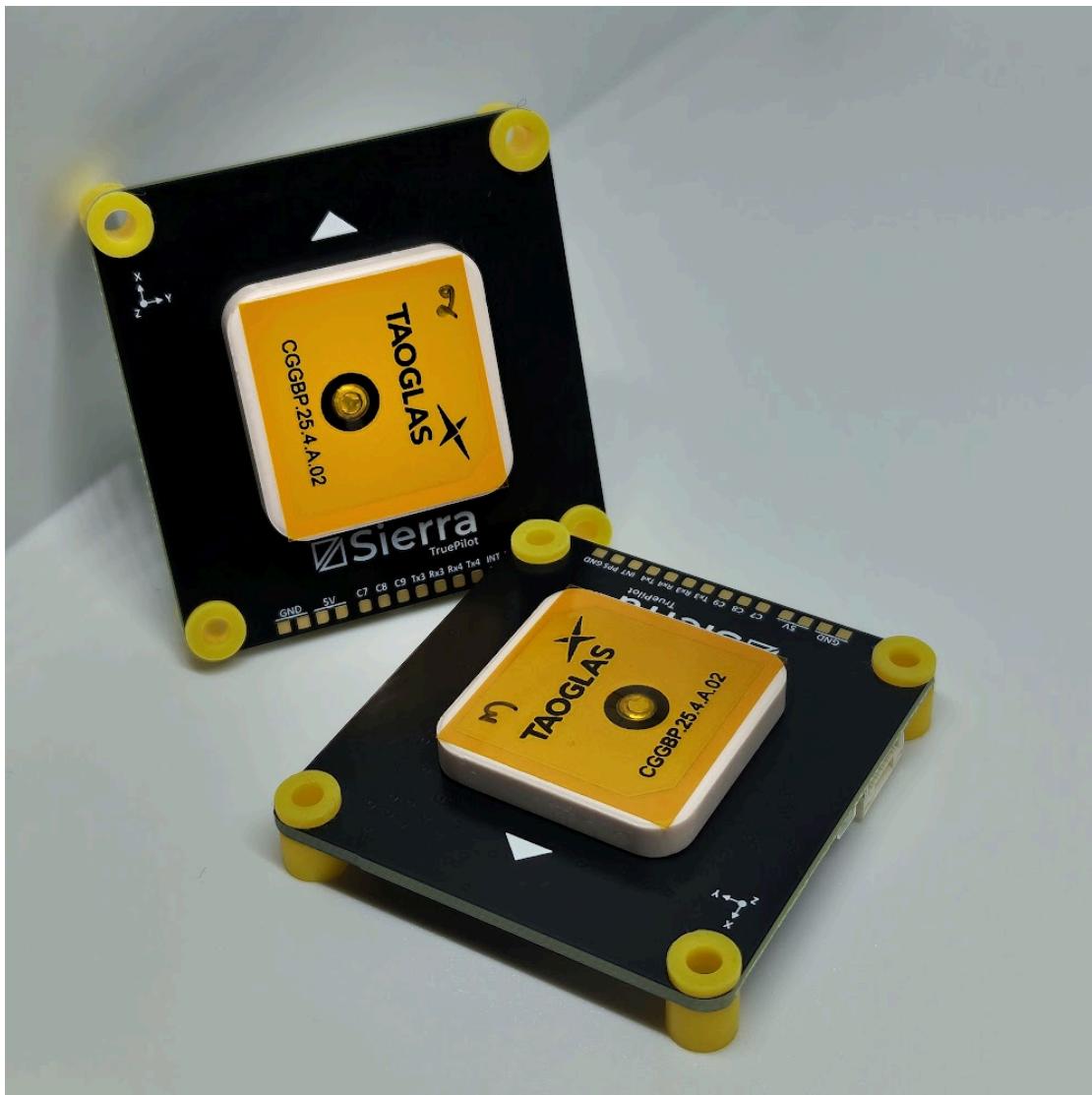




Sierra TruePilot



- STM32H7 with Cortex® -M7 core, floating point unit with double-precision data-processing
- 280 MHz CPU, 2MB of Flash memory, 1.6MB RAM
- 3x TDK ICM42688-P with heater
- Barometer: 2xDPS368
- IST8310 magnetometer
- Built-in GNSS options: M9N/F10N/F9P
- 1xCAN-FD driver
- 4x UARTs
- 9x PWM channels with DSHOT capability
- I2C for digital power module input
- External USB-C
- Built-in Neopixel notification LEDs
- Ultra Low noise LDOs
- GPIO based CAN termination switch
- Weight: 21g for L1 or 27g for L1+L5 with RTK, Dimension: 45x47mm
- Supports Ardupilot

1. CAN ports: CAN2

Note: Follows exact pinouts as Pixhawk Cube/ Pixhawk standards

Pin	Signal	Volt
1 (red)	VCC	+5V
2 (blk)	CAN_H	CAN high
3 (blk)	CAN_L	CAN low
4 (blk)	GND	GND

2. PWR: Digital voltage and current sensing

Pin	Signal	Volt
1 (red)	VCC	+5.3V
2 (blk)	VCC	+5.3V
3 (blk)	I2C_SCL	+3.3V
4 (blk)	I2C_SDA	+3.3V
5 (blk)	GND	GND
6 (blk)	GND	GND

3. URT1,2: Serial1 with DMA(best for high baud rates), Serial2 (RCIN)

PIN	SIGNAL	VOLTAGE
1	5V	5.3V
2	Serial1_Tx	3.3V
3	Serial1_Rx	3.3V
4	Serial3_Tx	3.3V
5	Serial3_Rx	3.3V
6	GND	GND

4. Serial3 is internal GPS

5. Serial 4 and Serial 5 as test pad on front side: TX3, RX3, TX4. RX4

6. USB

PIN	SIGNAL	VOLTAGE
1	VBUS	5V
2	USB+	3.3V
3	USB-	3.3V
4	GND	GND
5	GND	GND

7. PWM1-6: More PWMs on test pads C7, C8, C9

Pin	Signal	Volt
1 (blk)	PWM1	+3.3
2 (blk)	PWM2	+3.3
3 (blk)	PWM3	+3.3
4 (blk)	PWM4	+3.3
5 (blk)	PWM5	+3.3
6 (blk)	PWM6	+3.3
7 (blk)	GND	GND