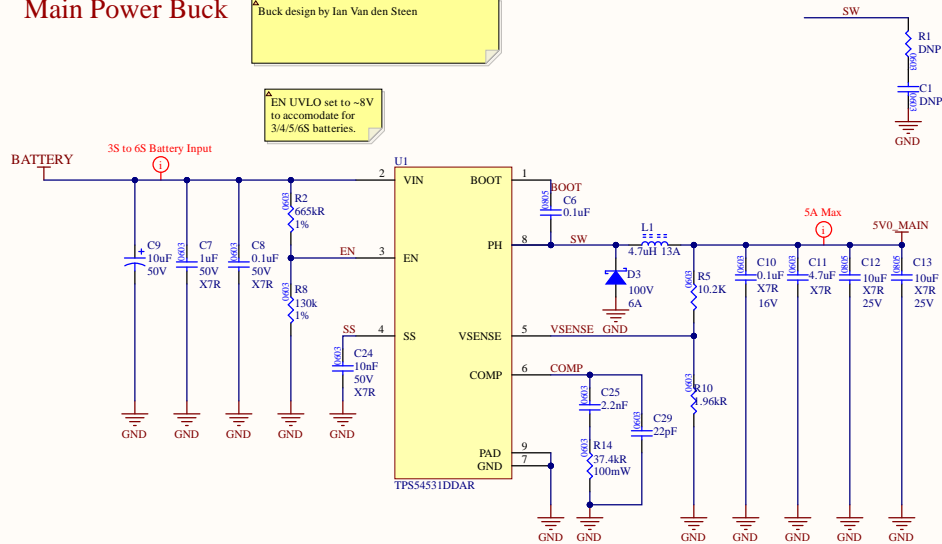


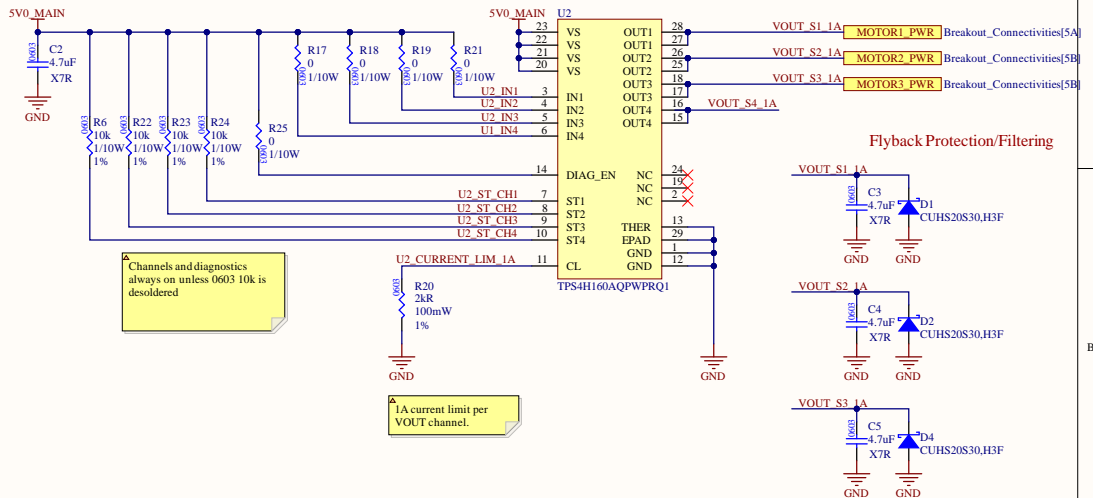
Main Power Buck

Buck design by Ian Van den Steen

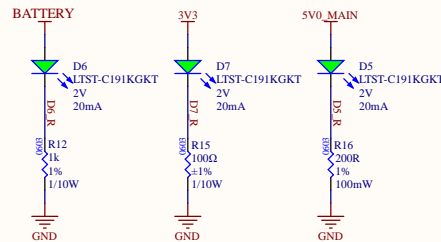
EN UVLO set to ~8V to accommodate for 3/4/5/6S batteries.



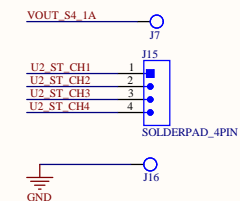
Motor Overcurrent Protection



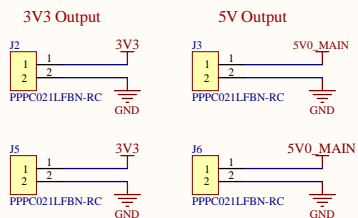
Power/Connection Indicators



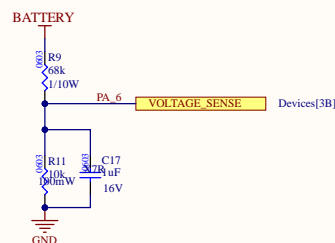
Test Points



Power Outputs



Input Voltage Sensing



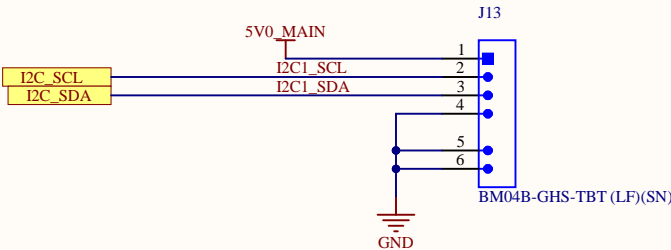
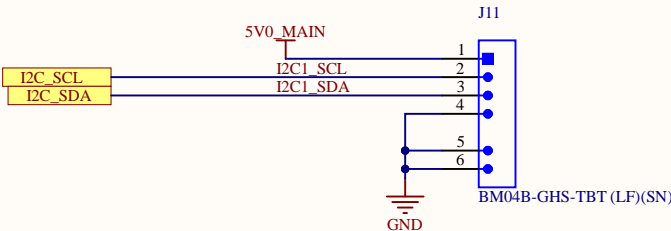
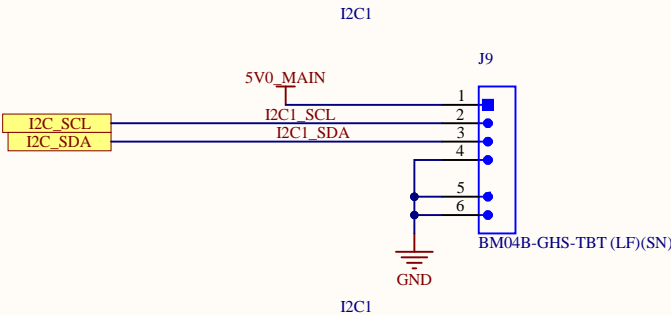
Input Power



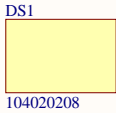
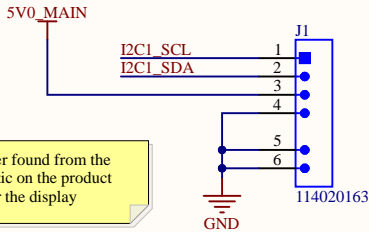
WARG		Waterloo Aerial Robotics Group 200 University Ave W Waterloo, Ontario, Canada N2L 3G1	
PROJECT	M3 Tracking Antenna Controller Rev 2.PrjPcb, [No Variations]		REVISION
DOCUMENT	Power.SchDoc		MODIFIED
ENGINEER	Ryan Scornazzon		2024-11-12
REVIEWER	*		SHEET 1 OF 3

Connector pin order follows Pixhawk Standards

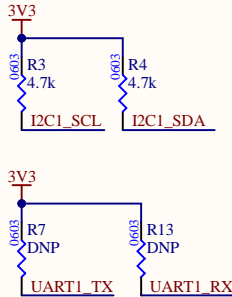
I2C Connectors (IMU+Barometer+Extra)



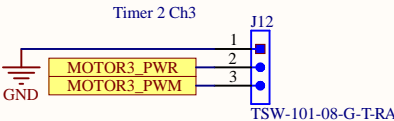
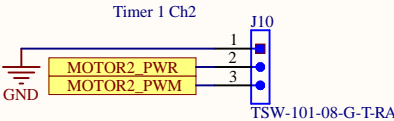
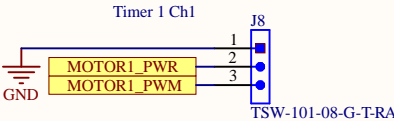
Display Connector/Display



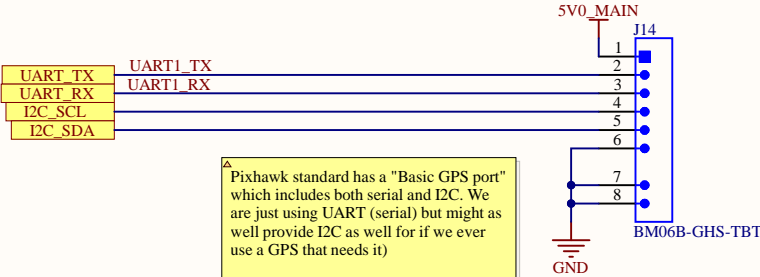
Pullups



PWM Servo Headers



UART Connector (GPS)



Pixhawk standard has a "Basic GPS port" which includes both serial and I2C. We are just using UART (serial) but might as well provide I2C as well for if we ever use a GPS that needs it)



Waterloo Aerial Robotics Group
200 University Ave W
Waterloo, Ontario, Canada
N2L 3G1



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DOCUMENT
Breakout_Connectivities.SchDoc

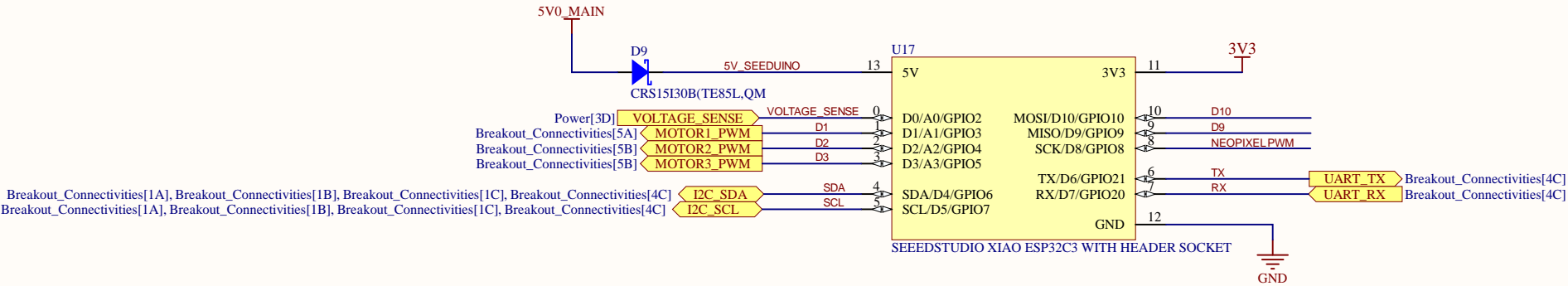
MODIFIED
2024-11-04

ENGINEER
Ryan Scomazzon

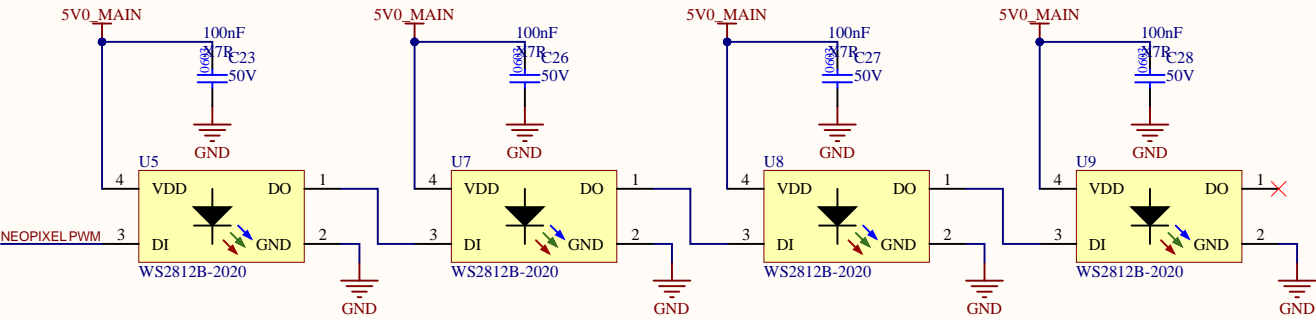
REVIEWER
*

SHEET 2 OF 3

SEEDUINO



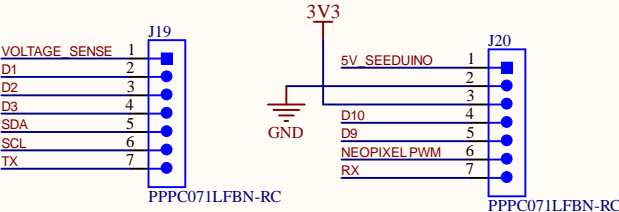
NEOPIXELS



Debug headers

Mechanical

MH1 MH2 MH3 MH4



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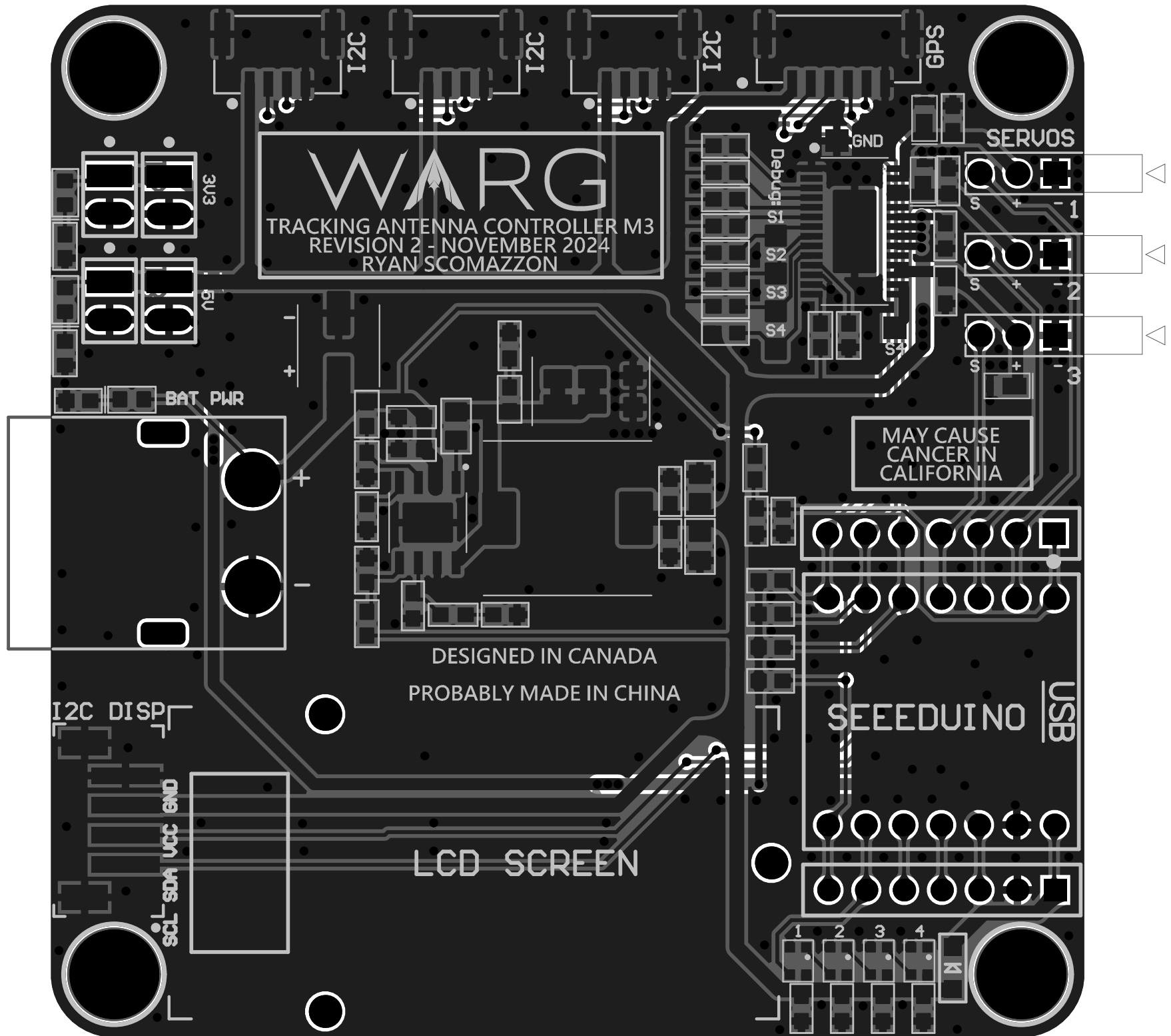
DOCUMENT
Devices.SchDoc

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2024-11-04

ENGINEER
Ryan Scomazon

REVIEWER
*

SHEET 3 OF 3



Board Stack Report