

	Energia	J1	J3	Energia		Energia	J4	J2	Energia
	pin #	1	21	pin #		pin #	40	20	pin #
CC2650/CC3100	1	3.3V	5V	21			P2.7	GND	20
CC2650	2	P6.0	GND	22	PWM/L, Left Motor PWM	39	P2.6	P2.5	19
CC2650/CC3100	3	P3.2	P6.1	23	PWM/R, Right Motor PWM	40	P2.4	P3.0	18
CC2650/CC3100	4	P3.3	P4.0	24	PWM Arm Height Servo	38	P2.4	P3.0	18
	5	P4.1	P4.2	25	CC3100, UART1_CTS	37	P5.6	P5.7	17
nHIB	6	P4.3	P4.4	26	CC3100, UART1_RTS	36	P6.6	IRST	16
Bump 2 [3]	7	P1.5	P4.5	27	CC2650	35	P6.7	P1.6	15
CC3100, SPI_CLK	8	P4.6	P4.7	28	CC3100, NWP_LOG_TX	34	P2.3	P1.7	14
Bump 4 [3]	9	P6.5	P5.4	29	CC3100, WLAN_LOG_TX	33	P5.1	P5.0	13
UCBISCL [4]	10	P6.4	P5.5	30	PWM Arm Tilt Servo	32	P3.5	P5.2	12
UCBISDA [4]					nsLPL [2] / nsLPR [2]	31	P3.7	P3.6	11

[1] This is encoder output. Sever VPU=VREG jumper and connect VPU to 3.3V

[2] This disables a motor driver. 0 to sleep/stop. Sever VCCMD=VREG jumper and connect VCCMD to 3.3V. Consider severing nSLPL=nSLPR jumper.

[3] Use Port 4 for edge-triggered interrupts

[4] Primary I2C channel supported by Enerigia

Bump 0 is right side of robot, Bump 5 is left side

CTRL on the motor board is a power switch. A high pulse (>1V) turns on the switch; a low pulse turns off the switch and power to the microcontroller. Leave this pin floating (an input) for normal operation.

Yellow highlights changes from previous pin assignments

Red highlights changes from version 4

Grey is changes from version 5

Orange needs to verify with Jan if routing possible to combine nSLP to free up an additional PWM pin

[illegible]