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	CC2650/CC3100	CC3100		_	P3.3	P4.0	24		Bump 0 [3]	ت				CC31	CC3100, UART1_CTS	T1_CTS	37	-	5.6	P5.7	17	available
		nHIB	5	_	P4.1	P4.2	25		Bump 1 [3]					CC31	CC3100, UART1_RTS	T1_RTS	36	-	P6.6	IRST	16	CC2650/
	Bun	Bump 2 [3]	6	_	P4.3	P4.4	26		TExaS scope input	pe inpu	+					CC2650	35	_	P6.7	P1.6	15	CC3100 S
	CC3100, SPI_CLK	SPI_CLK	7	_	P1.5	P4.5	27		Bump 3 [3]	_			CC	3100,	CC3100, NWP_LOG_TX	OG_TX	34	_	P2.3	P1.7	14	CC3100 S
	Bun	Bump 4 [3]	8	_	P4.6	1		I	Cl g dun	Ť	ı		<u>ც</u>	3100, \	CC3100, WLAN_LOG_TX	.OG_TX	33	_	P5.1	P5.0	13	ERB (3.3
	UCB1	UCB1SCL [4]	9	_	P6.5	P5.4	29		DIR_L				Ī	PWM	PWM Arm Tilt Servo	t Servo	32		33.5	P5.2	12	ELB (3.3\
	UCB1	UCB1SDA [4]	10		P6.4	P5.5	30	O DIR.	R R				T	nSLPL	nSLPL [2] / nSLPR [2]	LPR [2]	31	_	P3.7	P3.6	11	PWM Gr
Notes:																						
[1] This is	[1] This is encoder output. Sever VPU=VREG jumper and connect VPU to 3.3V	utput. S	Sever V	PU=VR	EG jum	per and	connec	t VPU to	3.3													
[2] This di	[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.	otor dri	ver. 0	to slee	p/stop.	Sever \	/CCMD:	=VREG j	umper :	and cor	nect V	CCMD t	o 3.3V.	Cons	ider sev	ering n	SLPL=n	SLPR ju	ımper.			
[3] Use Po	[3] Use Port 4 for edge-triggered interrupts	ge-trigg	ered in	terrupt	.S																	
[4] Primar	[4] Primary I2C channel supported by Energia	nel supi	ported	by Ene	rgia																	
Bump 0 is	Bump 0 is right side of robot, Bump 5 is left side	of robot	t, Bump	5 is le	ft side																	
CTRL on th	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 microco	oard is	a powe	er switc	h. A hi	gh puls	e (>1V)	turns or	the sw	/itch; a	low pul	se turn	s off th	e swit	ch and	power t	o the n	nicrocc	ontroller	ntroller. Leave this pin floating (an	is pin flo	pati
Yellow hig	Yellow highlights changes from previous pin assignments	inges fr	om pre	vious p	oin assig	gnment	U)															
Red highli	Red highlights changes from version 4	es from	versio	n 4																		
Grey is ch	Grey is changes from version 5	version	n 5																			
Orange ne	Orange needs to verify with Jan if routing possible to combine nSLP to free up an additional PWM pin	ify with	Jan if r	outing	possibl	e to cor	nbine n	SLP to f	ree up a	an addir	tional P	WM pii	3									
J5:																						
				no energia	ergia					L			L									
	OPT3101 Yellow Front Right LED	Ovigent IR Distance \	ovi92 trigiaH miA golsnA	(bbo) ətenimulli rəqqirə golenA	AUXR IR Distance \ OPT3101 GETlectance LED	Reflectance 3	Reflectance 1	NokiaS110 CS	Nokia5110 CD	Yellow Front Left LED	Reflectance 4	Programme Reflectance 6	available in UCB3CLK (not available in	UCB3SDA (not	ERA (3.3V)[1]							
Energia #	41 42	2 43	3 44	1 45	3 46	47	48	49	50	51	52	53	54	55	56	5/	3.3V (	GND				
	P8.5 P9.0	.0 P8.4	4 P8.2	2 P9.2	2 P6.2	2 P7.3	P7.1	P9.4	P9.6	P8.0	P7.4	P7.6 F	P10.0 P10.2		P10.4	5/	3.37	GND				
	P8.6 P8.7	.7 P9.1	1 P8.3	3 P5.3	3 P9.3	3 P6.3	P7.2	P7.0	P9.5	P9.7	P7.5	P7.7 F	P10.1 P10.3		P10.5	5/	3.37	GND				
Energia #	57 58	G	60	6	62	63	64	65	66	67	68	69	70	71	72	5/	3.37	GND				
	TED CED	TOTET9O	Servo	(nəvə) ətenimull	ION OTTCHIADI	TOTEINO	7 әэшегэәцәу	Reflectance 0	Nokia5110 Clock				+ :d di 5XIIV	UCB3SCL (not available in	ELA (3.3V) [1]							
	11/19/2018 changes from version 6, jan@pololu.com	8 chang	ges from	m versi	on 6, ja	n@polo	olu.com															
	2/11/2019 changes	change	e from	from rom05a02	5-00	-	(National Association of the Control	1														

Energia   11   13   Energia   14   13   Energia   14   14   15   Energia   15   15   15   15   15   15   15   1								
Din # 1 21   CC2650/CC3100	Energia			Energia	J4	J2	Energia	
CC2650/CC3100	pin#			pin#	40	20	pin #	
CC2650/CC3100   2		CC2650/CC3100	PWML, Left Motor PWM	40	P2.7	GND	20	CC2650/CC3100
CC2650/CC3100   3   P3.2   P6.1	<b>22</b> C(	CC2650/CC3100	PWMR, Right Motor PWM	39	P2.6	P2.5	19	CC2650/CC3100
CC2650/CC3100	23 (	Center IR Distance / OPT3101	PWM Arm Height Servo	38	P2.4	P3.0	18	CC3100, SPI_CS, GPIO
Bump 2 [3] 6 P4.1 P4.2  Bump 2 [3] 6 P4.3 P4.4  CC3100, SPI_CLK 7 P1.5 P4.5  Bump 4 [3] 8 P4.6 P5.4  UCB1SCL [4] 9 P6.5 P5.4  UCB1SDA [4] 10 P6.4 P5.5  UCB1SDA [4] 10 P6.4 P5.5  Port 4 for edge-triggered interrupts  Is right side of robot, Bump 5 is left side of robot, Bump 5 is left side on the motor board is a power switch. A high pulse (> highlights changes from version 4  changes from version 4  needs to verify with Jan if routing possible to combinate of the pulse to combinate in the pulse to combinate	24 Bı	Bump 0 [3]	CC3100, UART1_CTS	37	P5.6	P5.7	17	available GPIO? / OPT3101 RST?
Bump 2 [3] 6 P4.3 P4.4  CC3100, SPI_CLK 7 P1.5 P4.5  Bump 4 [3] 8 P4.6 P5.4  UCB1SCL [4] 9 P6.5 P5.4  UCB1SDA [4] 10 P6.4 P5.5  UCB1SDA [4] 10 P6.4 P5.5  Is encoder output. Sever VPU=VREG jumper and core idisables a motor driver. O to sleep/stop. Sever VCC Port 4 for edge-triggered interrupts  Port 4 for edge-triggered interrupts  Is right side of robot, Bump 5 is left side  Is right side of robot, Bump 5 is left side  In the motor board is a power switch. A high pulse (> highlights changes from previous pin assignments philights changes from version 4  Changes from version 4  Bump 2 [3] P4.3 P4.5  P5.5  P5.4  P5.5  P5.4  P5.5  P5.4  P5.5  P6.4  P6.5  P6.5  P6.4  P6.6  P6.4  P6.6  P6.4  P6.6	25 Bı	Bump 1 [3]	CC3100, UART1_RTS	36	P6.6	IRST	16	CC2650/CC3100
Bump 4 [3] 8 P4.6  Bump 4 [3] 8 P4.6  UCBISCL [4] 9 P6.5 P5.4  UCBISDA [4] 10 P6.4 P5.5  UCBISDA [4] 10 P6.4 P5.5  is encoder output. Sever VPU=VREG jumper and core disables a motor driver. O to sleep/stop. Sever VCC Port 4 for edge-triggered interrupts  Port 4 for edge-triggered by Energia  Dis right side of robot, Bump 5 is left side  In the motor board is a power switch. A high pulse (> highlights changes from previous pin assignments phights changes from version 4  changes from version 4  paged to verify with Jan if routing possible to combinate the possible to combinate the possible to combinate the province of the possible to combinate the province of the possible to combinate the possible to combinate the possible to combinate the possible to combinate the province province the possible to combinate the possible to combin	26 TE	TExaS scope input	CC2650	35	P6.7	P1.6	15	CC3100 SPI MOSI
Bump 4 [3] 8 P4.6  UCB1SCL [4] 9 P6.5 P5.4  UCB1SDA [4] 10 P6.4 P5.5  is encoder output. Sever VPU=VREG jumper and cordisables a motor driver. O to sleep/stop. Sever VCC Port 4 for edge-triggered interrupts  Port 4 for edge-triggered interrupts  ary I2C channel supported by Energia Dis right side of robot, Bump 5 is left side on the motor board is a power switch. A high pulse (> highlights changes from version 4  changes from version 4  a needs to verify with Jan if routing possible to combine to the possible t	27 Bı	Bump 3 [3]	CC3100, NWP_LOG_TX	34	P2.3	P1.7	14	CC3100 SPI MISO
UCB1SCL [4] 9 P6.5 P5.4  UCB1SDA [4] 10 P6.4 P5.5  UCB1SDA [4] 10 P6.4 P5.5  Is encoder output. Sever VPU=VREG jumper and cordisables a motor driver. O to sleep/stop. Sever VCC Port 4 for edge-triggered interrupts  Port 4 for edge-triggered interrupts  Pary I2C channel supported by Energia  Tary I2C channel supported by Energia  Tary I2C channel supported by Energia  The motor board is a power switch. A high pulse (> highlights changes from previous pin assignments phights changes from version 4  Changes from version 4  The motor board is a power switch. A high pulse (> highlights changes from version 4  Changes from version 5	20	Damp 5 [3]	CC3100, WLAN_LOG_TX	33	P5.1	P5.0	13	ERB (3.3V) [1]
UCB1SDA [4] 10 P6.4 P5.5  is encoder output. Sever VPU=VREG jumper and core disables a motor driver. O to sleep/stop. Sever VCC Port 4 for edge-triggered interrupts narry I2C channel supported by Energia D is right side of robot, Bump 5 is left side not the motor board is a power switch. A high pulse (> highlights changes from previous pin assignments phlights changes from version 4 changes from version 5 needs to verify with Jan if routing possible to combine and the combine provided that the combine provided the combine provided that the combine provided the combine provided that t	29 D	DIR_L	PWM Arm Tilt Servo	32	P3.5	P5.2	12	ELB (3.3V)[1]
is encoder output. Sever VPU=VREG jumper and cordisables a motor driver. O to sleep/stop. Sever VCC Port 4 for edge-triggered interrupts nary 12C channel supported by Energia 1 is right side of robot, Bump 5 is left side not motor board is a power switch. A high pulse not motor board is a power switch. A high pulse not motor board is a power switch. A high pulse not motor board is a power switch. A high pulse not motor board is a power switch. A high pulse not motor board is a power switch. A high pulse shighlights changes from version 4 changes from version 5 meeds to verify with Jan if routing possible to combined to the combine	30 D	DIR_R	nSLPL [2] / nSLPR [2]	31	P3.7	P3.6	11	PWM Gripper Servo
is encoder output. Sever VPU=VREG jumper and cordisables a motor driver. 0 to sleep/stop. Sever VCC Port 4 for edge-triggered interrupts  nary I2C channel supported by Energia  is right side of robot, Bump 5 is left side  n the motor board is a power switch. A high pulse (> highlights changes from previous pin assignments phlights changes from version 4  changes from version 5  needs to verify with Jan if routing possible to combine to the combine series of								
disables a motor driver. O to sleep/stop. Sever VCC Port 4 for edge-triggered interrupts nary I2C channel supported by Energia  J is right side of robot, Bump 5 is left side n the motor board is a power switch. A high pulse (> highlights changes from previous pin assignments highlights changes from version 4 changes from version 5 needs to verify with Jan if routing possible to combine procession of the combine procession of the combine process of the com	onnect VPU t	to 3.3V						
Port 4 for edge-triggered interrupts  nary I2C channel supported by Energia ) is right side of robot, Bump 5 is left side  n the motor board is a power switch. A high pulse (> highlights changes from previous pin assignments phighlights changes from version 4 changes from version 5  needs to verify with Jan if routing possible to combinate the provided specific combinate in the provided specific possible to combinate the provided specific possible the provided	CMD=VREG	jumper and connect VCCMD	to 3.3V. Consider severing nS	LPL=nSLPR	jumper.			
nary I2C channel supported by Energia ) is right side of robot, Bump 5 is left side n the motor board is a power switch. A high pulse (>) highlights changes from previous pin assignments phlights changes from version 4 changes from version 5 needs to verify with Jan if routing possible to combine								
) is right side of robot, Bump 5 is left side 1 the motor board is a power switch. A high pulse (>) highlights changes from previous pin assignments phlights changes from version 4 changes from version 5 needs to verify with Jan if routing possible to combine								
the motor board is a power switch. A high pulse (x) highlights changes from previous pin assignments phights changes from version 4 changes from version 5 changes from version 5 paeeds to verify with Jan if routing possible to combine the combine of the combine the combine of								
highlights changes from previous pin assignments shlights changes from version 4 changes from version 5 areeds to verify with Jan if routing possible to combinated to the com	>1V) turns o	on the switch; a low pulse turi	ns off the switch and power to	the micro	controller	Leave ti	is pin flo	ntroller. Leave this pin floating (an input) for normal operation.
hlights changes from version 4 changes from version 5 needs to verify with Jan if routing possible to combinated to the								
changes from version 5 needs to verify with Jan if routing possible to combi								
needs to verify with Jan if routing possible to combin								
		from on additional DW/M n	5					