0	0
11	1	1	1	1

$T_C = x$

$x Q_C$	00	01	11	10
00	0	0	0	0
01	0	0	0	0
10	1	1	1	1
11	1	1	1	1



Burak Başol

24011037

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