

A

A

B

B

C

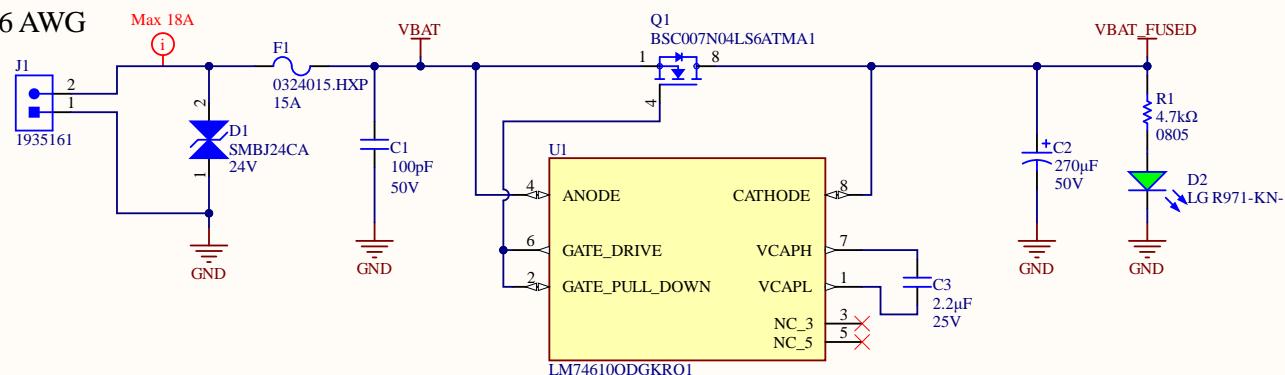
C

D

D

Battery Input (6s1p)

12-26 AWG



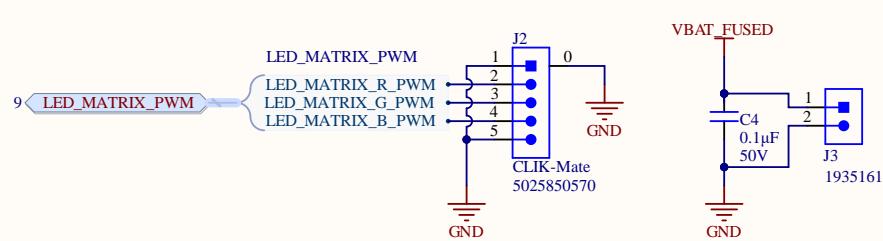
Ideal Diode Controller

LED forward drop = 2.0V
Max VBAT = 24V
Min VBAT = 18V

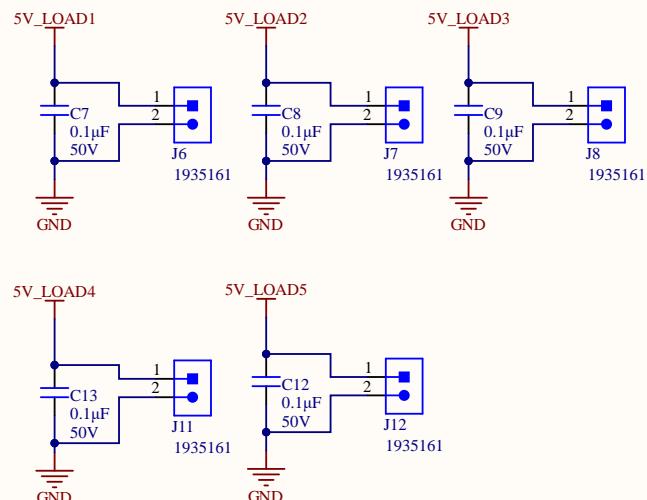
Max LED current = $(24-2)/4700 = 4.7\text{mA}$
Min LED current = $(18-2)/4700 = 3.4\text{mA}$

Title	Power Distribution Board Rev2 - Power	UW Robotics
Size:	Letter	Waterloo Ontario Canada N2L 3G6
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File:	C:\UWRT\MarsRover2021-hardware\Projects\Power	Distribution Board\Rev2\SH1 - POWER.SchDoc

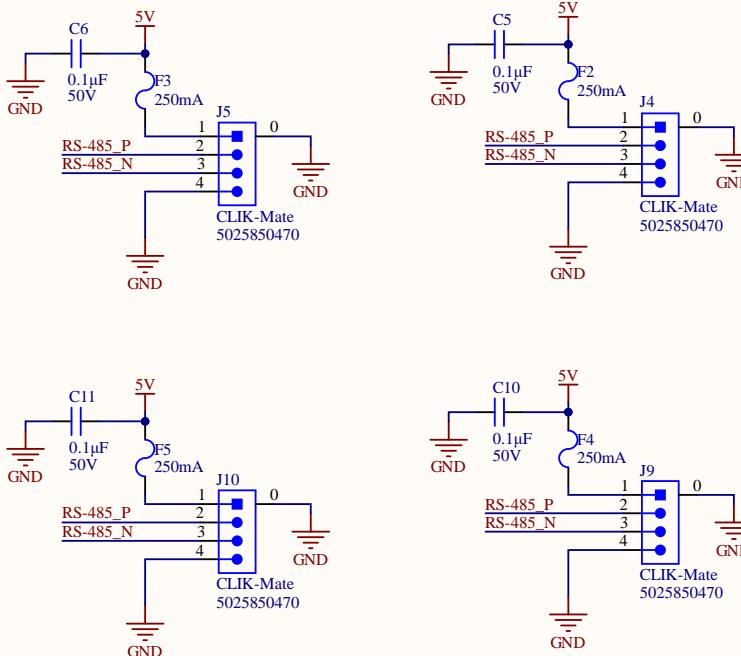
LED Matrix



5V Output



URM04 Ultrasonic Sensors



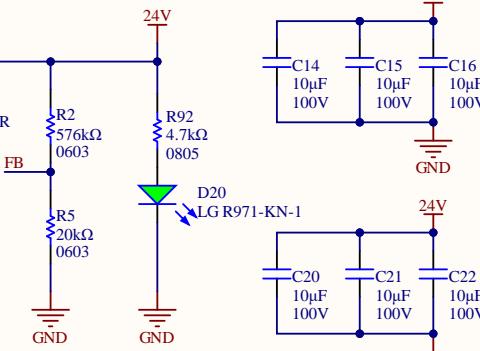
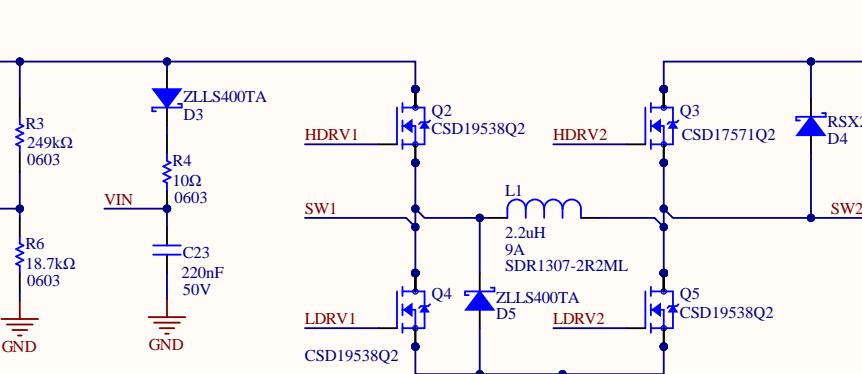
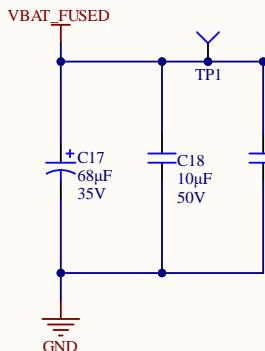
RS-485
12 RS-485 → RS-485_P
RS-485_N ← RS-485_N

Input voltage range: 18-25.8V

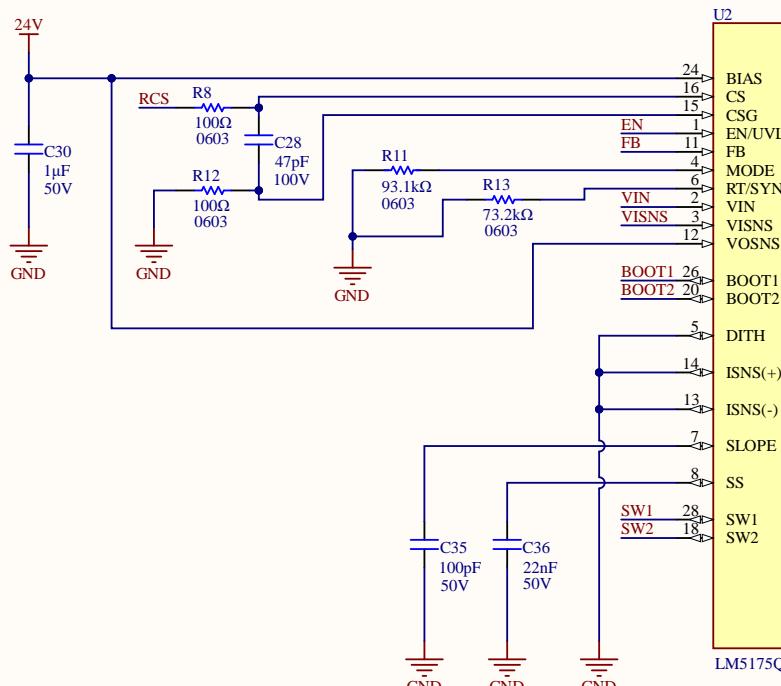
24V Buck-Boost Converter @ 3A Max

LED forward drop = 2.0V

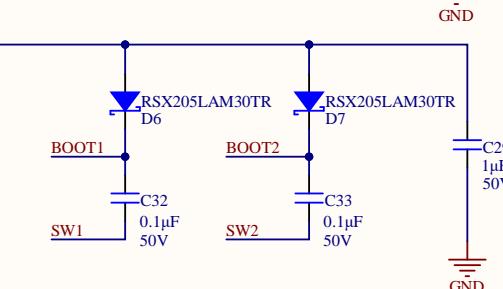
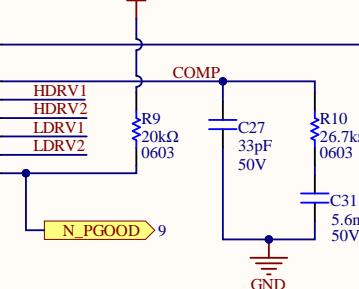
LED current = $(24-2)/4700 = 4.7mA$



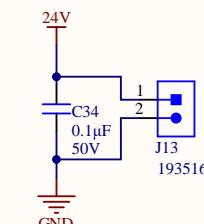
Inductor: SDR1307-2R2ML
20%, 6mΩ DCR
9A (rms), 18A (sat), 7mm tall

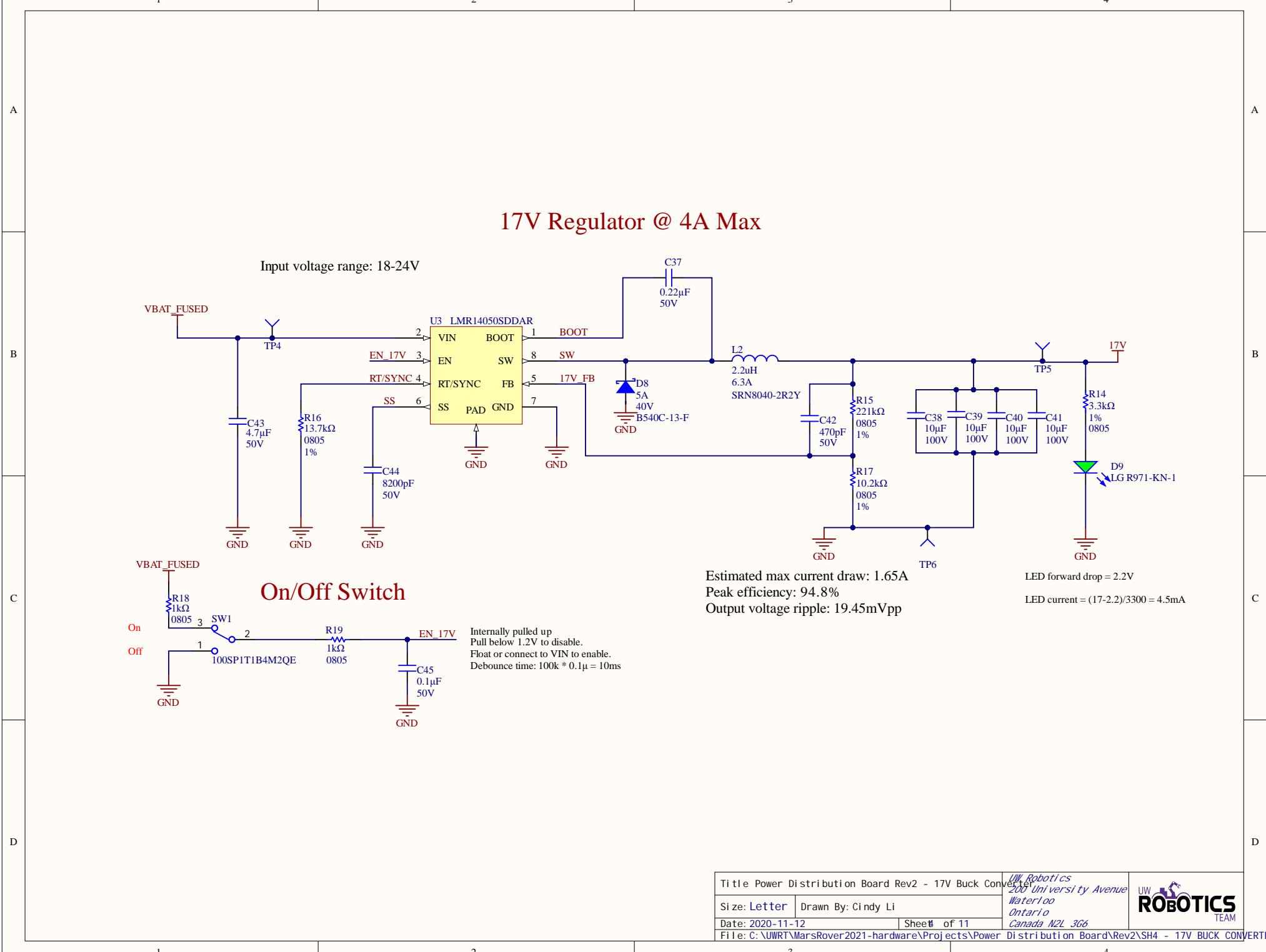


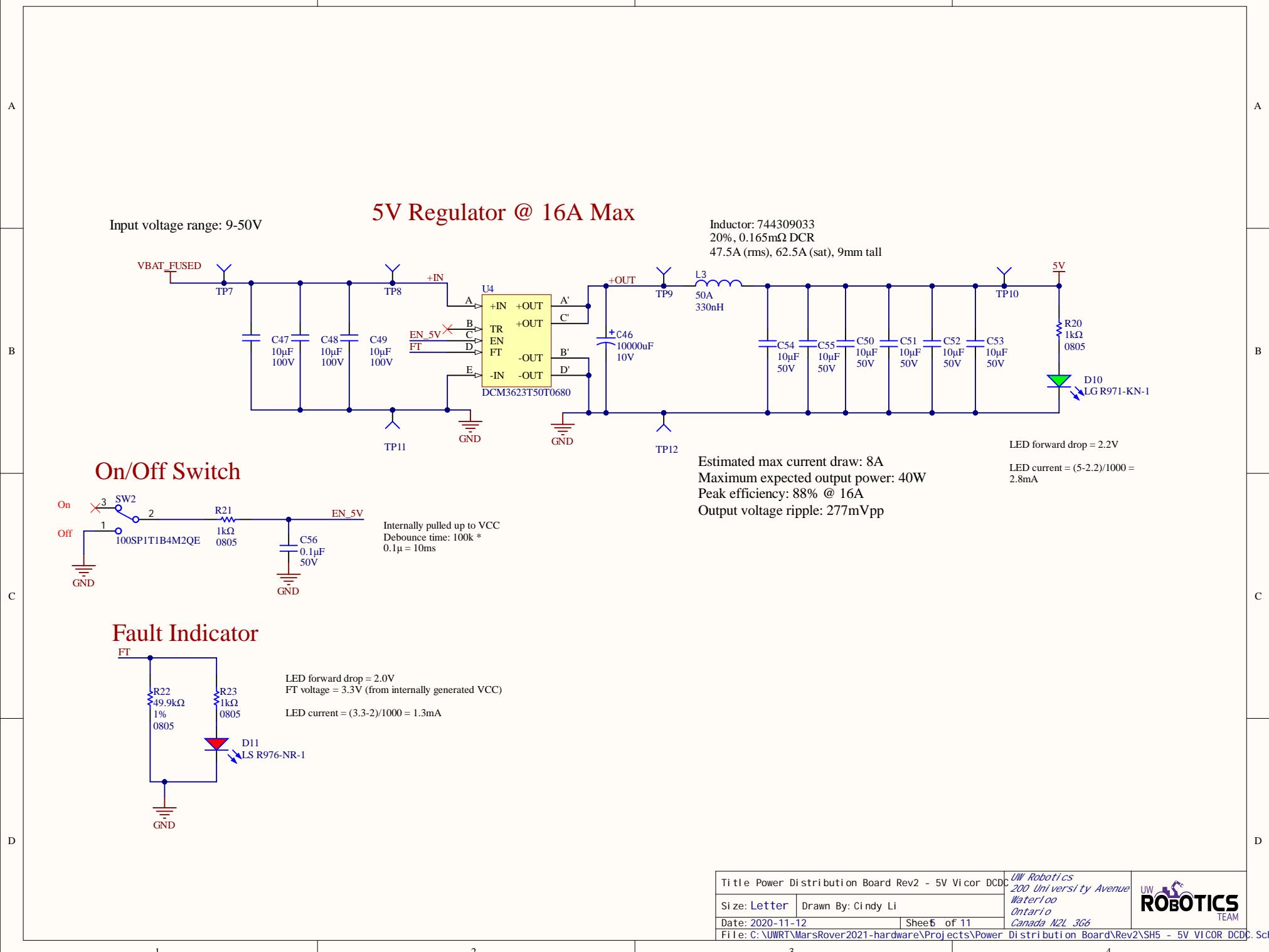
U2
LM5175QPWPRQ1
Title PDB Rev2 - 24V Buck-Boost Converter
Size: Letter Drawn By: Cindy Li
Date: 2020-11-12 Sheet 8 of 11
File: C:\UWRT\MarsRover2021-hardware\Projects\Power Distribution Board\Rev2\SH3 - 24V BUCK-BOOST CONVERTER.SchD



24V Output







A

A

B

B

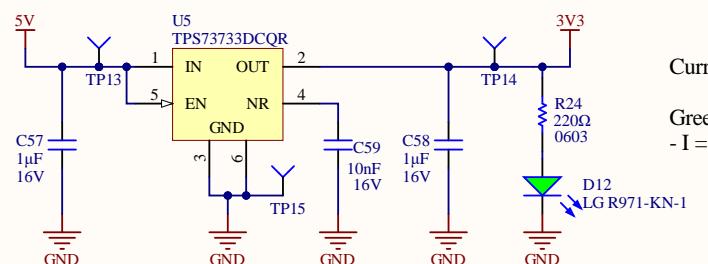
C

C

D

D

5V to 3.3V LDO (Max 1A)



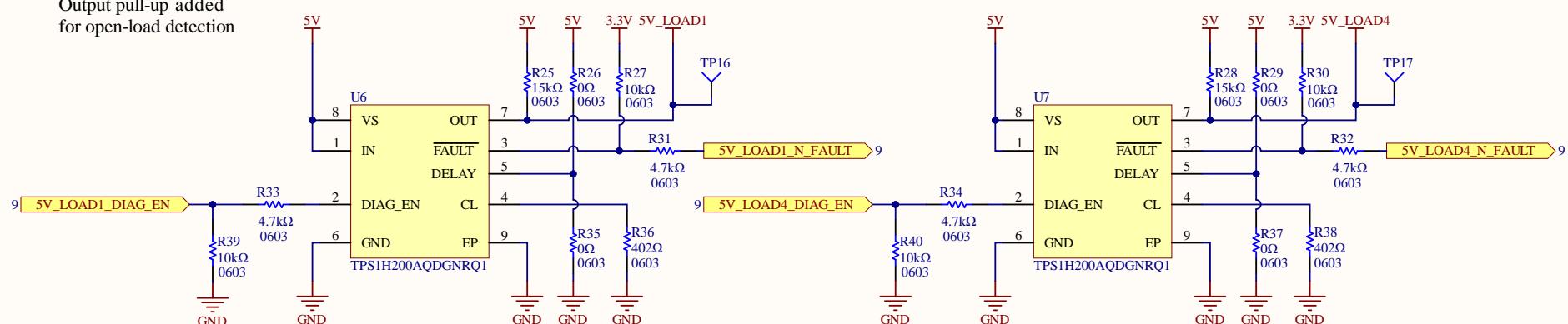
Current Calculations

Green LED voltage drop: 2.2V
 $- I = (3.3 - 2.2V) / 220 = 5mA$

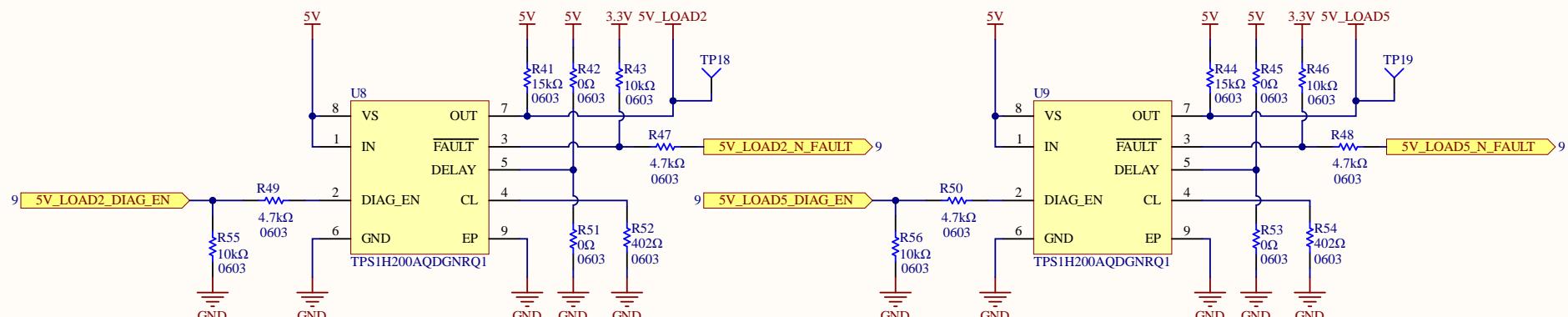
Title Power Distribution Board Rev2 - 3.3V Linear		<i>UW Robotics</i> 200 University Avenue Waterloo Ontario Canada N2L 3G6
Size: Letter	Drawn By: Cindy Li	
Date: 2020-11-12	Sheet 6 of 11	
File: C:\UWRT\MarsRover2021-hardware\Projects\Power Distribution Board\Rev2\SH6 - 3.3V LINEAR REGULATOR.SchDoc		UW ROBOTICS TEAM

5V Loads Smart Switches

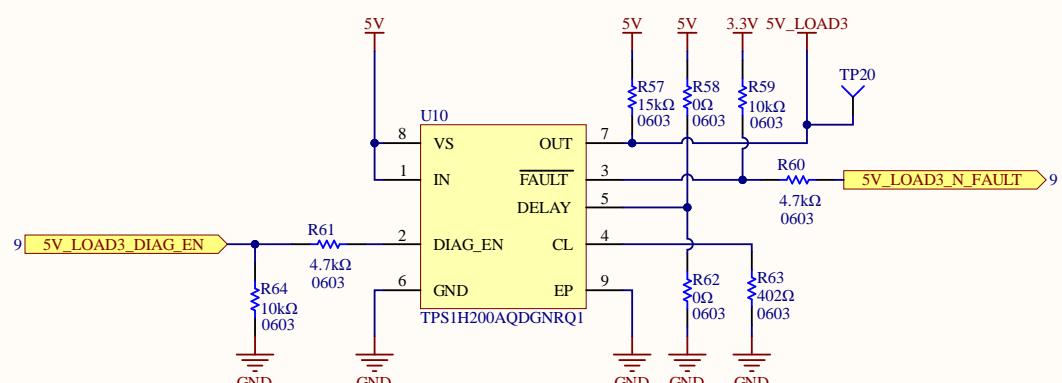
A
Output pull-up added for open-load detection



B



C



Smart Switch Current Limited to 5A

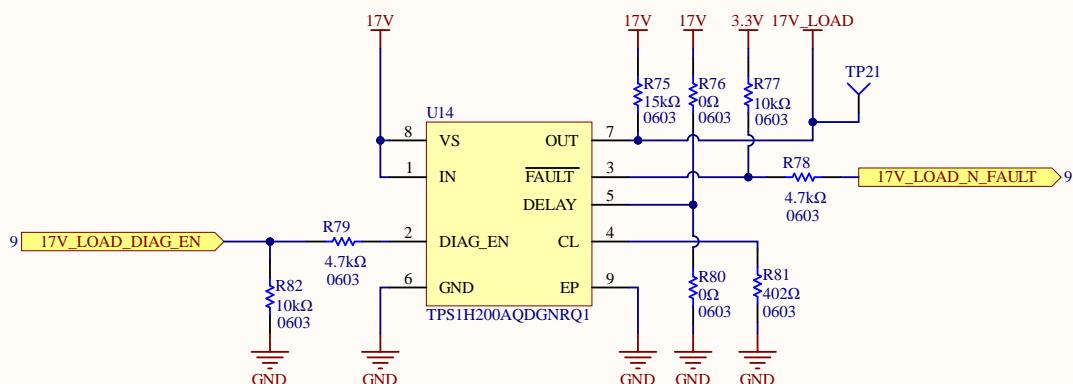
- $I_{out} = 5A$, $V_{CL(th)} = 0.8V$, $K_{CL} = 2500$ (values from datasheet)
- $R_{CL} = V_{CL(th)} * K_{CL} / I_{out} = 0.8 * 2500 / 5 = 400\Omega \rightarrow$ use $R_{CL} = 402\Omega$

Current Limit Configurations - Refer to DELAY Pin

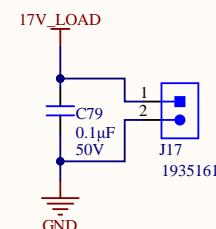
- Holding mode: depopulate pull-up and populate pull-down with a 0Ω resistor
- Latch-off mode: depopulate pull-up and populate pull-down with a capacitor or (calculated based on required delay time)
- Auto-retry mode: populate pull-up with a pull-up resistor and depopulate pull-down

A

17V Load Smart Switch

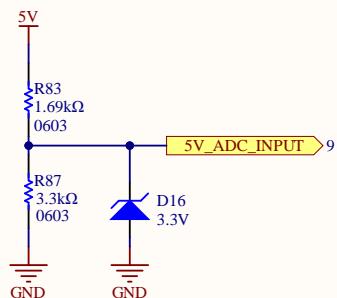


17V Output

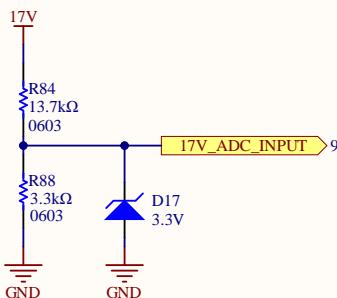


B

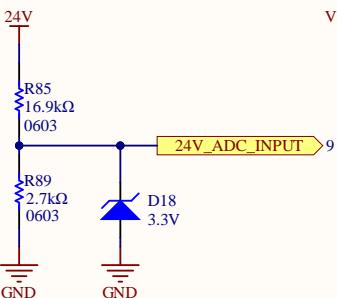
Power Rail Voltage Monitoring



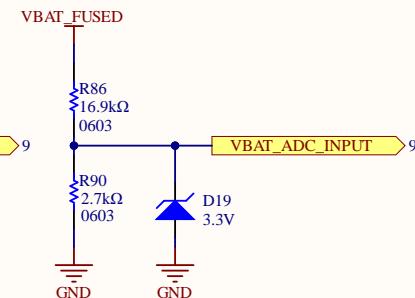
Divides 5V to 3.3V



Divides 17V to 3.3V



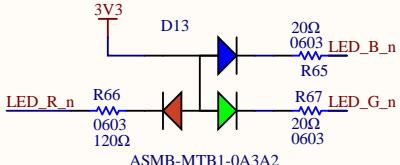
Divides 24V to 3.3V



Divides 24V to 3.3V

D

Status LED

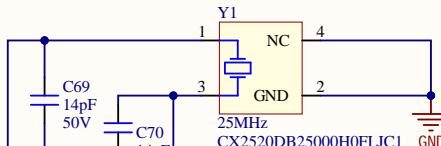


Current Calculations

RGB LED voltage drops:

- Red: 2.1V: $I = (3.3 - 2.1V)/120 = 10mA$
- Blue: 3.1V: $I = (3.3 - 3.1V)/20 = 10mA$
- Green: 3.1V: $I = (3.3 - 3.1V)/20 = 10mA$

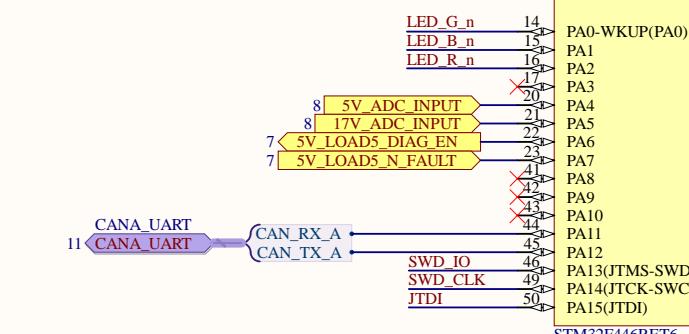
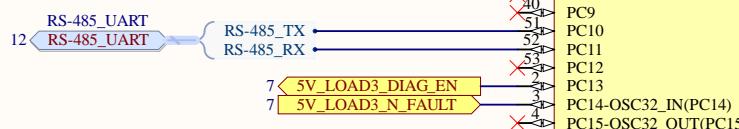
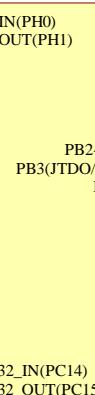
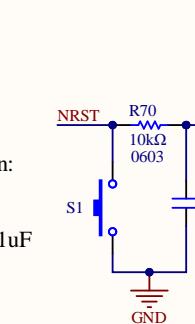
STM32F446RET6



Debounce Calculation:

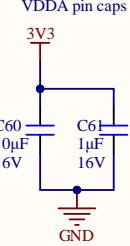
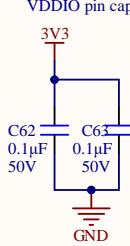
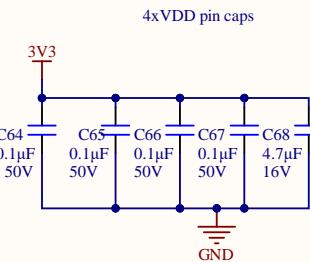
$$T = RC \rightarrow C = T/R$$

$$C = 10ms / 10k\Omega = 1\mu F$$

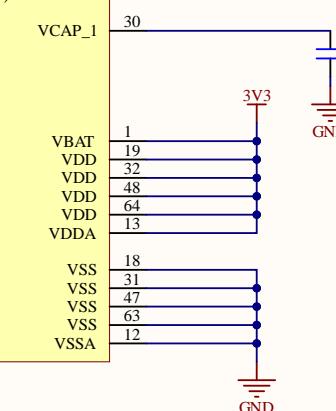
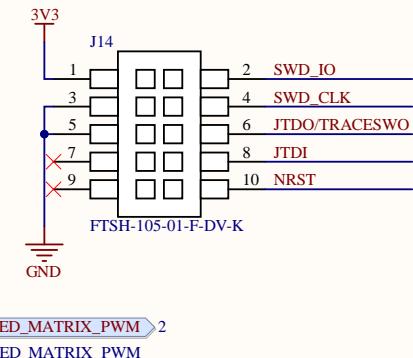


STM32F446RET6

Decoupling Caps



Debug/Programming

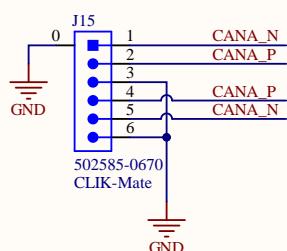


MH1
○ MOUNTING_HOLE_6CM
MH2
○ MOUNTING_HOLE_6CM
MH3
○ MOUNTING_HOLE_6CM
MH4
○ MOUNTING_HOLE_6CM

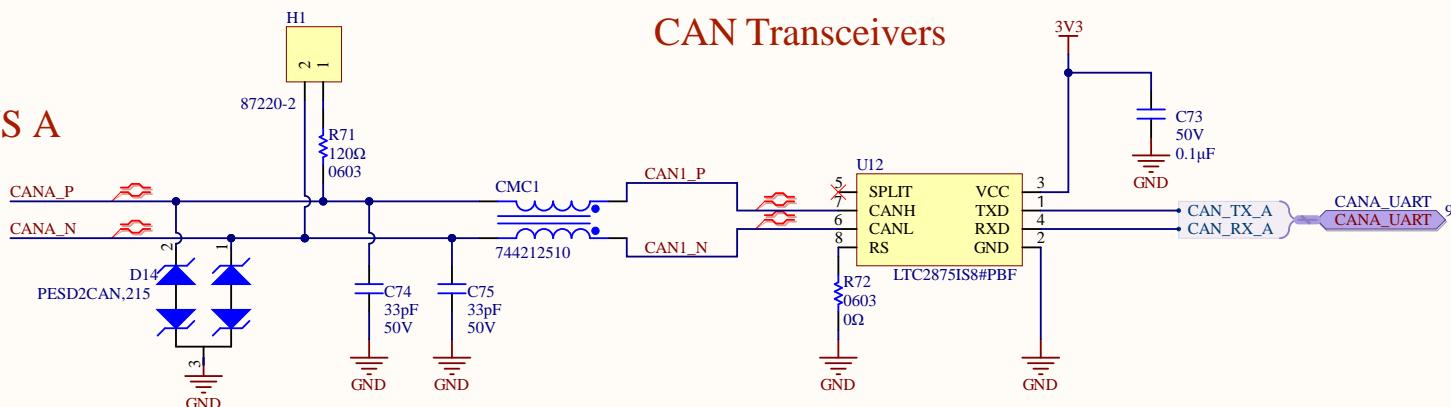
A

A

CAN BUS A



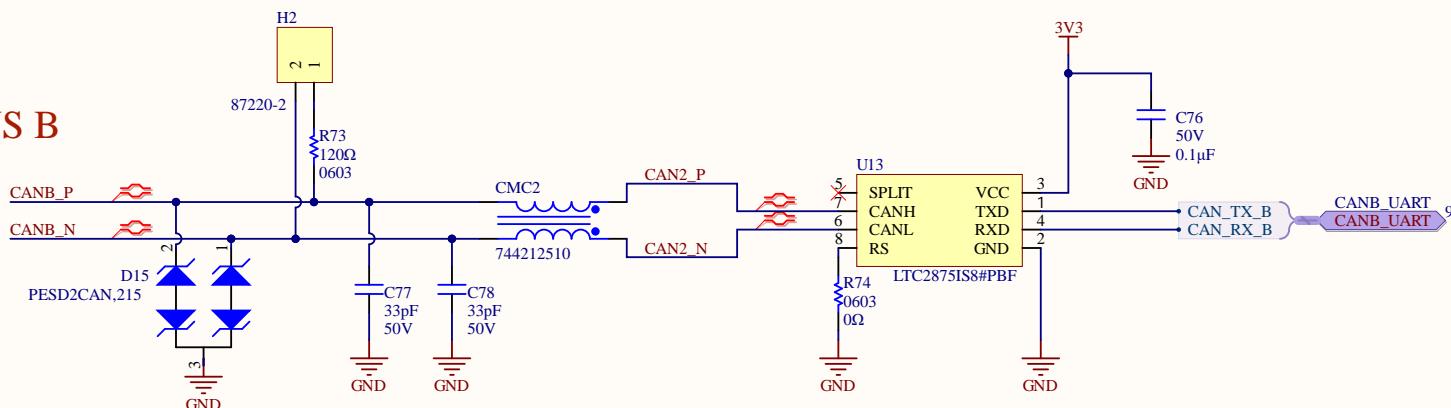
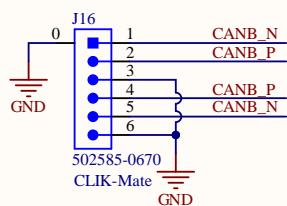
CAN Transceivers



B

1

CAN BUS B



1

1

D

1

Title	Power Distribution Board Rev2 - CAN		<i>UW Robotics 200 University Avenue Waterloo Ontario Canada N2L 3G6</i>	
Size:	Letter	Drawn By: Cindy Li		
Date:	2020-11-12	Sheet 0 of 11		
File:	C:\UWRT\MarsRover2021-hardware\Projects\Power		Distribution Board\Rev2\SH10 - CAN.SchDoc	

A

A

B

B

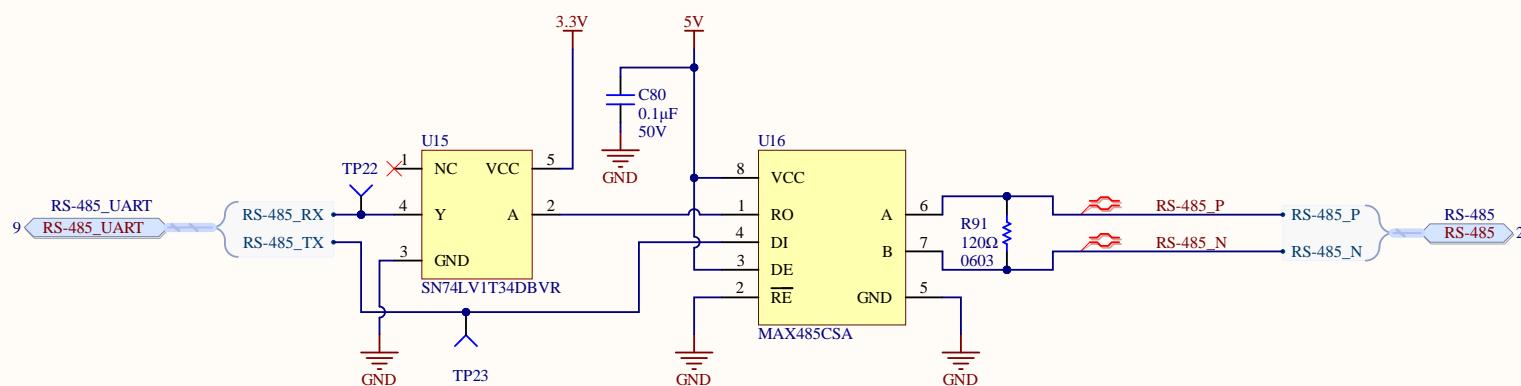
C

C

D

D

RS-485 Transceiver



Title Power Distribution Board Rev2 - RS-485		UW Robotics 200 University Avenue Waterloo Ontario Canada N2L 3G6	UW ROBOTICS TEAM
Size: Letter	Drawn By: Cindy Li		
Date: 2020-11-12	Sheet 1 of 11		
File: C:\UWRT\MarsRover2021-hardware\Projects\Power Distribution Board\Rev2\SH11 - RS-485.SchDoc			

