OpenROV Controller 2.5 Rev B

Digital I/O Channels

0	BB UART	28	User J3-4
1	BB UART	29	User J3-2
2	User J3-11	30	User J2-16
3	User J3-9	31	User J2-14
4	User J3-7	32	User J2-12
5	User J3-5	33	User J2-10
6	Servo1 J8-1	34	User J2-8
7	Servo2 J8-4	35	User J2-6
8	Servo3 J8-7	36	User J2-4
9	Servo4 J8-10	37	User J2-2
10	Servo5 J8-13	38	N/C
11	Servo6 J8-16	39	N/C
12	PWM4 J1-7/8	40	N/C
13	LED	41	N/C
14	User J2-11	42	N/C
15	User J2-9	43	N/C
16	ESC Power Switch	44	PWM1 J1-1/2
17	N/C	45	PWM2 J1-3/4
18	User J2-7	46	PWM3 J1-5/6
19	User J2-5	47	N/C
20	I2C SDA J1-14	48	N/C
21	I2C SCL J1-12	49	LED
22	User J3-16	50	SPI MISO to BB and ICSP Header
23	User J3-14	51	SPI MOSI to BB and ICSP Header
24	User J3-12	52	SPI SCK to BB and ICSP Header
25	User J3-10	53	SPI SS to BB
26	User J3-8		
27	User J3-6		

Analog I/O Channels

0	Controller and BB Battery Current	
1	ESC 3 Current	
2	ESC 2 Current	
3	ESC 1 Current	
4	Battery Voltage (after protection diodes)	
5	Battery 2 Current	
6	Battery 1 Current	
7	Humidity (optionally populated)	
8	Board Temperature	
9	User	J4-14
10	User	J4-12
11	User	J4-10
12	User	J4-8
13	User	J4-6
14	User	J4-4
15	User	J4-2

Revision History

Rev	Date	Engr	Changes
--	13 Aug 2013	RWH	Initial Prototype
A	20 Aug 2013	RWH	Prototype Batch. Revised J6 connector orientation. Changed BB node names. Revised C11, C15, and U5 and added C34 to avoid +5V and +3.3V brownout when switching ESCs on. Revised ESC mounting holes. Revised LED colors. Revised silkscreen. Added weak Arduino reset pullup for standalone operation. Added cap slot C35 to hold vehicle on if noisy tether connection. Added bypass points J17 for ESC power switch. Arduino reset function moved from BB pin 13 to BB pin 11.
B	2 Sep 2013	RWH	First production batch. J6 changed from socket to male board stacker. 4th mounting hole added to board. Revised fiducial locations. Inverted logical case of UART LEDs. BB TX LED moved from Arduino space to BB space. Board ID EEPROM circuitry DNP.

Sheet Finder

OpenROV

Cover Page

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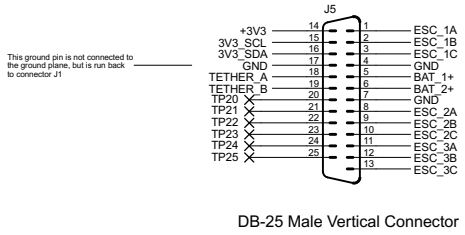
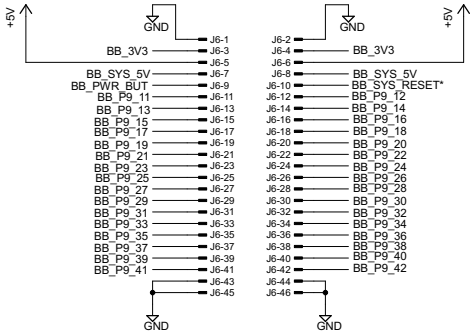
Wire Harness Connector

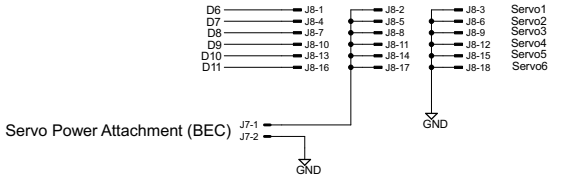


DB-25 Male Vertical Connector

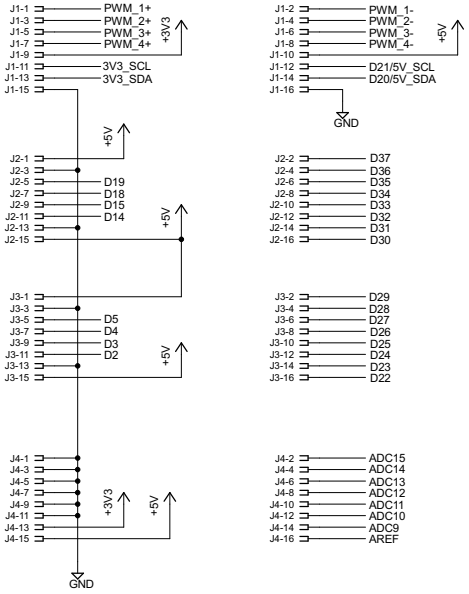
BeagleBone P9 Connector



Servo Outputs

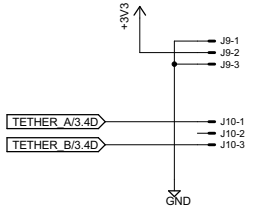


Header Sockets



Alignment Fiducials

Homeplug Adaptor Connectors



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Input / Output

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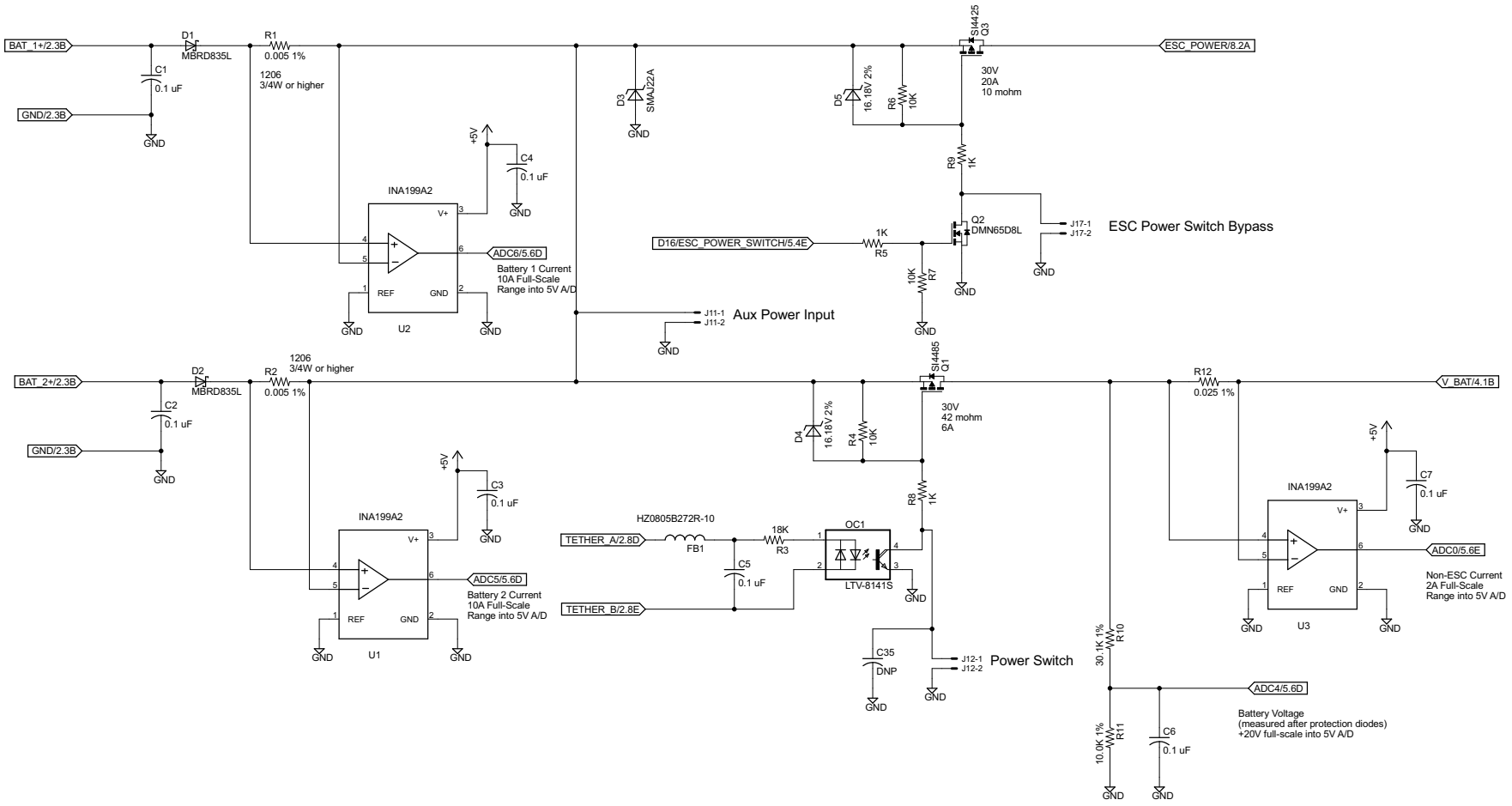

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Power Switching

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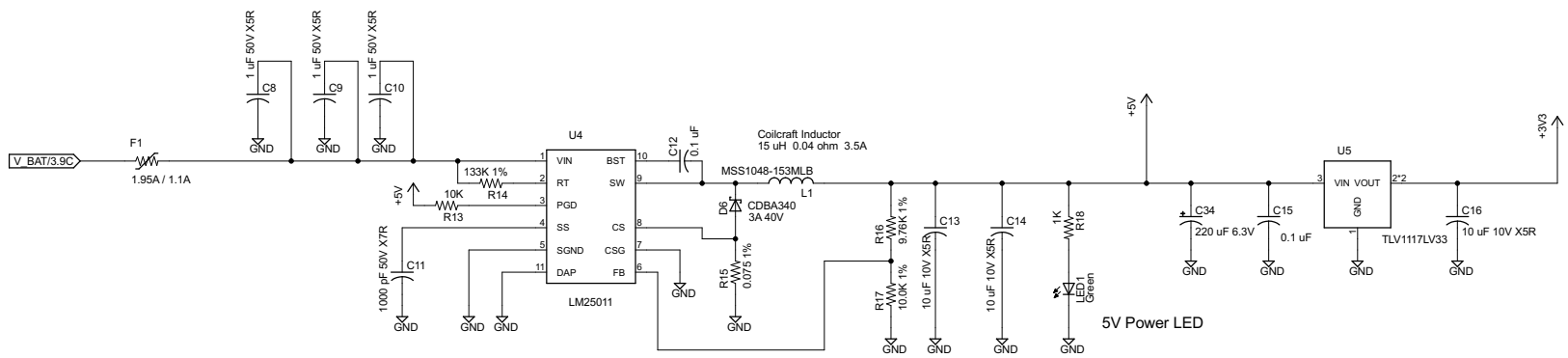

+5V Supply Adapted from the CircuitCo OpenROV Cape

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5V and 3.3V Power

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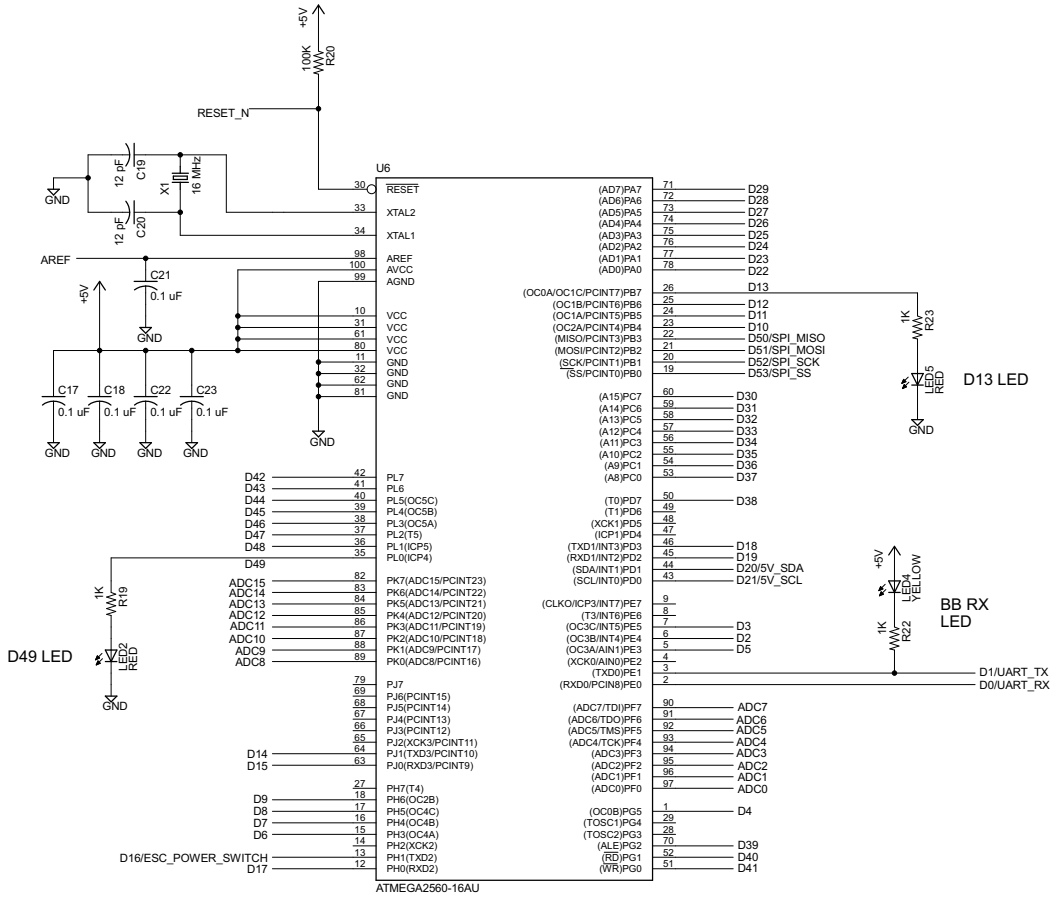

Adapted from Arduino Mega 2560 R3

OpenROV

Microcontroller

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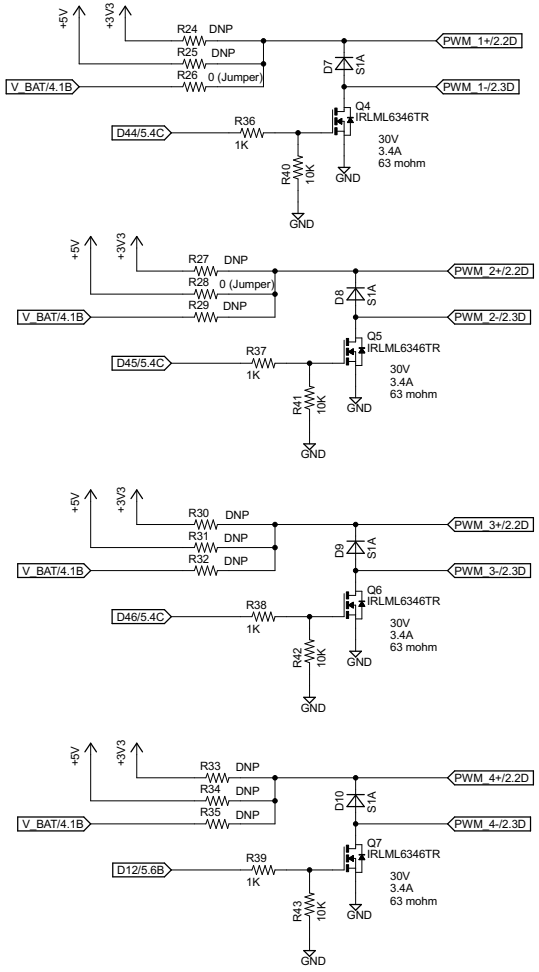
PWM Outputs

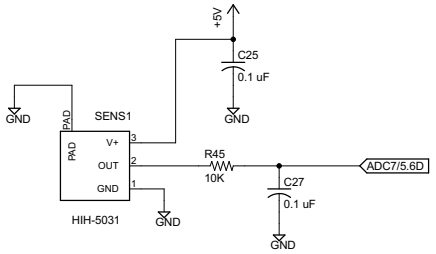
Populate one jumper only for each PWM channel.

Select from maximum output of 3.3V, 5V, or battery voltage

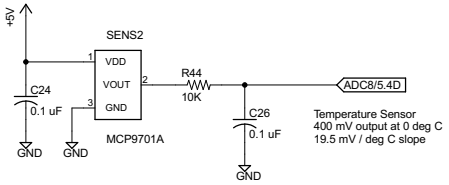
Default configuration is Battery Voltage on Channel 1 (LED Modules), and 5V on Channel 2 (Scaling Lasers)



Humidity Sensor



Temperature Sensor



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PWM and Environment Sensors

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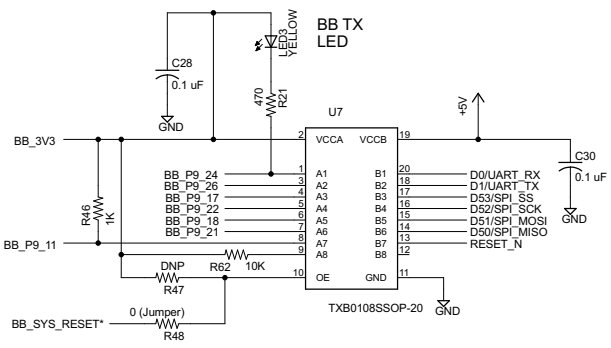
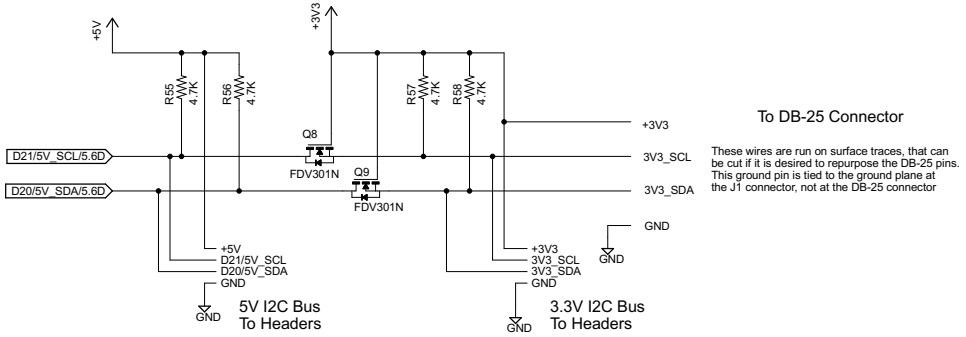
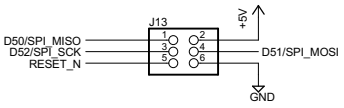
BeagleBone Interface



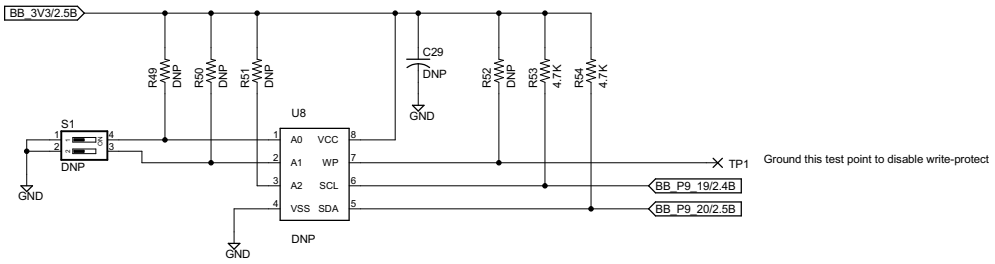
I2C Interface



ICSP Header



BeagleBone Cape ID



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I2C and BeagleBone Interface

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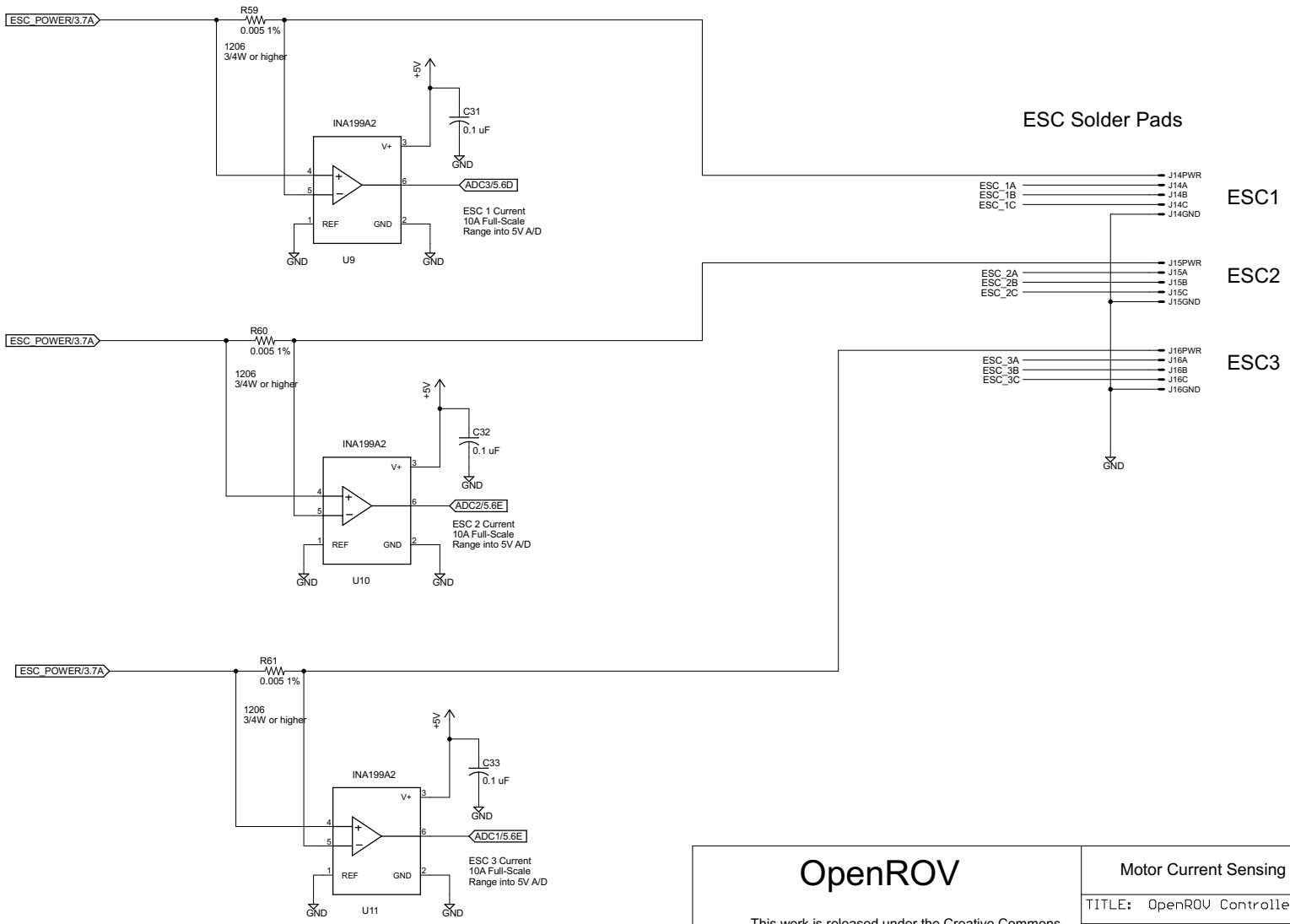

OpenROV

Motor Current Sensing and ESC Connections

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