

The FRC Control System - A Primer

Laying out and explaining the Integral control system hardware that is needed to make an FRC Robot run.

Please consult the Regular FRC Control System Diagrams for a more complete implementation of the system.

Robot Signal Light
An industrial-grade light that allows a robot to visually communicate its status either to your drive team, or field staff.

RSL Wiring
Minimum 22 AWG
"La" and "Lb" terminals connected to each other.

CAN wires should be a twisted pair with a twist per 1 inch or denser.

Ethernet Cable
Must be connected to the radio using the port labeled "RIO".
It is Recommended that you use a new ethernet cable to ensure reliability of the connection.

Radio Power
Minimum 22 AWG

Radio

Enables wireless communication from your robot to the field, and to your team's Driver's Station.

Robot Communication

Main Power and Distribution

High Current Channels

Up to 40A continuous load for these.
Used for motors, pneumatics controllers, and everything else

Low Current Channels

Up to 15A continuous, 20A peak load for these.
Used for the RoboRIO, Radio and other low current devices.

12V40A

12V20A

12V30A

12V10A

ATO Breakers

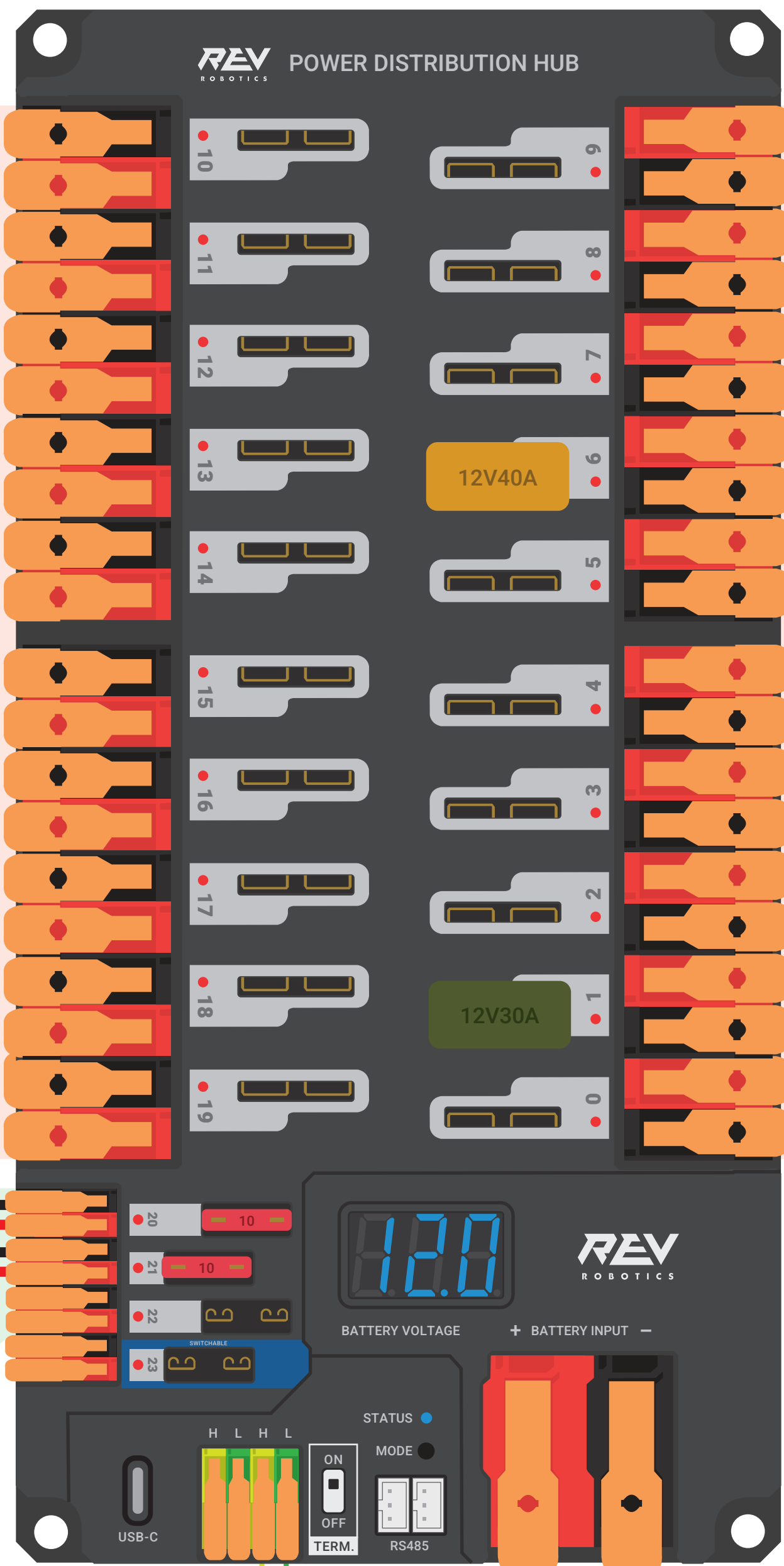
ATM Fuses

Circuit Breakers / Fuses

Comes in ATO (High Current) or ATM (Low Current) form factors. These slot in to allow supplying power but also to give current protection to the channel its connected to.

Power Distribution Hub

Distributes battery power, and provides fused low and high current channels towards various components in the robot.



The Battery

A Sealed SLA-type battery, it stores and provides the power needed for a robot to run for a Full Match (2:30 Minutes). **Replaced with a recharged one every match.**

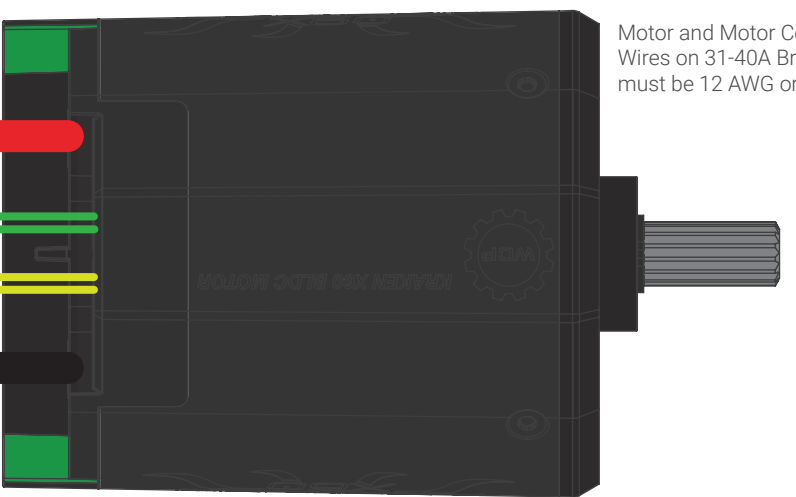
Motor Controllers

Controls the motors that your robot has.
Only 1 motor is allowed per controller in most cases.
Motor Controllers come in different types.

Integrated Controllers

Example Shown is a Kraken X60 Motor + Talon FX

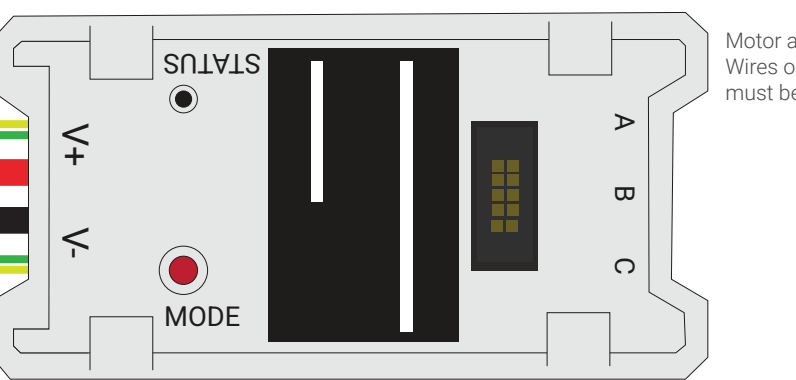
These controllers are integrated into their motor, making it either inseparable, or separable as an installable module
These controllers can either be controlled through CAN or PWM.



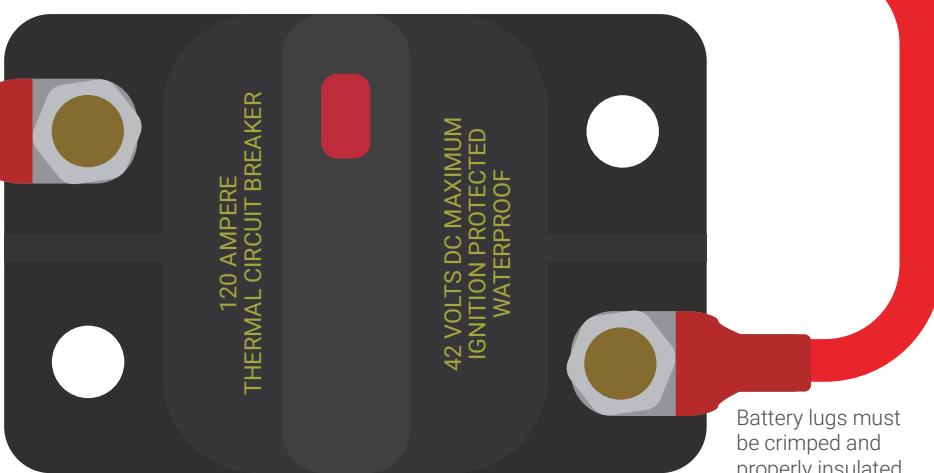
Discrete Controllers

Example Shown is a Spark MAX motor controller

These controllers are separate from their motors, meaning you can pair any of these with any compatible motor.
These controllers can either be controlled through CAN or PWM.



Motor Control



120A Main Breaker

Protects the robot from drawing too much current at the battery level.
Also acts as the robot's power switch.

Making your robot aware

Sensors detect movements or certain changes in your robot or its surroundings, so that you can utilize them for your robot's functionality.

Read more on the different types of sensors and how you could utilize them at:
<https://docs.wpilib.org>

Limit Switch Example

Analog Encoder Example

USB Camera Example

Sensors

BASIC FRC CONTROL SYSTEM

V.3.10.PR

TEAM 3161



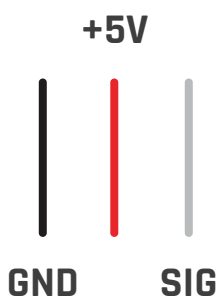
Power

12V DC Main



PWM

26 AWG Minimum



CAN

28 AWG Minimum



Wires

American Wire Gauge (AWG)

Minimum Gauge per connection type shown.



Always practice proper safety precautions and practices when working with electrical systems.

More Information about the FRC Control System can be found at
<https://docs.wpilib.org>

KEEP IN MIND