

**Arduino Nano (Lidar Controller)** 2  
Microcontroller: Atmel ATmega168 or ATmega328  
Operating Voltage (logic level):5 V

**Lidar Controller Board** 3  
Hosting connections related  
to the lidar

**DC Converter** 4  
Converts the 11.1V into two  
5V 3A USB connections

**Power Distrubution Board** 5  
Splits the 11.1V into 4x 11.1V outputs

**Electronic Speed Controller (ESC)** 7  
Maximum current: 40 A  
Type: Brushed

**Raspberry Pi Camera** 14  
Max resolution: 1080p  
Connection: CSI  
Megapixels: 5

**T55 Crawler Engine** 12  
Motor type: Brushed  
Voltage input: 7-12V

**Lidar Lite V2 "Blue Label"** 1  
Range: 40 meters  
Accuracy: +/- 0.025m  
Power: 5V DC  
Current Consumption: <100mA continuous operation  
Acquisition Time: < 0.02 sec  
Rep Rate: 1-500Hz  
Interface: I2C or PWM

**Continuous rotation micro digital servo** 6  
Operating Voltage: 4.8-6Volts  
Speed: 0.12sec/60degree

**Secondary Power Distribution Board** 1  
5V DC + GND splitter

**Arduino Uno (Motor Controller)** 9  
Microcontroller: ATmega328P  
Operating Voltage: 5V  
Serial Connection: USB

**Raspberry pi 2 Model B** 10  
CPU: 900MHz quad-core ARM Cortex-A7  
RAM: 1GB  
USB ports: 4  
Camera interface (CSI)

**LiPo Battery** 11  
Voltage: 11.1  
Charge: 4300 mAh

**Steering Servo** 13  
Operating voltage: 5-6V  
Angular Limit: 60-125 degrees

DRAWN Andreas Fransson	2016-06-05	Group 1		
CHECKED		TITLE		
QA		CASP.ER		
MFG				
APPROVED				
		SIZE D	DWG NO 1	REV 3
		SCALE 1 / 2	SHEET 1 OF 1	