



Micro DC Motor with Encoder-SJ02 SKU: FIT0458



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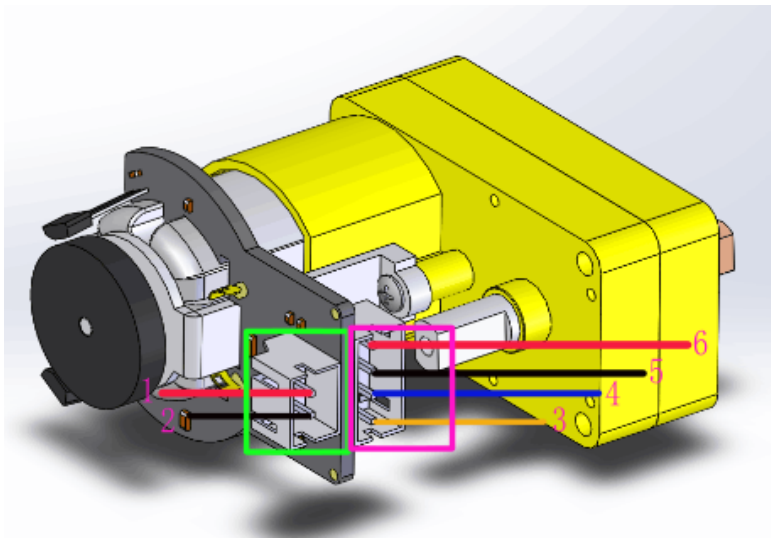
Introduction

This is the DFRobot Micro DC geared motor with encoder. It is a motor with a 120:1 gearbox and an integrated quadrature encoder that provides a resolution of 16 pulse single per round giving a maximum output of 1920 within one round. With an Arduino controller and motor driver, applications for this might include a closed-loop PID control or PWM motor speed control. This motor is an ideal option for mobile robot projects. The copper output shaft, embedded thread and reinforced connector greatly extends the motor's service life.

Specification

- Gear ratio: 120:1
- No-load speed @ 6V: 160 rpm
- No-load speed @ 3V: 60 rpm
- No-load current @ 6V: 0.17A
- No-load current @ 3V: 0.14A
- Max Stall current: 2.8A
- Max Stall torque: 0.8kgf.cm
- Rated torque: 0.2kgf.cm
- Encoder operating voltage: 4.5~7.5V
- Motor operating voltage: 3~7.5V (Rated voltage 6V)
- Operating ambient temperature: -10~+60°C

Pin Description



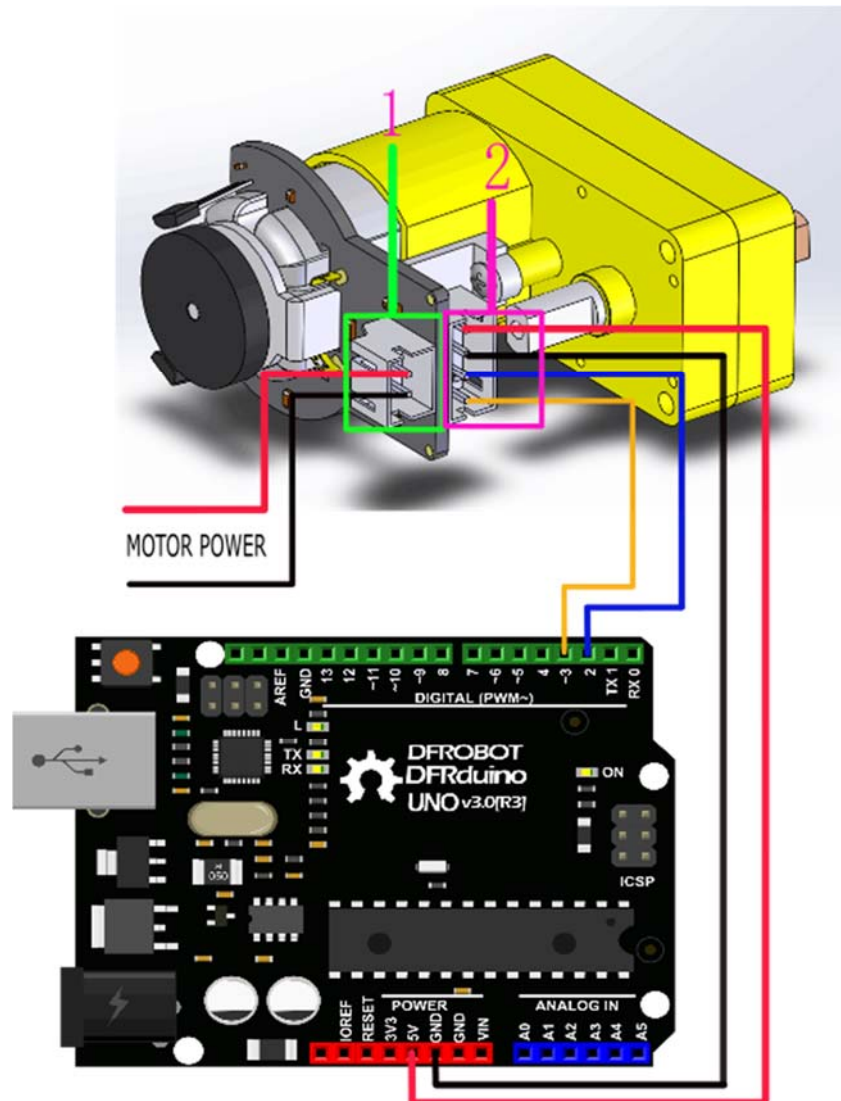
Grade	Name	Functional Description
1	Motor power supply pin +	3-7.5V, Rated voltage 6V
2	Motor power supply pin -	
3	Encoder A phase output	Changes square wave with the output frequency of Motor speed
4	Encoder B phase output	Changes square wave with the output frequency of Motor speed(interrupt port)
5	Encoder supply GND	
6	Encoder supply +	4.5-7.5V

Tutorial

Ready to work

- **hardware**
DFRduino UNO x1
DC power supply x1
L298 x1
- **software**
Arduino IDE Download Arduino IDE <https://www.arduino.cc/en/Main/Software>

Wiring Diagram



This tutorial is intended to use the encoder, Select D2 pin and D3 pin, Wherein D2 as an interrupt port, D3 as an input pin. In practice, two pins need to ensure that one of pins must be an interrupt pin, and the other definable (see the interrupt port with different board).

Interrupt Port with Different Board

Notcie: attachInterrupt()

Board	int.0	int.1	int.2	int.3	int.4	int.5
Uno, Ethernet	2	3				
Mega2560	2	3	21	20	19	18
Leonardo	3	2	0	1	7	

If using an Arduino UNO and you want to use interrupt port 0 (Int.0), you need to connect digital pin D2 on the board. The following code is only used in UNO and Mega2560. If you want to use Arduino Leonardo, you should change digital pin D3 instead of digital pin D2.

See the link for details <http://arduino.cc/en/Reference/AttachInterrupt>

Encoder Sample Code 1

```
//The sample code for driving one way motor encoder
const byte encoder0pinA = 2;//A pin -> the interrupt pin 0
const byte encoder0pinB = 3;//B pin -> the digital pin 3
byte encoder0PinALast;
int duration;//the number of the pulses
boolean Direction;//the rotation direction

void setup()
{
  Serial.begin(57600);//Initialize the serial port
  EncoderInit();//Initialize the module
}

void loop()
{
  Serial.print("Pulse:");
  Serial.println(duration);
  duration = 0;
```

```

    delay(100);
}

void EncoderInit()
{
    Direction = true;//default -> Forward
    pinMode(encoder0pinB, INPUT);
    attachInterrupt(0, wheelSpeed, CHANGE);
}

void wheelSpeed()
{
    int Lstate = digitalRead(encoder0pinA);
    if((encoder0PinALast == LOW) && Lstate==HIGH)
    {
        int val = digitalRead(encoder0pinB);
        if(val == LOW && Direction)
        {
            Direction = false; //Reverse
        }
        else if(val == HIGH && !Direction)
        {
            Direction = true; //Forward
        }
    }
    encoder0PinALast = Lstate;

    if(!Direction) duration++;
    else duration--;
}

```

Code 1 Expected Output:

Explanation: Here you can see serial data. When the motor turns forward, the digital output value is > 0. When the motor reverses direction, digital output < 0. The faster the motor's speed, the greater the value of the number.

Pulse:-118	Pulse:117
Pulse:-119	Pulse:117
Pulse:-119	Pulse:118
Pulse:-119	Pulse:116
Pulse:-119	Pulse:116
Pulse:-119	Pulse:117
Pulse:-120	Pulse:116
Pulse:-119	Pulse:116
Pulse:-120	Pulse:117
Pulse:-118	Pulse:117
Pulse:-119	Pulse:117
Pulse:-118	Pulse:117
Pulse:-118	Pulse:118
Pulse:-119	Pulse:117
Pulse:-118	Pulse:117
Pulse:-119	Pulse:118
Pulse:-119	Pulse:118
Pulse:-119	Pulse:118
Pulse:-119	Pulse:117
Pulse:-120	Pulse:118
Pulse:-120	Pulse:116
Pulse:-120	Pulse:116
Pulse:-120	Pulse:116
Pulse:-120	Pulse:116
Pulse:-120	Pulse:116
Pulse:-119	Pulse:116

Encoder Sample Code2

PID control : PID algorithm to control the motor speed by L298P DC motor driver board

1. Motor power port is connected to the L298 drive motor M1 port
 2. Download and install Arduino PID <https://github.com/br3ttb/Arduino-PID-Library/>

```
//The sample code for driving one way motor encoder
#include <PID_v1.h>
const byte encoder0pinA = 2;//A pin -> the interrupt pin 0
const byte encoder0pinB = 3;//B pin -> the digital pin 3
int E_left =5; //The enabling of L298PDC motor driver board connection to the
digital interface port 5
int M_left =4; //The enabling of L298PDC motor driver board connection to the
digital interface port 4
```

```

byte encoder0PinALast;

double duration,abs_duration;//the number of the pulses
boolean Direction;//the rotation direction
boolean result;

double val_output;//Power supplied to the motor PWM value.
double Setpoint;
double Kp=0.6, Ki=5, Kd=0;
PID myPID(&abs_duration, &val_output, &Setpoint, Kp, Ki, Kd, DIRECT);

void setup()
{
    Serial.begin(9600);//Initialize the serial port
    pinMode(M_left, OUTPUT);    //L298P Control port settings DC motor driver board for the output mode
    pinMode(E_left, OUTPUT);
    Setpoint =80; //Set the output value of the PID
    myPID.SetMode(AUTOMATIC);//PID is set to automatic mode
    myPID.SetSampleTime(100);//Set PID sampling frequency is 100ms
    EncoderInit();//Initialize the module
}

void loop()
{
    advance();//Motor Forward
    abs_duration=abs(duration);
    result=myPID.Compute();//PID conversion is complete and returns 1
    if(result)
    {
        Serial.print("Pluse: ");
        Serial.println(duration);
        duration = 0; //Count clear, wait for the next count
    }
}

```

```

}

void EncoderInit()
{
    Direction = true;//default -> Forward
    pinMode(encoder0pinB,INPUT);
    attachInterrupt(0, wheelSpeed, CHANGE);
}

void wheelSpeed()
{
    int Lstate = digitalRead(encoder0pinA);
    if((encoder0PinALast == LOW) && Lstate==HIGH)
    {
        int val = digitalRead(encoder0pinB);
        if(val == LOW && Direction)
        {
            Direction = false; //Reverse
        }
        else if(val == HIGH && !Direction)
        {
            Direction = true; //Forward
        }
    }
    encoder0PinALast = Lstate;

    if(!Direction) duration++;
    else duration--;

}

void advance();//Motor Forward
{
    digitalWrite(M_left,LOW);
    analogWrite(E_left,val_output);
}

```



```
}  
void back();//Motor reverse  
{  
    digitalWrite(M_left,HIGH);  
    analogWrite(E_left,val_output);  
}  
  
void Stop();//Motor stops  
{  
    digitalWrite(E_left, LOW);  
}
```

Code 2 Expected Behaviour:

The code PID value has been set as 80, so the motor will stabilize at about 80 rpm. If outside forces such as changes in motor drive voltage, the motor's resistance, etc affect the speed, the program will adjust the PWM value to stabilize the rotational speed at 80.

More

- Motor dimension drawing
https://github.com/Arduinolibrary/DFRobot_Micro_DC_Geared_Motor_with_Encoder/raw/master/FIT0458%20Micro%20DC%20Motor%20with%20Encoder-SJ02.pdf