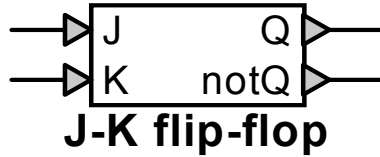


Flip-flop: J-K unlocked



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1 Description

This device is an implementation of an unlocked J-K flip-flop without override controls. For a version with the override controls, use the device "J-K unlocked full".

1.1 Pins

This device has four pins:

<i>pin</i>	<i>type</i>	<i>description</i>
J	input	J input
K	input	K input
Q	output	Q output
notQ	output	notQ output

1.2 Parameters

The initial value of Q must be defined if the device is possibly holding or toggling at $t=0$. When the device operates in clearing or setting mode at $t=0$, the initial value is ignored.

The value of the *stepped_mode* flag determines whether the device operates in *stepped* or *ramped* mode. In *stepped* mode (the default for ideal logical signals), the outputs are represented as stepped signals, where changes in value are observed as vertical steps at the time they occur. In *ramped* mode, the value transitions of the outputs are seen as ramps between $t-\Delta t$ and t .

<i>parameter</i>	<i>description</i>
Q_ini	initial value of Q if holding or toggling at $t=0$
stepped_mode	=1 to indicate stepped mode (default) =0 to indicate ramped mode

1.3 Input

The input pins may be connected to any control signals.

Numerical input values are automatically interpreted as logical values by this device, as follows:

<i>input</i>	<i>converted logical value</i>	<i>logical value representation</i>
value > 0	true	1
value ≤ 0	false	0

1.4 Output

The outputs are Q and its logical inverse *notQ*. Their representation as *stepped* or *ramped* signals is determined by the value given to the parameter *stepped_mode*.

The numerical representation of the output logical values is:

<i>output logical value</i>	<i>output numerical value</i>
true	1
false	0

1.5 Representation

The implementation of the model can be inspected by opening the device's subcircuit.

The model applies the following logic for determining its state:

<i>rule sequence</i>	<i>action</i>	<i>output</i>
if J>0 and K≤0	setting	Q(t) = 1
else if J≤0 and K>0	clearing	Q(t) = 0
else if J>0 and K>0	toggling	Q(t) = not Q(t-Δt)
else	holding	Q(t) = Q(t-Δt)
endif		
if holding at t=0	use Q_ini	Q(0) = Q_ini
if toggling at t=0	use Q_ini	Q(0) = Q_ini