Sheet1

	States						
	in	in	out	out	out		
	auto	ctrl	auto	manual	manip		
		0 (	<mark>)</mark>	0	0	1	
		0 :	<mark>1</mark>	0	1	0	
		1 (	<mark>)</mark>	0	0	1	
		1 :	<mark>1</mark>	1	0	0	
	in	in	in	in	out	out	
	IsDriveCont	auto	manual	manip	uart	ppm	
		0 (	)	0	0	0	0
		0 (	)	0	1	0	1
		0 (	)	1	0	0	0
NA			)	1	1		
		0 :	1	0	0	0	0
NA		0 :	1	0	1		
NA		0 :	1	1	0		
NA		0 :	1	1	1		
		1 (	)	0	0	0	0
		1 (	)	0	1	0	0
		<u> </u>	)	1	0	0	1
NA			)	1	1		
		1 :	1	0	0	1	0
NA		1 :	1	0	1		
NA		1	1	1	0		
NA		1	1	1	1		

only if auto an If (manual ANI

## Sheet1

All possible states of rover operation are extracted in this chart.

Control inputs include:

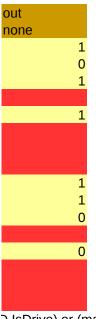
- 1. "auto" for choosing autonomous drive mode ( = 1) or manua
- 2. "ctrl" for choosing drive mode ( = 1) or manipulation mode

Manipulation can be chosen with two possible combinations, since

Final outputs tell the MCU where to get control data:

- 1. "uart" is the port for autonomous contol data input
- 2. "ppm" is the port for manual control data input

The input "IsDriveCont" is a boolean value which can easily be set chip's use. The chip can be used as the motor Drive controller, or tl



D IsDrive) or (manip AND !IsDrive)

Sheet1

there is no autonomous manipulation.

t in the MCU firmware to define the he Manipulation controller.