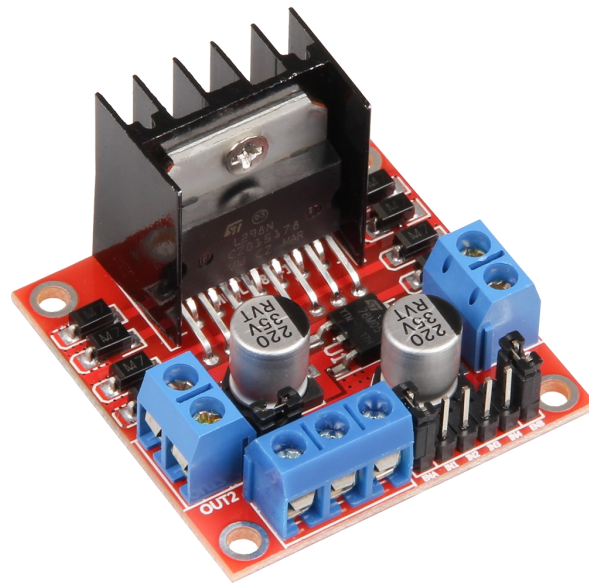


MotoDriver2



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Dear customer,
thank you for purchasing our product. Please find our instructions below.

1. Introduction

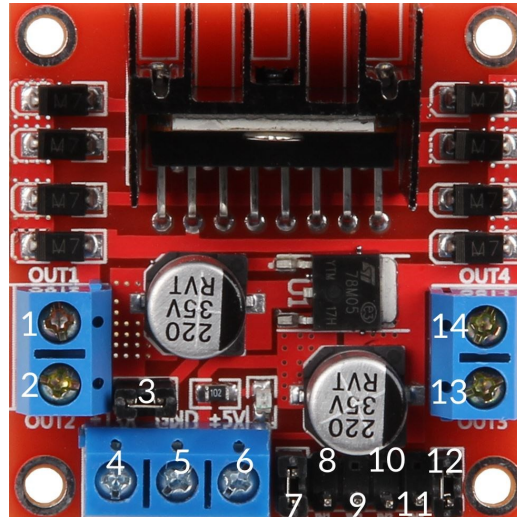
The MotoDriver2 is an extension-board which allows you to control and use up to two direct-current motors at once.

The motors can be controlled with a constant voltage from 5V to 35V.

Technical Specification

Model	SBC-MotoDriver2
Driver	L298N
Logical voltage	5V
Drive Voltage	5V— 35V
Drive Current	2A
Power	Max. 25W
Dimensions (L x B x H)	43mm x 43mm x 27mm
Scope of delivery	MotoDriver2
EAN	425023681513

2. PIN Assignment

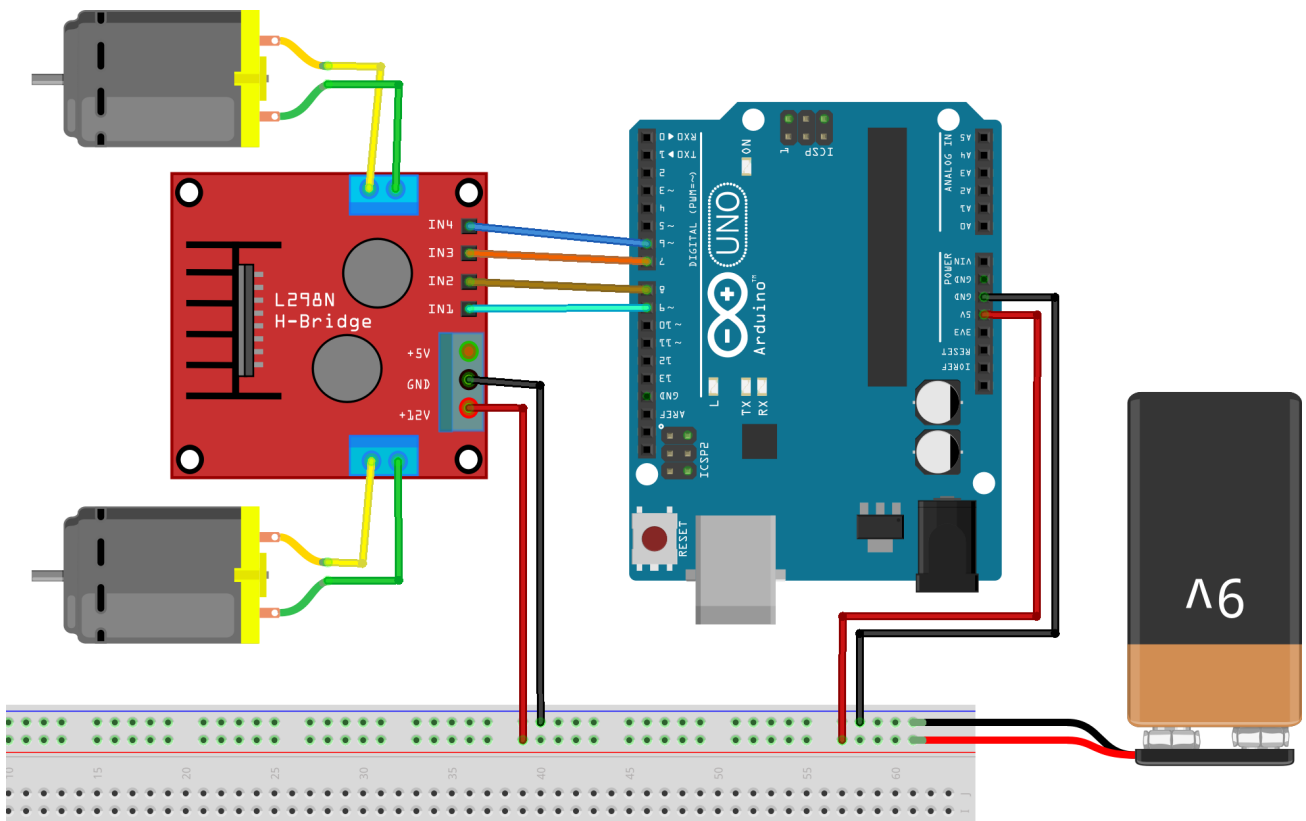


PIN	Belegung
1	DC Motor 1 / Stepper Motor +
2	DC Motor 1 / Stepper Motor GND
3	12V Jumper
4	Power Supply +
5	Power Supply GND
6	5V Output (if Jumper 3 is in place)
7	DC Motor 1 Jumper
8	Input 1
9	Input 2
10	Input 3
11	Input 4
12	DC Motor 2 Jumper
13	DC Motor 2 / Stepper Motor +
14	DC Motor 2 / Stepper Motor GND

Note: Remove the Jumper at position 3 if your power supply is above 12V. This activates the power supply for the on-board 5V regulator.

The 5V output is perfect for supplying power to an Arduino. This output is only active, if the jumper on position 3 is set.

3. Anschluss an einen Arduino Uno



MotoDriver 2	Arduino
Input 1	9
Input 2	8
Input 3	7
Input 4	6

The power supply for the MotoDriver2 (PIN 4) needs to be between 5V and 35V, depending on your setup.

4. Verwendung

To use the motors with the module, connect the motors, the module and your Arduino as seen in the image before.

Transfer the following code-example to your Arduino to test the functionality.testen.

```
//Motor 1
const int motorPin1 = 9;
const int motorPin2 = 8;
//Motor 2
const int motorPin3 = 7;
const int motorPin4 = 6;

int speed = 180;

void setup(){

    //Set pins as outputs
    pinMode(motorPin1, OUTPUT);
    pinMode(motorPin2, OUTPUT);
    pinMode(motorPin3, OUTPUT);
    pinMode(motorPin4, OUTPUT);

    //Motor Control A in both directions
    analogWrite(motorPin1, speed);
    delay(2000);
    analogWrite(motorPin1, 0);
    delay(200);
    analogWrite(motorPin2, speed);
    delay(2000);
    analogWrite(motorPin2, 0);

    //Motor Control B in both directions
    analogWrite(motorPin3, speed);
    delay(2000);
    analogWrite(motorPin3, 0);
    delay(200);
    analogWrite(motorPin4, speed);
    delay(2000);
    analogWrite(motorPin4, 0);

}

void loop(){

}
```