

заг 1

ТОА на уу

Начало

↓ a1

$\tilde{I}p := y; Pr := x;$
 $SH := 0; SL := 0$

$y_1 = \{y_{11}, y_{12}, y_{13}, y_{14}\}$

сб. уелносење през
инваријантно осигурање

↓ a2

$P = 0$

↓ y-2

↓ не
↓ a3

$\tilde{I}p = 0$

$SL := SL + Pr$

↓ a4

$SH := SH + c$

↓ a5

$\tilde{I}op := \tilde{I}op - 1$

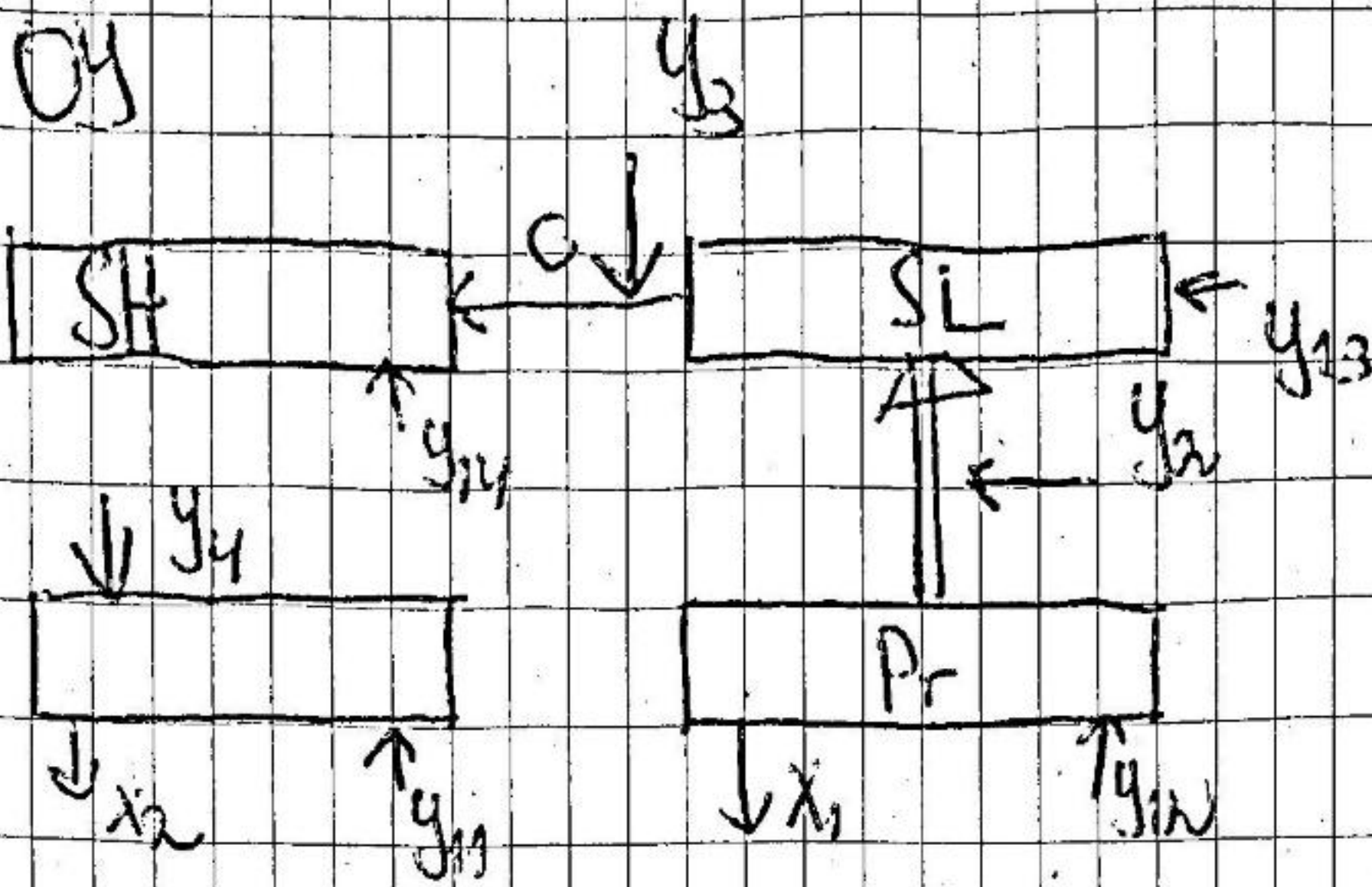
↓ a1

Криво

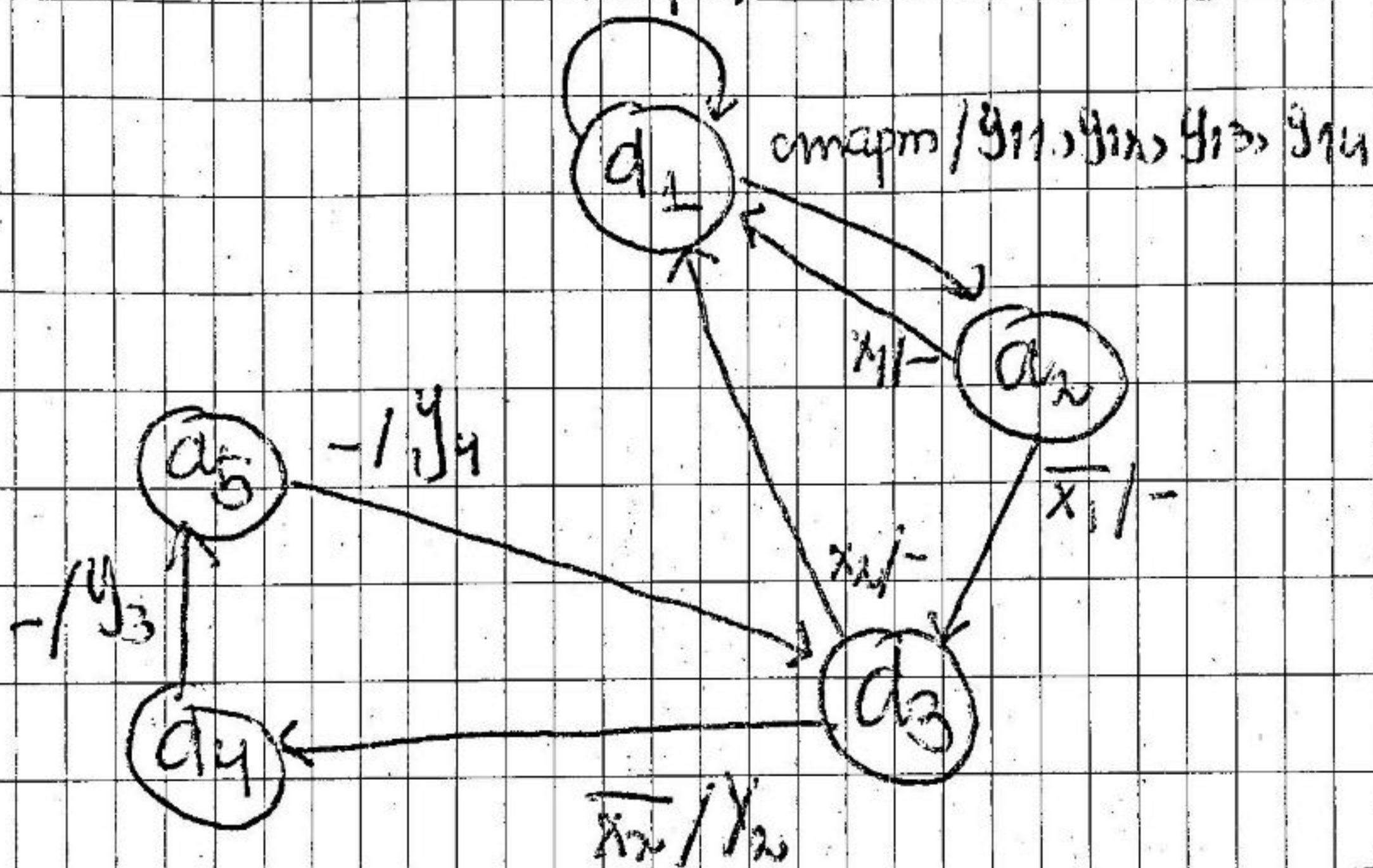
вс. ам.
за упр. у-е

Линија напредно

ампроување



Алгоритм на МММ-маршрутиране, граф



$a(t)$	код	времетра	код	$a(t+1)$	код	тригери		
	$Q_1 Q_2 Q_3$				$Q_1 Q_2 Q_3$	D_1	D_2	D_3
a_1	0 0 0	старт	-	a_1	0 0 0	0	0	0
		старт	$y_{11}, y_{12}, y_{13}, y_{14}$	a_2	0 0 1	0	0	1
a_2	0 0 1	x_1	-	a_1	0 0 0	0	0	0
		$\overline{x_1}$	-	a_3	0 1 1	0	1	1
a_3	0 1 1	x_2	-	a_1	0 0 0	0	0	0
		$\overline{x_2}$	y_{12}	a_4	1 1 1	1	1	1
a_4	1 1 1	-	y_3	a_5	1 1 0	1	1	0
a_5	1 1 0	-	y_4	a_3	0 1 1	0	1	1

$$y_{11} = y_{12} = y_{13} = y_{14} = \overline{Q_1} \overline{Q_2} \overline{Q_3} \text{ - output}$$

$$y_2 = \overline{Q_1} \cdot Q_2 \cdot Q_3 \cdot \overline{x_2}$$

$$y_3 = Q_1 \cdot Q_2 \cdot Q_3$$

$$y_4 = Q_1 \cdot Q_2 \cdot \overline{Q_3}$$

$$D_1 = \overline{Q_1} \cdot \overline{Q_2} \cdot \overline{Q_3} \cdot \overline{x_2} + Q_1 \cdot Q_2 \cdot Q_3$$

$$\frac{D_2}{Q_3} = \overline{Q_1} \cdot \overline{Q_2} \cdot \overline{Q_3} \cdot \overline{x_1} + \overline{Q_1} \cdot \overline{Q_2} \cdot Q_3 \cdot \overline{x_2} + Q_1 \cdot Q_2 \cdot Q_3 + Q_1 \cdot Q_2$$

$$D_3 = \overline{Q_1} \cdot \overline{Q_2} \cdot \overline{Q_3} \text{ - output} + \overline{Q_1} \cdot \overline{Q_2} \cdot Q_3 \cdot \overline{x_1} + Q_1 \cdot Q_2 \cdot Q_3 \cdot \overline{x_2} + Q_1 \cdot Q_2 \cdot Q_3$$