

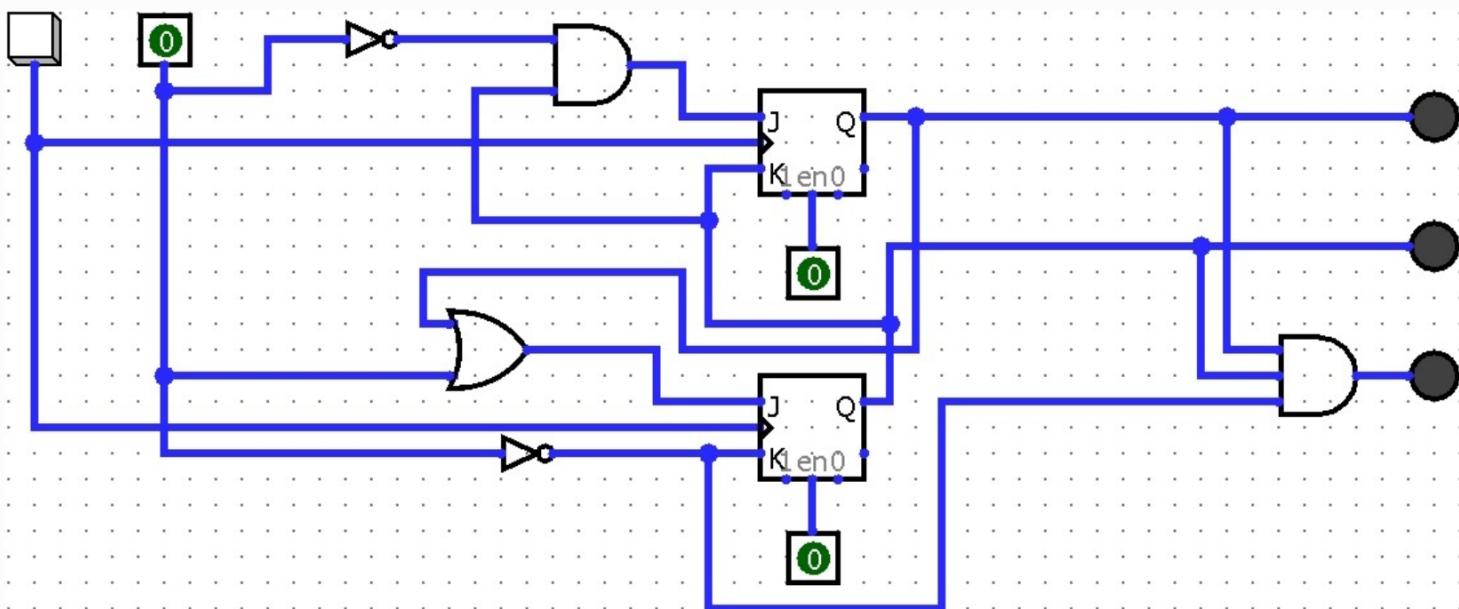
Sımdiki  $\theta$ .

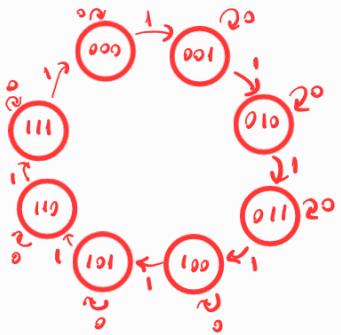
$x$	$Q_A(t)$	$Q_B(t)$	$Q_A(t+1)$	$Q_B(t+1)$	$J_A$	$K_A$	$J_B$	$K_B$	$Z$	$J_A = \bar{x} Q_B$	$J_B = x + Q_A$
0	0	0	0	0	0	x	0	x	0	0	0
	0	1	1	0	1	x	x	1	0	0	0
	1	0	1	1	x	0	1	x	0	0	0
	1	1	0	0	x	1	x	1	1	0	0
1	0	0	0	1	0	x	1	x	0	0	0
	0	1	0	1	0	x	x	0	0	0	0
	1	0	1	1	x	0	1	x	0	0	0
	1	1	0	1	x	1	x	0	0	0	0

$x$	$Q_B$	$K_A = Q_B$
0	00	00
	01	10

$x$	$Q_B$	$K_D = \bar{x}$
0	00	00
	01	10

$x$	$Q_B$	$Z = \bar{x} Q_A Q_B$
0	00	00
	01	10





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

$$T_A = \times Q_B Q_C$$

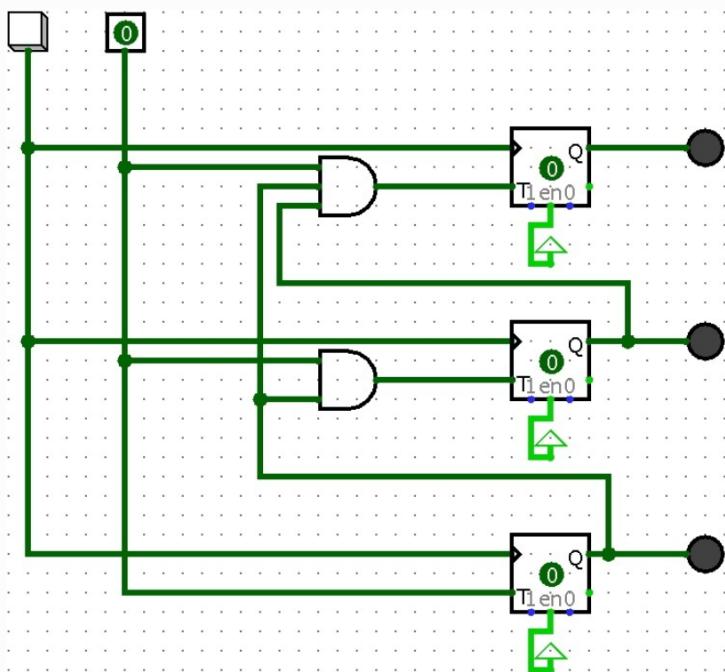
$\times Q_C$	00	01	11	10
$\times Q_B$	00	01	11	10
00	0	0	0	0
01	0	0	0	0
10	0	0	0	0
11	0	1	1	1

$$T_B = \times Q_C$$

$\times Q_C$	00	01	11	10
$\times Q_B$	00	01	11	10
00	0	0	0	0
01	0	0	0	0
10	1	0	0	0
11	1	1	1	1

$$T_C = \times$$

$\times Q_C$	00	01	11	10
$\times Q_B$	00	01	0	0
00	0	0	0	0
01	0	0	0	0
10	1	1	1	1
11	1	1	1	1



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