

Qu-Bot Pin-outs

Qu-Bot works on ATMEL ATMega16 microcontroller. You can reprogram it and customize code according to your requirements. This data is for advance users only.

The Pin-outs for ATMega16/32 to Qu-Bot are as shown below.

Inputs	Outputs
<p>Front Left Sensor : PA3 Front Centre Sensor : PA4 Front Right Sensor : PA5</p> <p>Bottom Right Sensor : PA0 Bottom Centre Sensor : PA1 Bottom Left Sensor : PA2</p> <p>Wheel Encoder Left : PD2 (INT0) Wheel Encoder Right : PD3 (INT1)</p> <p>IR Input : PB2 (INT2)</p> <p>Switch1 : PC4 Switch2 : PD7 Switch3 : PD6</p> <p>*All above sensors are active low. Front bottom and wheel encoder sensors are digital inputs.</p> <p>LDR : PA6 (ADC6)</p>	<p>Left Motor Forward : PC1 Left Motor Backward : PC0 Left Motor PWM : PD5(OCR1A) Right Motor Forward : PC2 Right Motor Backward : PC3 Right Motor PWM : PD4(OCR1B)</p> <p>Buzzer : PA7</p> <p>LED1 : PC5 LED2 : PC6 LED3 : PC7</p> <p>LCD LCD DATA0 : PB4 LCD DATA1 : PB5 LCD DATA2 : PB6 LCD DATA3 : PB7 LCD ENABLE : PB3 LCD R/W: PB1 LCD RS : PB0</p> <p>USB RX : PD0(RXD) TX : PD1(TXD) DTR : RESET (Controller gets reset when it receives pulse on DTR line)</p>