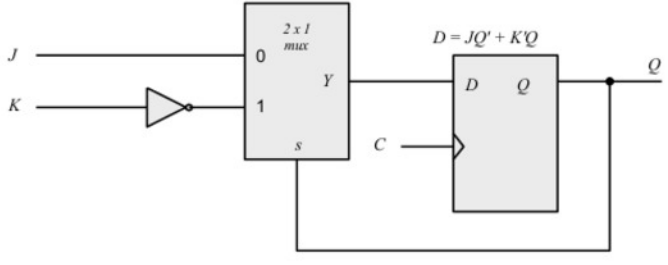
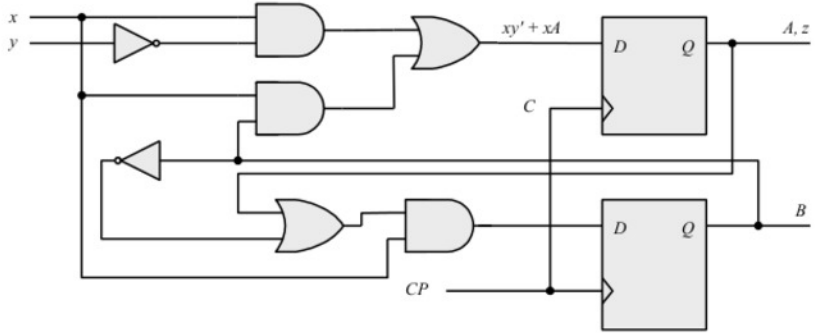
5.2



5.6

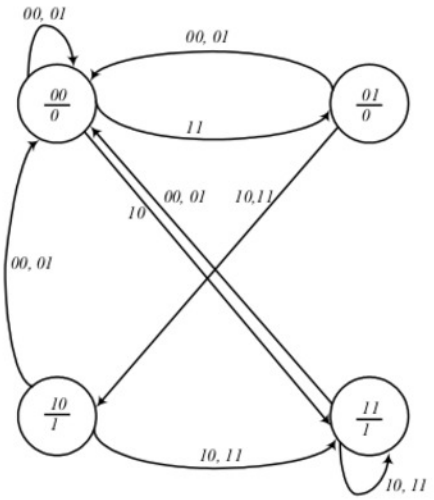


(b)

$A(t+1) = xy' + xB$
$B(t+1) = xA + xB'$
$z = A$

Present state		Inputs		Next state		Output
A	B	x	y	A	B	z
0	0	0	0	0	0	0
0	0	0	1	0	0	0
0	0	1	0	1	1	0
0	0	1	1	0	1	0
0	1	0	0	0	0	0
0	1	0	1	0	0	0
0	1	1	0	1	0	0
0	1	1	1	1	0	0
1	0	0	0	0	0	1
1	0	0	1	0	0	1
1	0	1	0	1	1	1
1	0	1	1	1	1	1
1	1	0	0	0	0	1
1	1	0	1	0	0	1
1	1	1	0	1	1	1
1	1	1	1	1	1	1

(c)



5.9

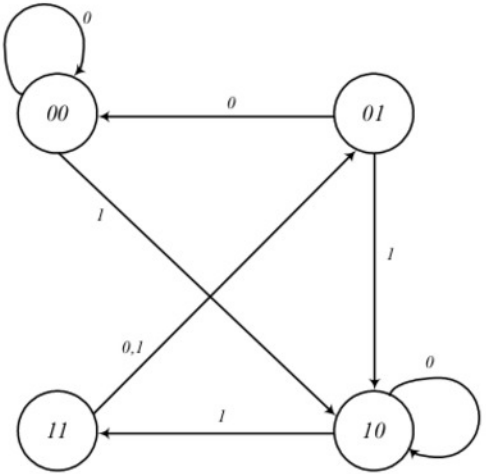
$J_A = x$ $\quad K_A = B$

$J_B = x$ $\quad K_B = A'$

$A(t+1) = J_A A' + K_A' A = xA' + B'A$

$B(t+1) = J_B B' + K_B' B = xB' + AB$

x	A	B	$xA' + B'A$	$xB' + AB$
0	0	0	0	0
0	0	1	0	0
0	1	0	1	0
0	1	1	0	1
1	0	0	1	1
1	0	1	1	0
1	1	0	1	1
1	1	1	0	1



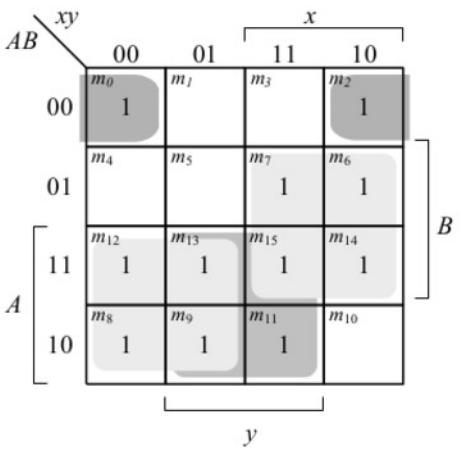
5.10 **(a)** $J_A = Bx + B'y'$ $\quad J_B = A'x$

$K_A = B'xy'$ $\quad K_B = A + xy'$ $\quad z = Ax'y' + Bx'y'$

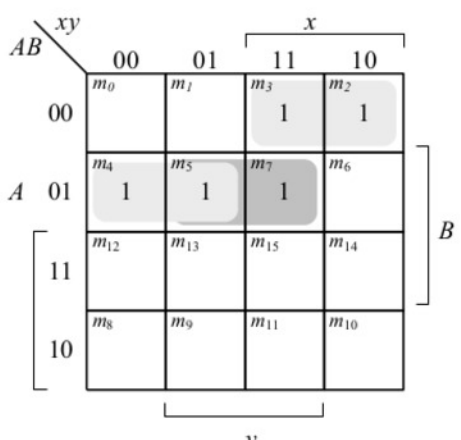
(b)

Present state		Inputs		Next state		Output	FF Inputs			
A	B	x	y	A	B	z	J_A	K_A	J_A	J_B
0	0	0	0	1	0	0	1	0	0	0
0	0	0	1	0	0	0	0	0	0	0
0	0	1	0	1	1	0	1	1	1	1
0	0	1	1	0	1	0	0	0	1	0
0	1	0	0	0	1	1	0	0	0	0
0	1	0	1	0	1	0	0	0	0	0
0	1	1	0	1	0	0	1	0	1	0
0	1	1	1	1	1	0	1	0	1	0
1	0	0	0	1	0	0	1	0	0	1
1	0	0	1	1	0	0	0	0	0	1
1	0	1	0	0	0	0	1	1	0	1
1	0	1	1	1	0	0	0	0	0	1
1	1	0	0	1	0	1	0	0	0	1
1	1	0	1	1	0	0	0	0	0	1
1	1	1	0	1	0	0	1	0	0	1
1	1	1	1	1	0	1	1	0	0	1

(c)



$A(t+1) = Ax' + Bx + Ay + A'B'y'$



$B(t+1) =$ A'B'x+A'Bx'+A'By

5.12 (b)

Present state	Next state 0	Next state 1	Output 0	Output 1
a	f	b	0	0
b	d	a	0	0
d	g	a	1	0
f	f	b	1	1
g	g	d	0	1