

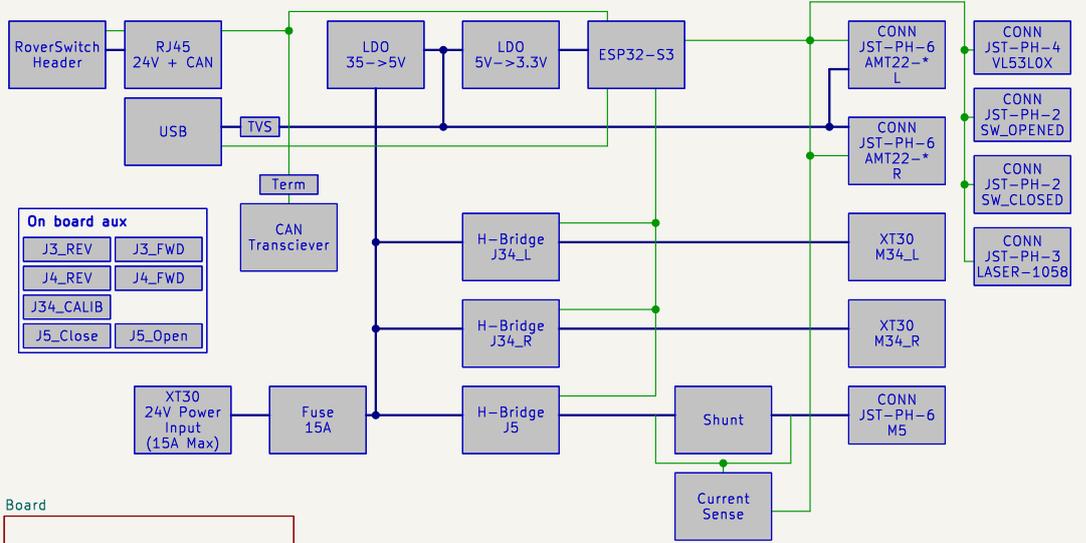
**PCB Order settings**  
 - Layer count: 4  
 - Stackup nb: JLC04161-H-7628

**PCB Description**  
 The ArmJ345 interface 3 low amp (<6A) motor drivers to drive the differential wrist and the gripper. The gripper is torque controlled with a current sensor on the driver's output.  
 There's also a lidar in the gripper to evaluate the position of the object we're trying to grab. This PCB allows a RoverSwitch PCB to be stack over it to share 24V and CAN

**Off board parts to order**  
 TODO

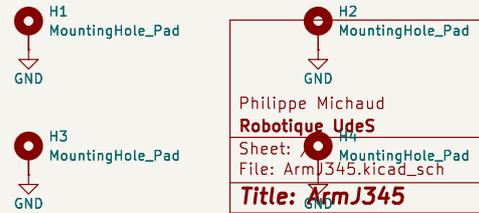
- |                             |              |
|-----------------------------|--------------|
| ST0242                      | 1528-1403-ND |
| JUMPER 2PINS (QPC02SXGN-RC) |              |
| PHR-2                       | PHR-2        |
| PHR-3                       | PHR-4        |
| PHR-6                       | PHR-6        |
| PHR-6                       |              |

**Board block schematic**



Board  
 File: Board.kicad\_sch

**Mechanical parts**



Philippe Michaud  
**Robotique UdeS**  
 Sheet: 1/2  
 File: ArmJ345.kicad\_sch  
**Title: ArmJ345**  
 Size: A5 Date: 2025-02-08  
 KiCad F.D.A. 9.0.0

**Rev: 2**  
 Id: 1/2

	1	2	3	4	5	6
A						A
B						B
C						C
D						D
	1	2	3	4	5	6

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**Robotique UdeS**

Sheet: /Board/  
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Id: 2/2