

VULTURE_PMCB_V02

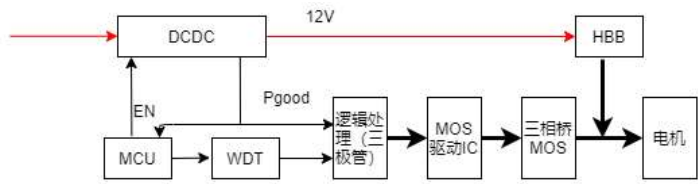
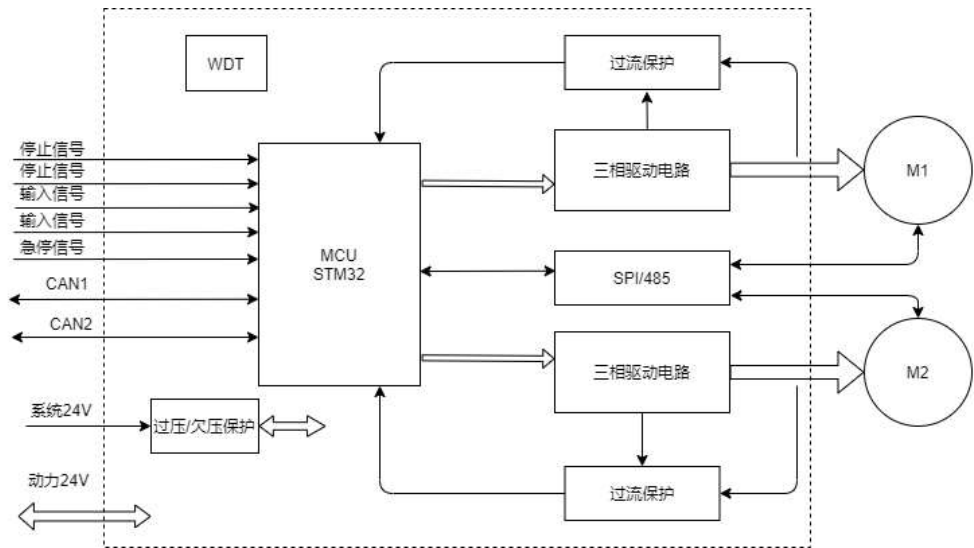
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Syrius 恒星		Syriusrobotics Technologies(ShenZhen)	
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Change List

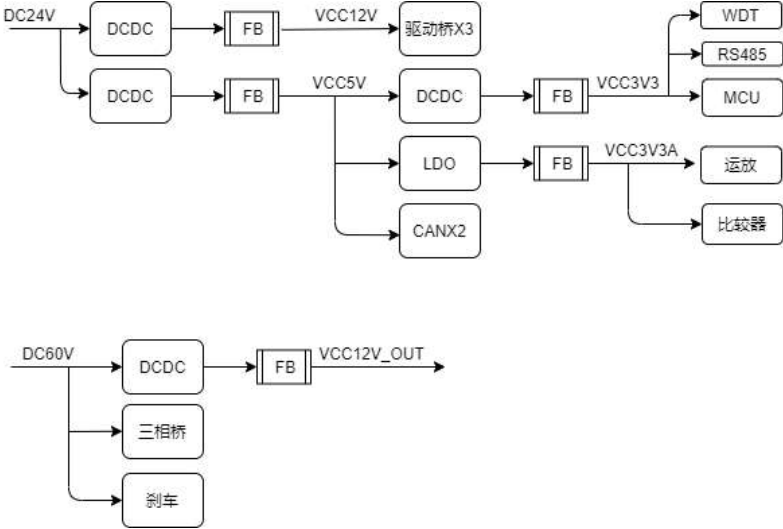
VER.	WHO	DATA	Description
PMCB_V01	liangkuai	2023.11.29	第一版设计 1，版本规划和修改ID0,ID1,ID2,ID3。 2，抱闸控制增加RC，可以控制调节电源电压。 3，三相hall信号采集使用不同的中断源。 4，增加限位开关的接入控制功能。
PMCB_V02	liangkuai	2024.02.28	

Block Diagram

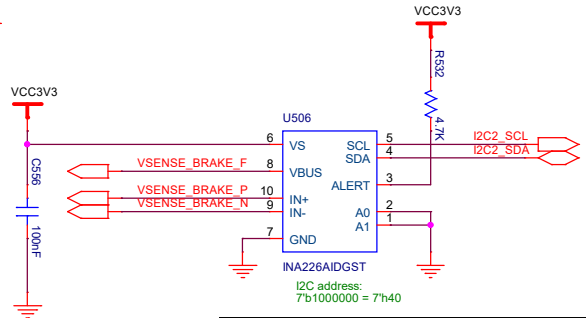
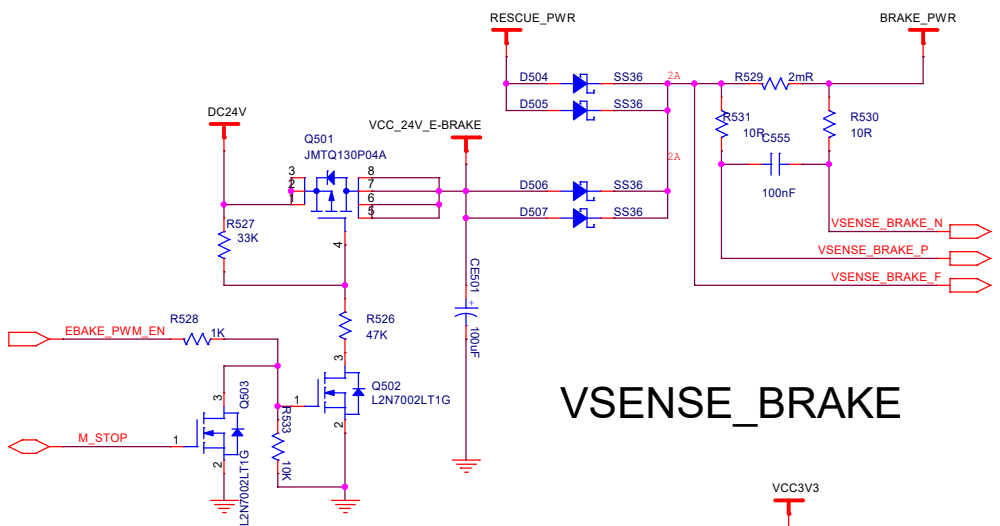
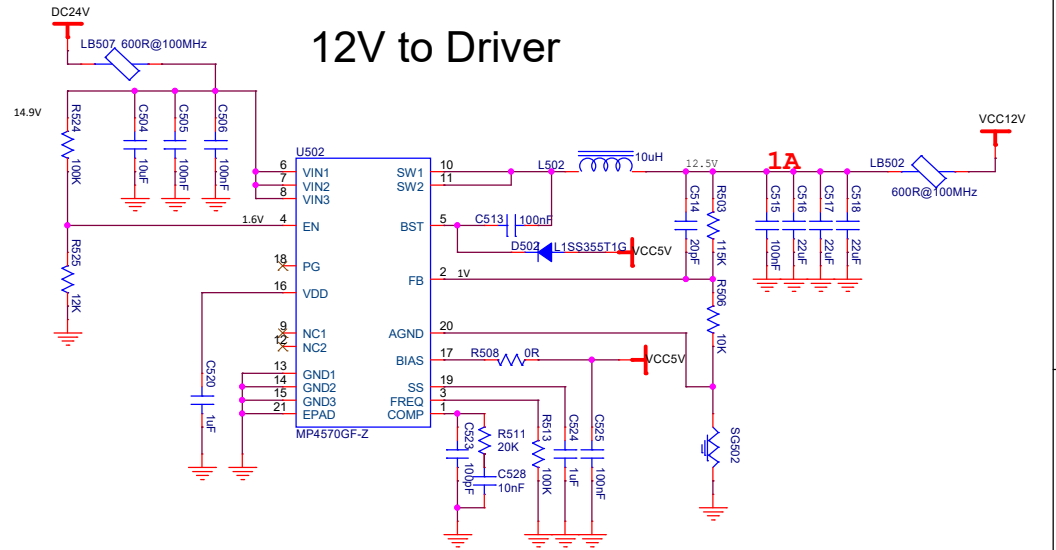
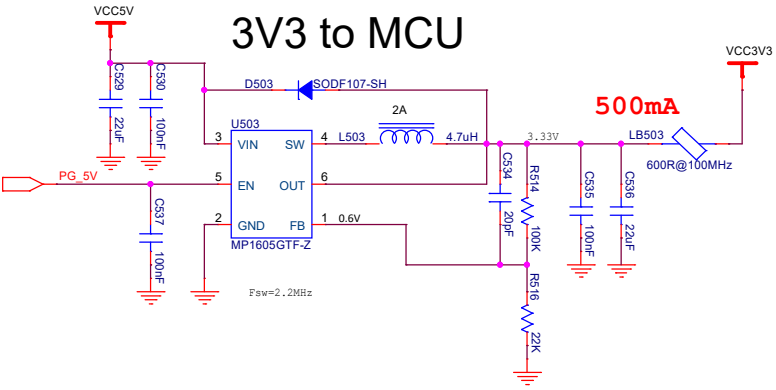
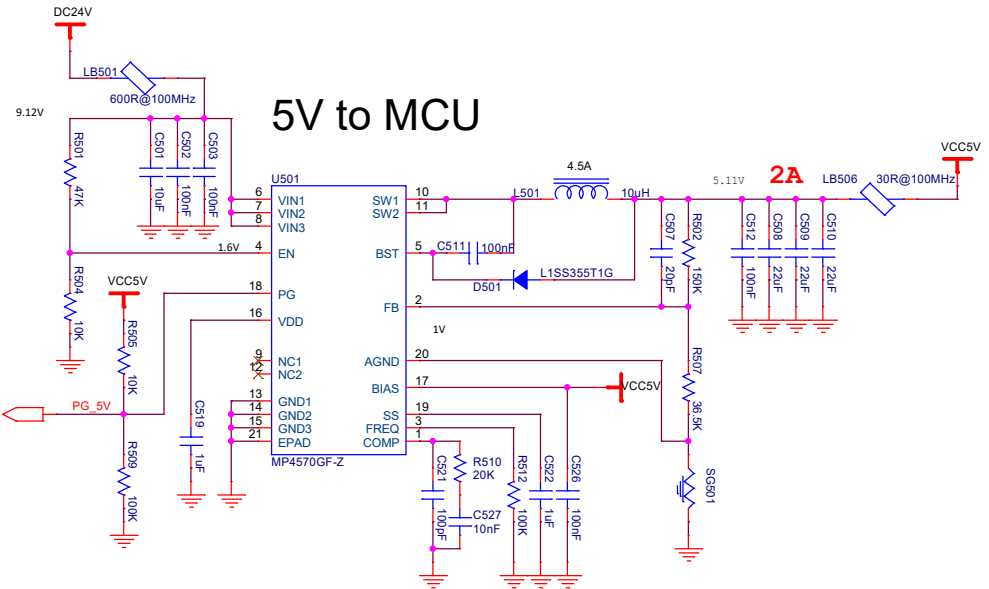


- 1.MCU 驱动电机前 (包括自检), 先打开对外12V电源 (高电平打开), 并检测12V是否正常, 对外12V正常后才能驱动mos
- 2.MCU检测到过流事件, 先让电机自由状态, 在关闭对外12V输出

Power Tree



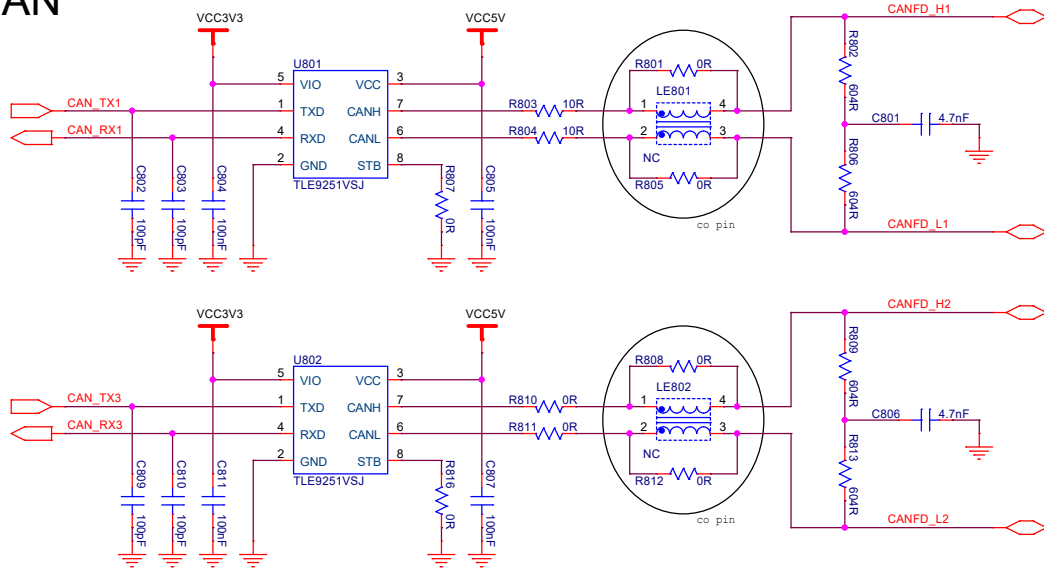
Power



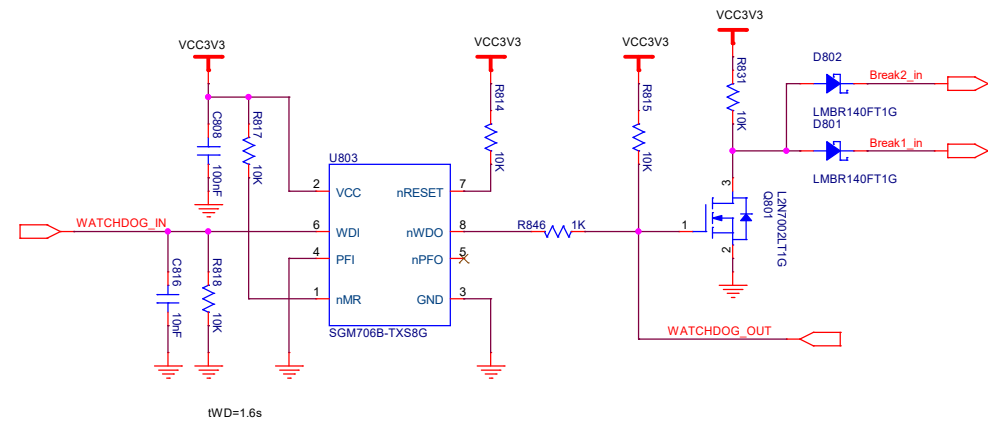
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CAN&WD&RS485

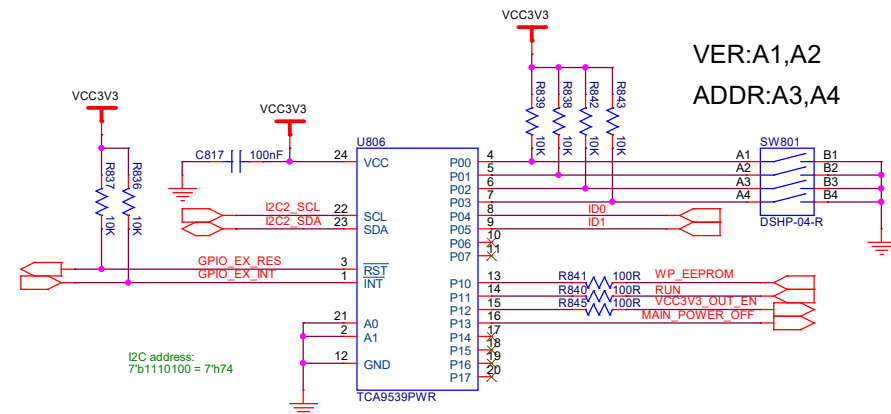
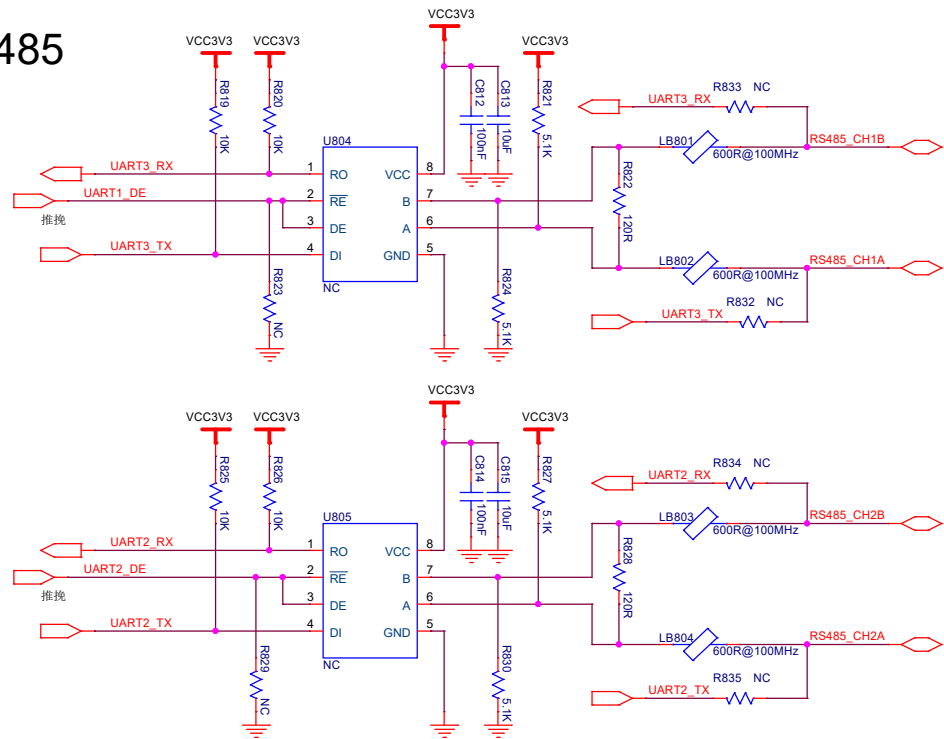
CAN



WATCH DOG



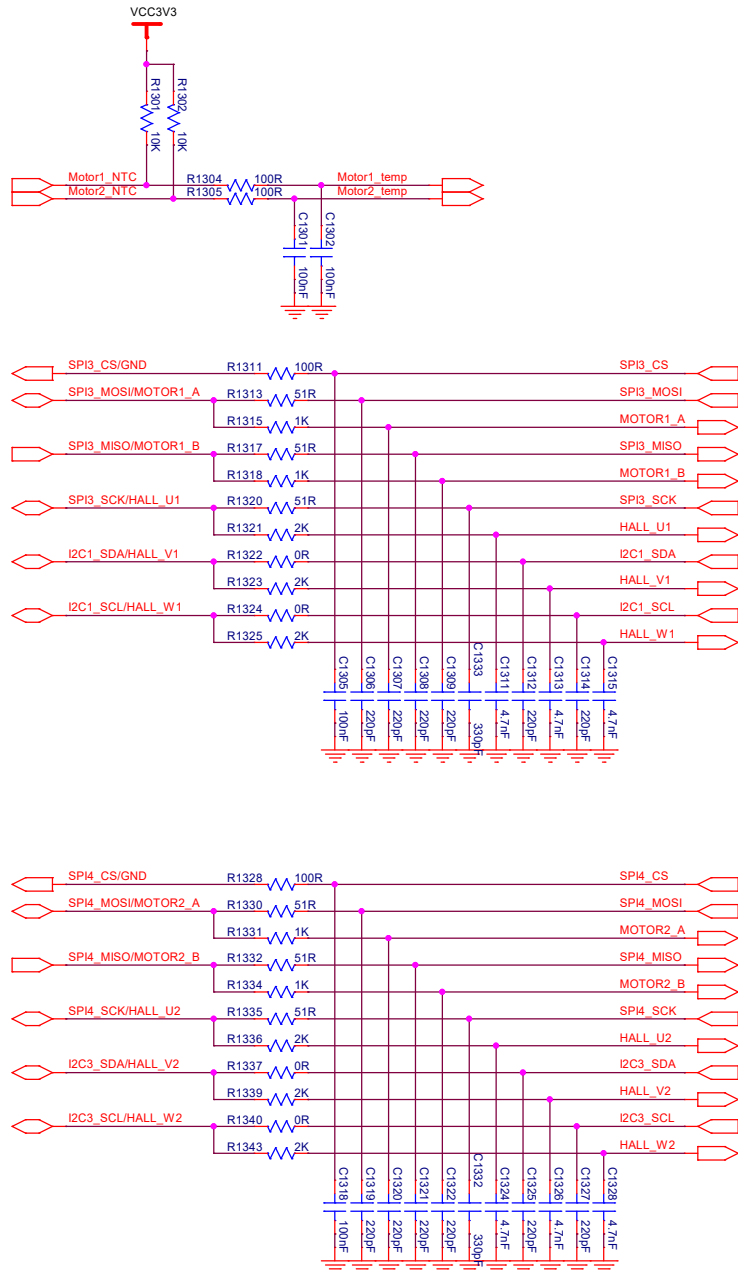
RS485



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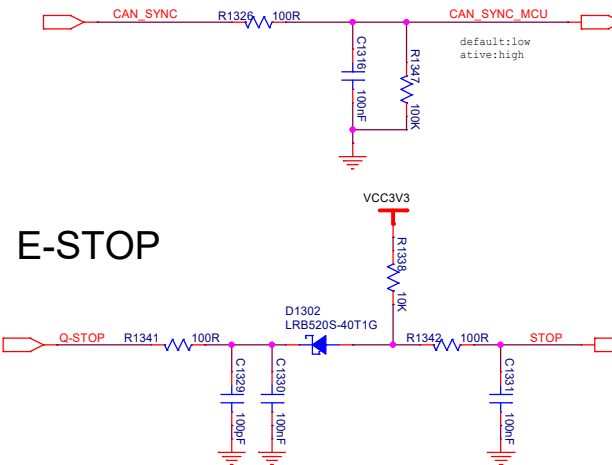
Peripheral

MOTOR OUT



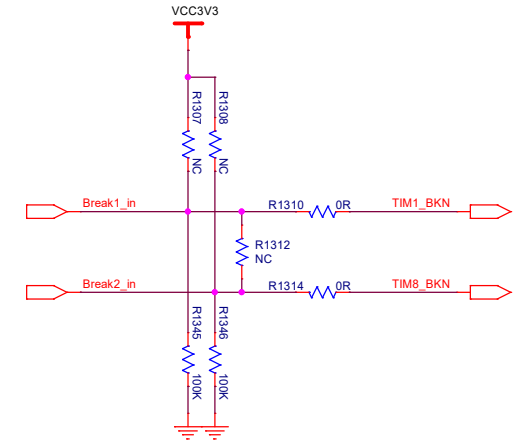
12V OUT DETECT

CAN SYNC



E-STOP

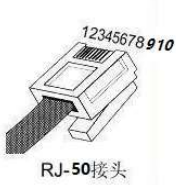
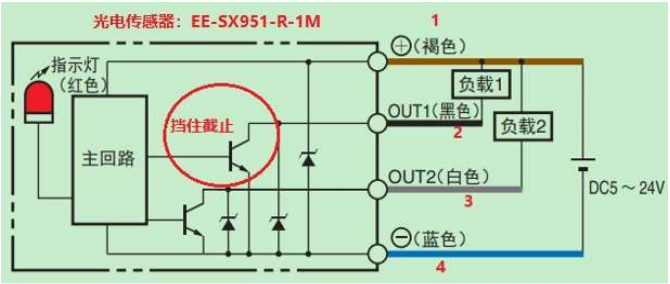
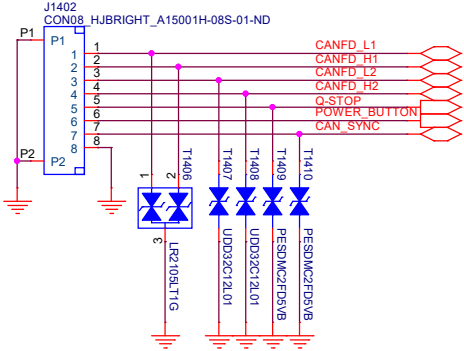
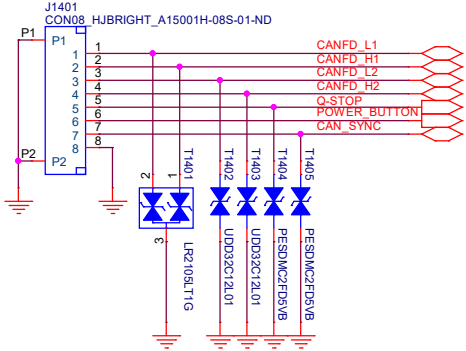
OCP BREAK



Sirius 炬星			
Siriusrobotics Technologies(ShenZhen)			
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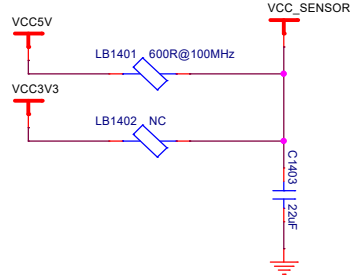
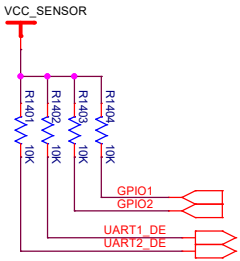
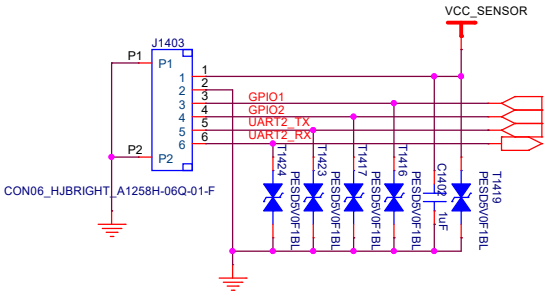
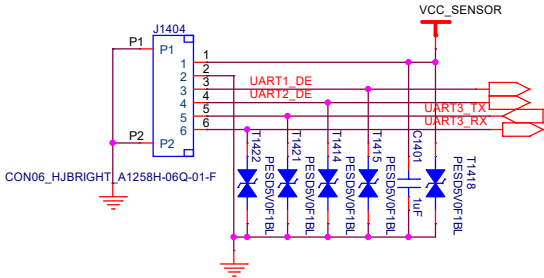
Connector to Board

SYSTEM



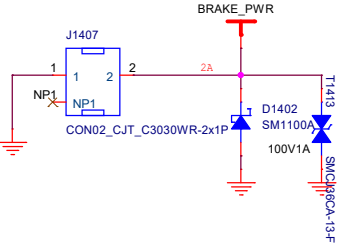
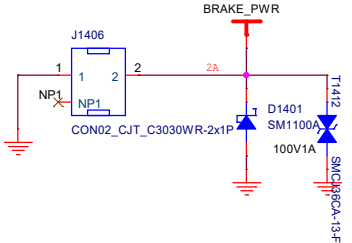
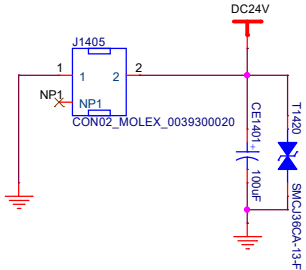
- 光电传感器 RJ-50水晶头 (10P)
- 1、褐色: 电源正极 ----- 第二脚
 - 2、黑色: 输出OUT1 ----- 第三脚
 - 3、白色: 输出OUT2 ----- 第四脚
 - 4、蓝色: 电源负极 ----- 第六脚

GPIO/UART

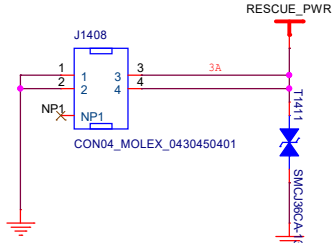


POWER IN

BAKE



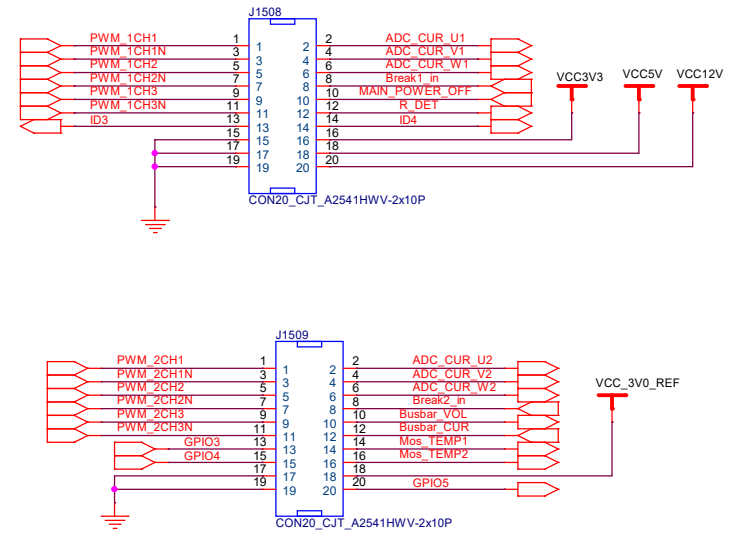
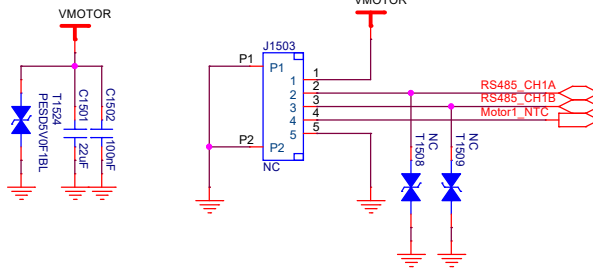
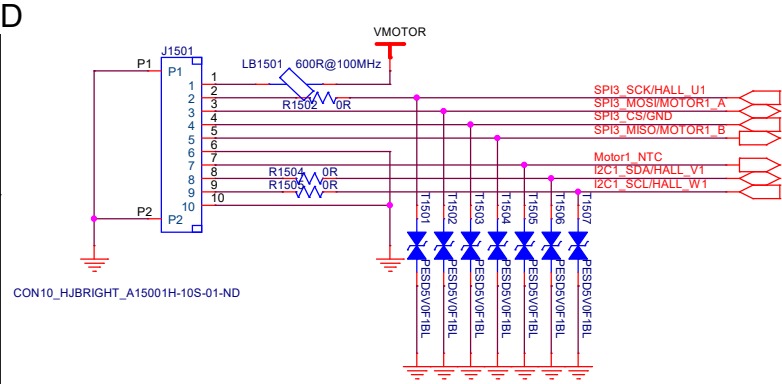
RESCUE



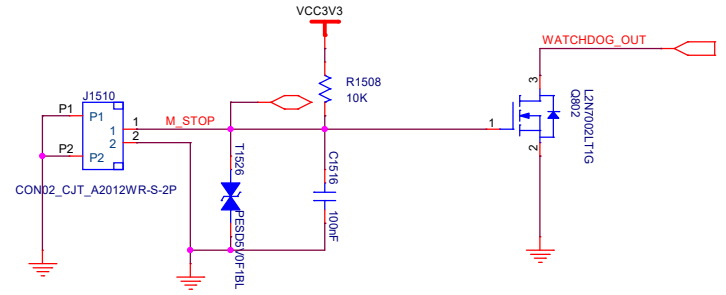
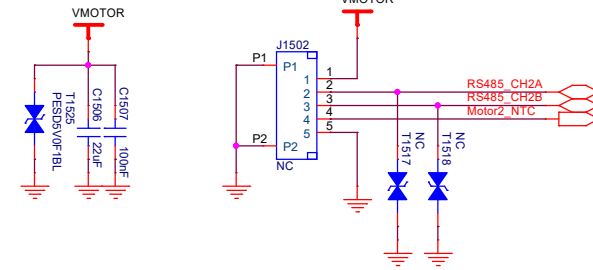
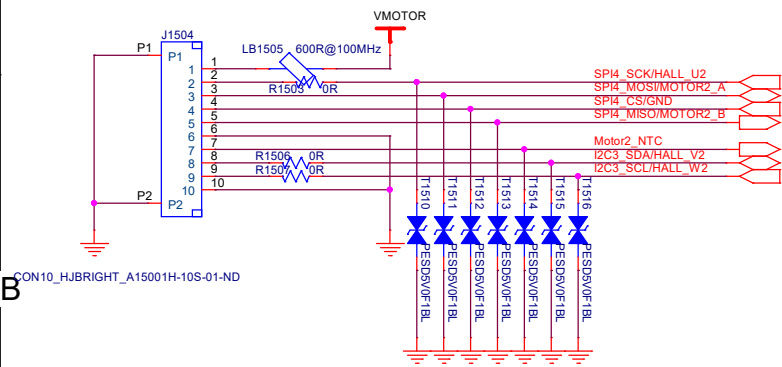
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Connector to Device

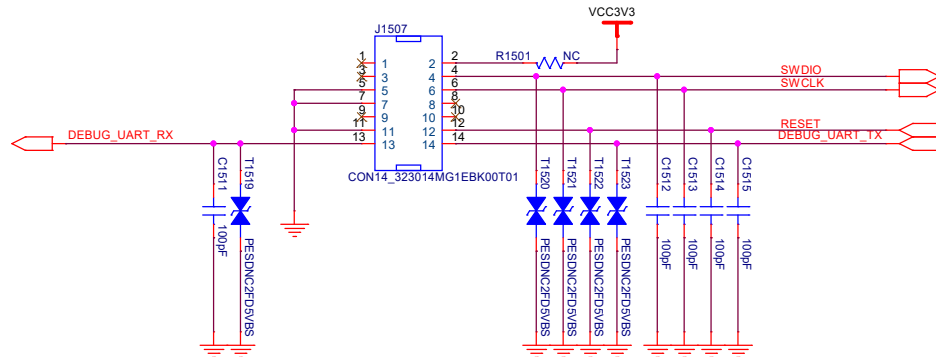
MOTOR1



MOTOR2



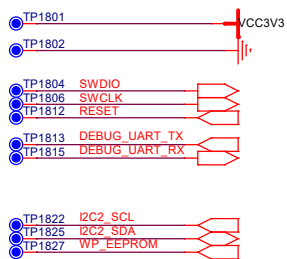
DEBUG



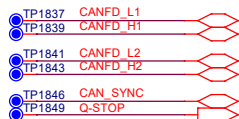
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Test Point

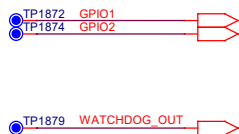
SYSTEM



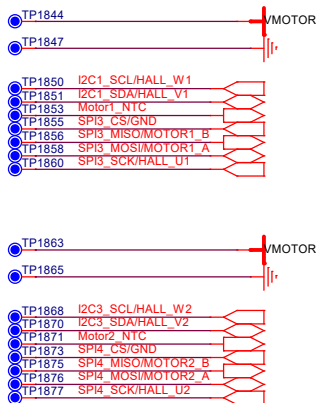
CAN



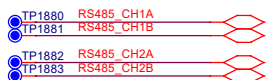
GPIO



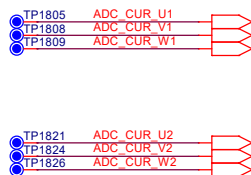
MOTOR



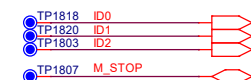
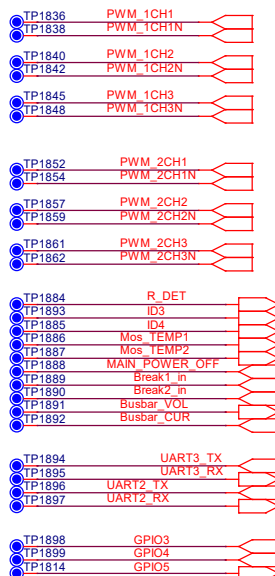
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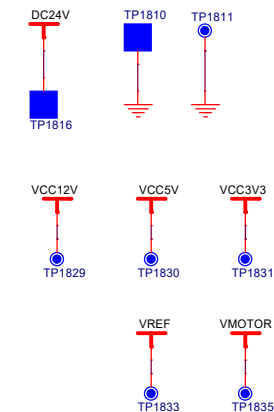
CURRENT SENSE



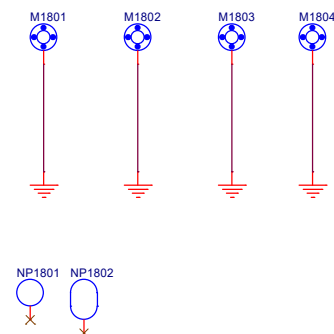
PWM



POWER



MACHINE



Syrius 巨星				Syriusrobotics Technologies(ShenZhen)	
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