CRFC Tackle Sensor V4

User Manual

A close up of a circuit board

Description automatically generated

Figure - Tackle Sensor V4

# Revision History

|  |  |  |  |
| --- | --- | --- | --- |
| Revision | Date | Author | Description |
| 1 | 09/30/2024 | Eddie Hunckler | Initial draft. |

Table of Contents

[Revision History 2](#_Toc178548271)

[Introduction 3](#_Toc178548272)

[IO Electrical Characteristics 5](#_Toc178548273)

[Power Connector J2 5](#_Toc178548274)

[LED Connector J4 5](#_Toc178548275)

[Status Connector J5 5](#_Toc178548276)

[Getting Started 7](#_Toc178548277)

[Powering The Module 7](#_Toc178548278)

[Interfacing with LEDs 8](#_Toc178548279)

[Configuring the On-board Switches 8](#_Toc178548280)

[Configuring with Remote IO 9](#_Toc178548281)

[Configuring with the Serial UART 10](#_Toc178548282)

[Resources 13](#_Toc178548283)

# Introduction

The tackle sensor module is a subsystem designed to detect if an upsetting event or tackle has occurred during gameplay in the Collegiate Robotic Football Conference. This sensor is required to be rigidly mounted to the HDPE baseplate in a robot. For the latest rules regarding the tackle sensor, please see the Collegiate Robotic Football Conference website: <https://collegeroboticfootball.org/>.

This document will focus on the functional behavior of the tackle sensor subsystem as well as provide technical details for interfacing with the module.

The tackle sensor has four primary connectors labeled J1, J2, J4, and J5. (There is no J3!) J1 is used to program the device and should not be used by any team unless directed to by the Conference for the purposes of updating the firmware on the device. J2 must be used by every team as it provides power to the tackle sensor module. J4 can be connected to a 12V common anode LED strip or equivalent. J5 provides an advanced configuration interface for monitoring or controlling eligible or ineligible status, for monitoring or controlling home or away, for monitoring tackle state, or for configuring the home LED color via UART.

A circuit board with many different components

Description automatically generated

Figure - Connector Locations

The major features of the module are the following:

* Drives RGB LEDs indicating the robot system states which are as follows:
  + Tackled or not tackled
  + Eligible receiver or ineligible receiver
  + Home or away.
* Allows configuration of the system states via on-board configuration switches or via remote IO.
* Continuously monitor acceleration of the system at 100 Hz. If the filtered acceleration exceeds 2.5g in either the X or Y axis, the system triggers a tackle.
* A tackle lasts 1 second and the LEDs display red.
* During a tackle the Tackle status remote IO monitor pin changes state.
* Ineligible receivers are unable to be tackled.

# IO Electrical Characteristics

## Power Connector J2

|  |  |  |
| --- | --- | --- |
| Pin | Description | Requirements |
| 1 | GND | Power input ground. System ground. |
| 2 | V\_SUPPLY | Power input - 10V to 30V DC |

J2 has reverse polarity protection up to 30V DC. This will protect the system against damage if the submodule power connector is incorrectly wired.

## LED Connector J4

|  |  |  |
| --- | --- | --- |
| Pin | Description | Requirements |
| 1 | 12V+ | Power Output to LED Strips, 1A Maximum Current Source |
| 2 | RED | Open Collector, 500mA Maximum Current Sink |
| 3 | GREEN | Open Collector, 500mA Maximum Current Sink |
| 4 | BLUE | Open Collector, 500mA Maximum Current Sink |

J4 pin 1 has a PTC fuse with a trip current of 1.5A and hold current of 750mA with a time to trip of 100ms. This will help protect the system against too large of LED loads placed on the 12V output.

## Status Connector J5

|  |  |  |
| --- | --- | --- |
| Pin | Description | Requirements |
| 1 | UART TX | Serial UART command interface TX line. |
| 2 | UART RX | Serial UART command interface RX line. |
| 3 | TACKLE STATUS | Tackle status output. 3.3V Logic Output |
| 4 | HOME/AWAY | Home/away input or high impedance output. 3.3V Logic Input or Output. |
| 5 | ELIGIBLE/ INELIGIBLE | Eligible/ineligible input or high impedance output. 3.3V Logic Input or Output. |
| 6 | GND | System ground. |

The serial UART requires the following configuration: 115200 baud, 1 start bit, 8 data bits, no parity bit, 1 stop bit. (115200bps, 8N1).

The tackle sensor logic levels are as follows:

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| Condition | Pin 1 | Pin 2 | Pin 3 | Pin 4 | Pin 5 |
| TACKLED | X | X | L | X | X |
| NOT TACKLED (OK) | X | X | H | X | X |
| HOME | X | X | X | L | X |
| AWAY | X | X | X | H | X |
| ELIGIBLE | X | X | X | X | L |
| INELIGIBLE | X | X | H | X | H |

H: High Level – 3.3V

L: Low Level – 0V

X: Does not matter, is not affected.

# Getting Started

## Powering The Module

The system is powered through connector J2. The connectors on this module are all JST XHP style connectors with differing numbers of pins. For the power connector, the mating part will be a [XHP-2](https://www.digikey.com/en/products/detail/jst-sales-america-inc/XHP-2/555485) connector with mating connector pins [SXH-001T-P0.6N](https://www.digikey.com/en/products/detail/jst-sales-america-inc/SXH-001T-P0-6N/7041446). This is an extremely common form factor, and many equivalent substitutes exist if these are unavailable. High quality premade cables can also be purchased from standard suppliers and places like Amazon.

This device is designed to be compatible with a variety of different power systems with minimal additional circuitry requirements. The recommended supply voltage range is from 10V to 30V. Voltages less than 10V are possible to use with the system, but not recommended due to the higher current requirements.

The plot below shows the power requirements of the tackle sensor given various input supply voltages and LED loads. The LED loads will vary based on the style and the number of LEDs that will be driven. This chart is an actual performance measurement of the device and include inefficiencies that might exist within the device.

Figure - Supply Current Draw vs. Supply Voltages & Load Currents

**Example:**

Let’s assume I’m building a robot with a 24V battery, and I have chosen LED strips that require a maximum of 500mA. How much current will the tackle sensor draw?

I can look on the chart and see that the 500mA LEDs will require about 300mA at 24V. I can then include this in my power budget for the system that I’m creating.

## Interfacing with LEDs

For the power connector, the mating part will be a XHP-4 connector with mating connector pins [SXH-001T-P0.6N](https://www.digikey.com/en/products/detail/jst-sales-america-inc/SXH-001T-P0-6N/7041446). This is an extremely common form factor, and many equivalent substitutes exist if these are unavailable. A standard common anode RGB LED strip will be compatible with this output as they are typically 12V compatible and they have integrated current limiting resistors.

A diagram of a circuit

Description automatically generated

Figure - Example LED Connection

## Configuring the On-board Switches

The system state can be configured using the on-board DIP switches. The table below indicates the switch position and the system state. The system state is also printed on the tackle sensor itself for ease of use.

|  |  |
| --- | --- |
| Description | Switch Configuration |
| Tackle sensor is eligible. Tackle sensor is home. |  |
| Tackle sensor is ineligible. Tackle sensor is home. |  |
| Tackle sensor is ineligible.  Tackle sensor is away. |  |
| Tackle sensor is eligible. Tackle sensor is away. |  |

## Configuring with Remote IO

The tackle sensor system is also configurable using remote IO lines that can be connected to custom circuitry to set the tackle sensor operating state. The tackle sensor subsystem is compatible with 3.3V logic levels. When using 3.3V compatible system logic, the inputs and outputs can be directly monitored with a microcontroller or controlled with a microcontroller output.

The tackle output pin can be monitored with a digital input on a microcontroller. The inputs need to be set to high impedance input mode. Then the state of the TACKLE STATUS can be monitored. Additionally, the HOME/AWAY and the ELIGIBLE/INELIGIBLE status pins can be monitored via microcontroller inputs. When monitored via high impedance inputs, the switches on the tackle sensor PCBs control the configuration mode of the tackle sensor.

A screenshot of a computer

Description automatically generated

Figure - Monitor Remote IO with MCU Inputs

Alternatively, the HOME/AWAY and the ELIGIBLE/INELIGIBLE status pins can be driven by 3.3V logic levels externally. When doing this, the states of the switches on-board the tackle sensor are ignored, and the logic level driven to each pin is what determines the state of the tackle sensor. This provides a way to interface the custom microcontroller system to the tackle sensor. The system designer could then be able to remotely toggle between home and away or eligible and ineligible.

A computer screen shot of a diagram

Description automatically generated

Figure - Control Remote IO with MCU Outputs

## Configuring with the Serial UART

The simplest way to configure a tackle sensor is to build up a small cable that includes a USB to UART and the J5 connector. This adapter gives the designer the ability to easily send commands to the tackle sensor for configuration purposes. When configuring the tackle sensor, the changes are stored in non-volatile on-board memory.

Below is a diagram of the wiring between a USB to UART adapter and the XHP-6 connector that will interface with the Status Connector on the tackle sensor. Please note that the TX line from the USB to UART adapter goes to the RX line on the tackle sensor and the RX line from the USB to UART goes to the TX line on the J5 connector.

A red and black electrical device

Description automatically generated

Figure - Serial UART Wiring Diagram

Configure the USB to UART at a baudrate of 115200 with the configuration of 8 data bits, no parity bit, and 1 stop bit. The configuration is 115200-8-N-1. A serial terminal can be used to directly send and receive the messages.

The following commands and responses are available.

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| **Function** | **Character (Hex)** | **Example Command** | **Example Response** | **Description** |
| Set RGB Value | l (0x6C) | l:255,255,0\n | l:255,255,0\n | Set the RGB value of the home LED. Saved to settings with each send. Limit to less than 10,000 lifetime sends. |
| Get Acceleration | a (0x61) | a\n | a:0,0,1000\n | Reports the latest acceleration X, Y, and Z in milli-g. |
| Get Acceleration Magnitude Range | r (0x72) | r\n | r:0,100,0,100\n | Reports the minimum and maximum acceleration observed since the last call to this function. Min X, Max X, Min Y, and Max Y in milli-g. |
| Get Home Away Status | h (0x68) | h\n | h:1\n | Home = 1. Away = 0. |
| Get Eligible Status | e (0x65) | e\n | e:1\n | Eligible = 1. Ineligible = 0. |
| Get Tackled Status | t (0x74) | t\n | t:0\n | Tackled = 1. Not tackled = 0. |
| Get Firmware Version | v (0x76) | v\n | v:0.0.0\n | Reports the firmware version. |

This protocol has been fully implemented in a webapp that can be found hosted on GitHub: <https://collegiate-robotic-football-conference.github.io/tackle-sensor-utility/>. This requires a Chrome browser to work properly. Once connected, the information will be pulled from the device periodically. The minimum and maximum acceleration in the X and Y directions will be plotted in real-time. The Home Jersey color can be selected with the color picker.

A screenshot of a computer

Description automatically generated

Figure - Tackle Sensor Configurator Web App

Resources  
The latest design files and firmware can be found on the Collegiate Robotic Football Conference GitHub page.

* Firmware - <https://github.com/Collegiate-Robotic-Football-Conference/tackle-sensor-firmware>
* Hardware - <https://github.com/Collegiate-Robotic-Football-Conference/tackle-sensor-hardware>
  + Reference Sheet PDF - <https://github.com/Collegiate-Robotic-Football-Conference/tackle-sensor-hardware/blob/main/Releases/REV2_02_04_2024/reference_sheet_rev2.pdf>
  + Schematic PDF - <https://github.com/Collegiate-Robotic-Football-Conference/tackle-sensor-hardware/blob/main/Releases/REV2_02_04_2024/schematic_sheet_rev2.pdf>
  + 3D Model STEP File - <https://github.com/Collegiate-Robotic-Football-Conference/tackle-sensor-hardware/blob/main/Releases/REV2_02_04_2024/tackle_sensor_hardware.STEP>
* Configuration Utility - <https://github.com/Collegiate-Robotic-Football-Conference/tackle-sensor-utility>

A black background with a black square

Description automatically generated with medium confidence

A diagram of a computer

Description automatically generated