

# Motor Constraint

Reference

**Panel:**  
Physics ▸ Rigid Body Constraint

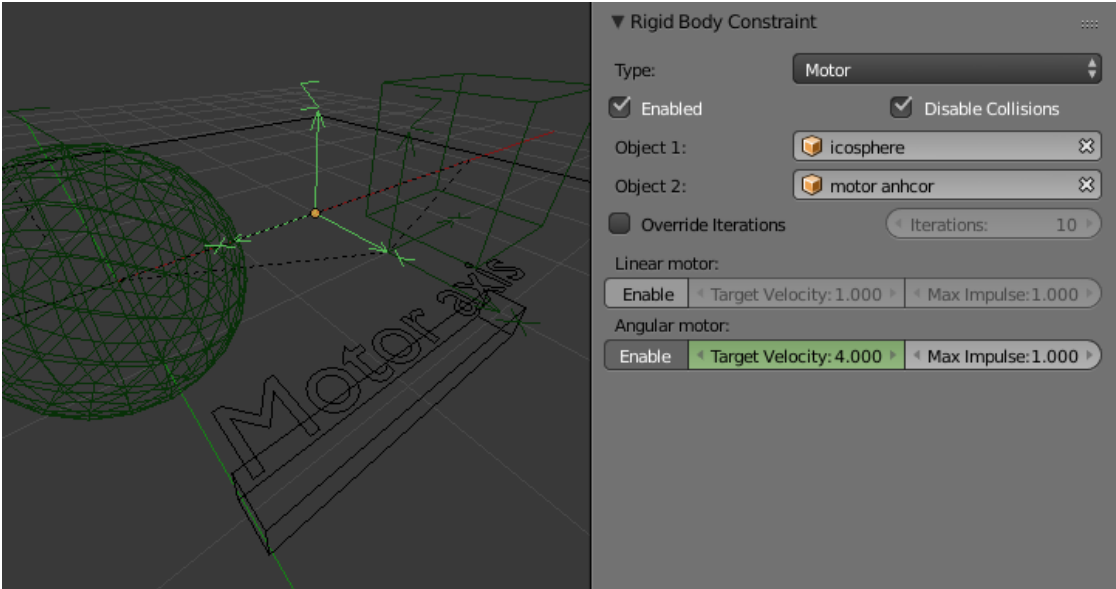
**Type:**  
Motor

The motor constraint causes translation and/or rotation between two entities. It can drive two objects apart or together. It can drive simple rotation, or rotation and translation (although it will not be constrained like a screw since the translation can be blocked by other physics without preventing rotation)

The rotation axis is the X axis of the object hosting the constraint. This is in contrast with the Hinge which uses the Z axis. Since the Motor is vulnerable to confusing perturbations without a matching Hinge constraint, special care must be taken to align the axes. Without proper alignment, the motor will appear to have no effect (because the hinge is preventing the motion of the motor).

TODO

Update image



The screenshot shows a 3D environment with a wireframe sphere and a wireframe cube. A motor constraint is applied between them, indicated by a red line and arrows. The settings panel on the right is titled 'Rigid Body Constraint' and shows the following options:

- Type: Motor
- Enabled: ☒
- Disable Collisions: ☒
- Object 1: icosphere
- Object 2: motor anchor
- Override Iterations: ☐ Iterations: 10
- Linear motor: ☐ Enable Target Velocity: 1.000 Max Impulse: 1.000
- Angular motor: ☒ Enable Target Velocity: 4.000 Max Impulse: 1.000

Motor constraint options.

## Options

### Linear Motor/Angular Motor

**Enable**

Enable linear or angular motor respectively.

**Target Velocity**

Target linear or angular motor velocity respectively.

**Max Impulse**

Maximum linear or angular motor impulse respectively.

