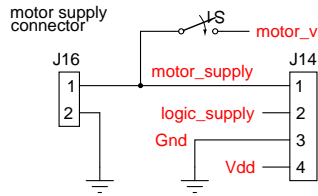
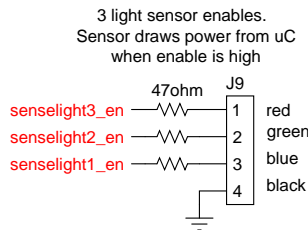
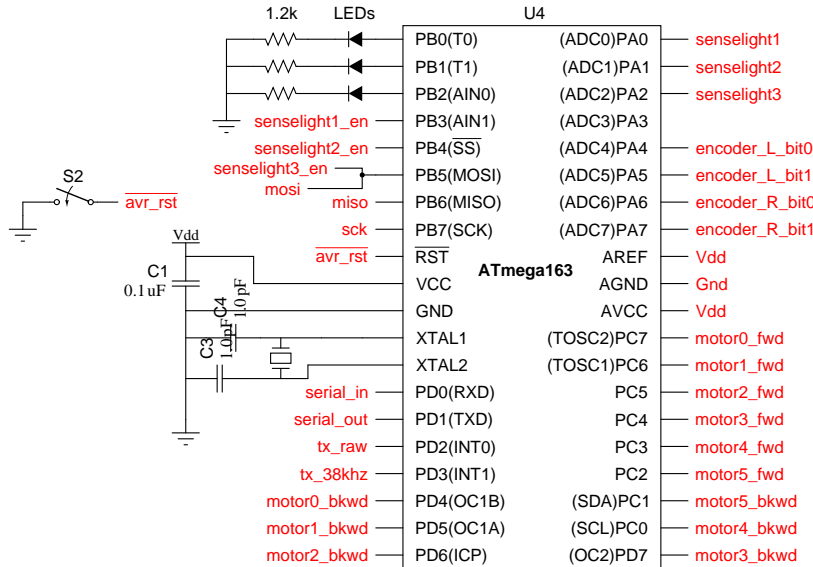
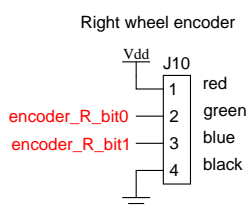
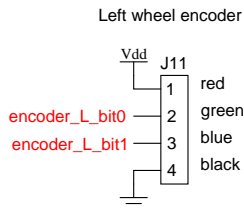
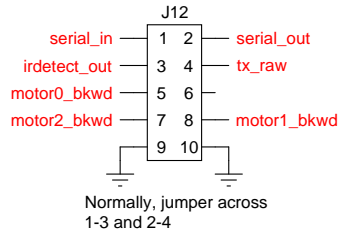
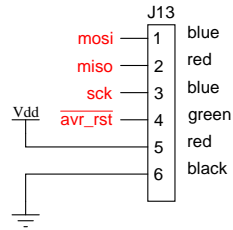
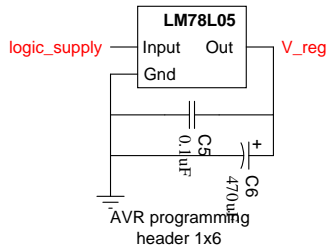
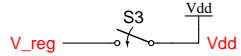


Mobile robot schematic  
Bryce Denney  
February 2002

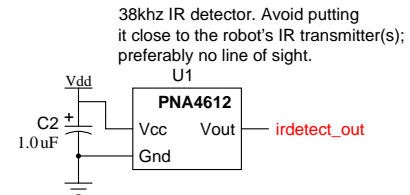
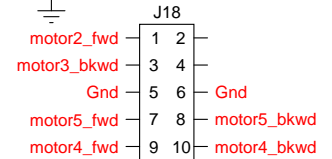
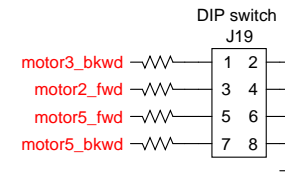
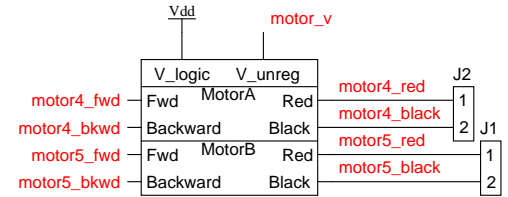
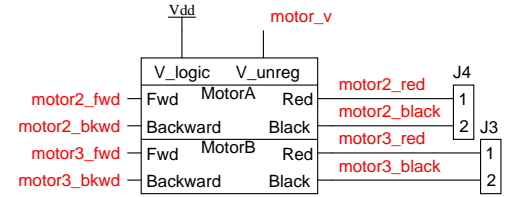
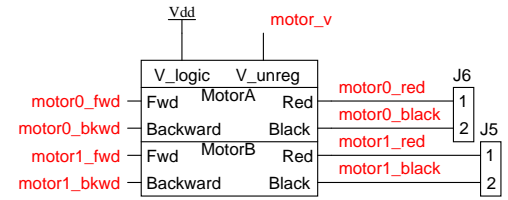
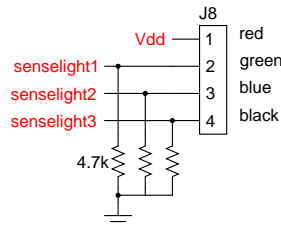
Note: Use script called "combine-quad-nand" to fix up the netlist before sending to PCB.



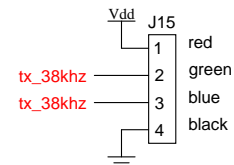
Put jumper on J14 pins 1&2 to use motor supply for logic too. Or apply 7V+ across pins 2&3 for separate logic supply. Or apply regulated 5V across pins 3&4 with separate motor supply.



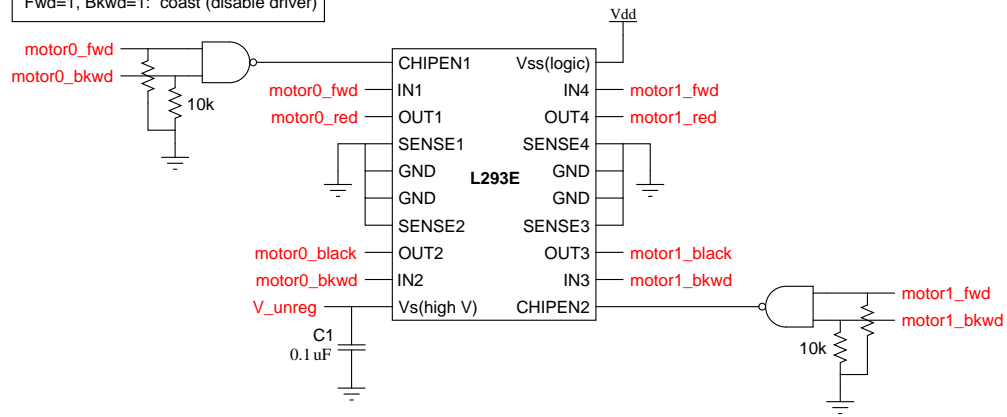
Analog light sensor readings



IR transmitter header



Encoding:  
 Fwd=0, Bkwd=0: brake  
 Fwd=1, Bkwd=0: forward  
 Fwd=0, Bkwd=1: backward  
 Fwd=1, Bkwd=1: coast (disable driver)



All motor outputs have protection diodes.

