Motor Geared With Encoder

Notes

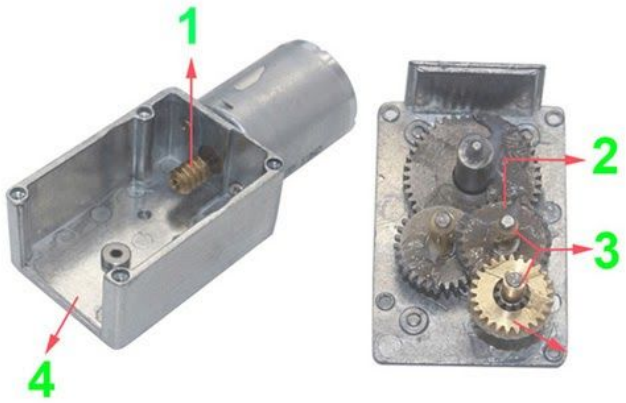
Micro DC Worm Gear Motor Hall Encoder 12V 90RPM Electric Mini Motors With Self Locking Adjustable Speed And Reversed For Robot Smart Device etc.
Name of the motor: JGY-370B 12V Mini Worm Gear Motor Encoder In DC Motor
Rated voltage have DC 12V
Speed:90rpm
Rated torque between 0.2 To 26.5 KG.CM; stall torque: between 0.9-45KG
Direction of rotation of the motor: CW Or CCW, Support Reversed; Control the clockwise or counterclockwise rotation of the motor by changing the way the positive and negative electrodes are connected
The motor has a self-locking function ; After disconnect the power supply, the shaft can be securely locked, can not easy to move by other force. When your project is not connected to the power, you can make your project safely stay somewhere.

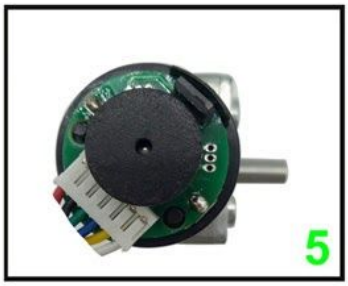
Motor Wiring

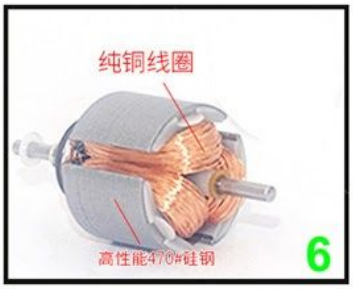
1. Red line: the positive pole of the motor is connected to the positive pole of the power supply +
2. Black wire: the negative pole of the motor is connected to the negative pole of the power supply -
3. Green line: Connect sensor ground wire - (5V)
4. Blue line: connect sensor power + (5V)
5. Yellow line: signal A output point (11 pulses)
6. White line: signal B output point (11 pulses)

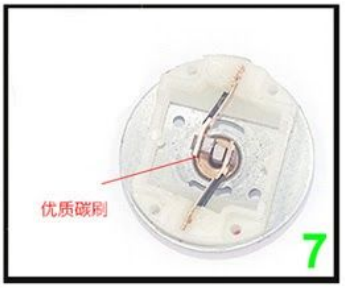
Motor Parts

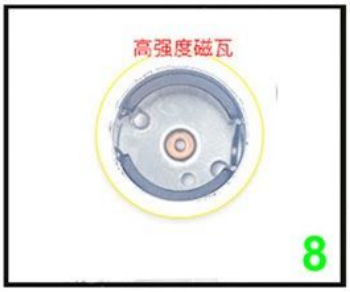
1. The worm gear is made of copper
2. Imported lubricants used
3. Use all metal gears
4. The gearbox is made of aluminum alloy
5. The encoder has two Hall elements bi-phase AB output, the basic signal 11PPR
6. Pure copper coil, high temperature resistance, super conductive, life is 10 times that of Inferior motor
7. High quality carbon brush, wear-resistant, prolongs the service life of the motor
8. high quality magnet, complete and does not change the magnetic field, so that the performance is the motor is better, and the rotor does not get stuck
9. D-axis
10. The encoder has a protective cover to prevent the encoder from being damaged and preventing water droplets from splashing onto the encoder

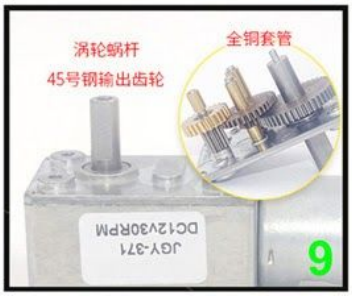


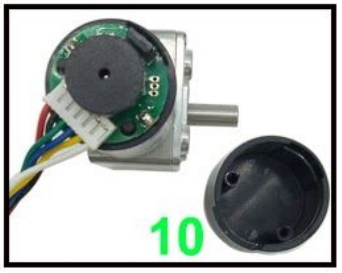




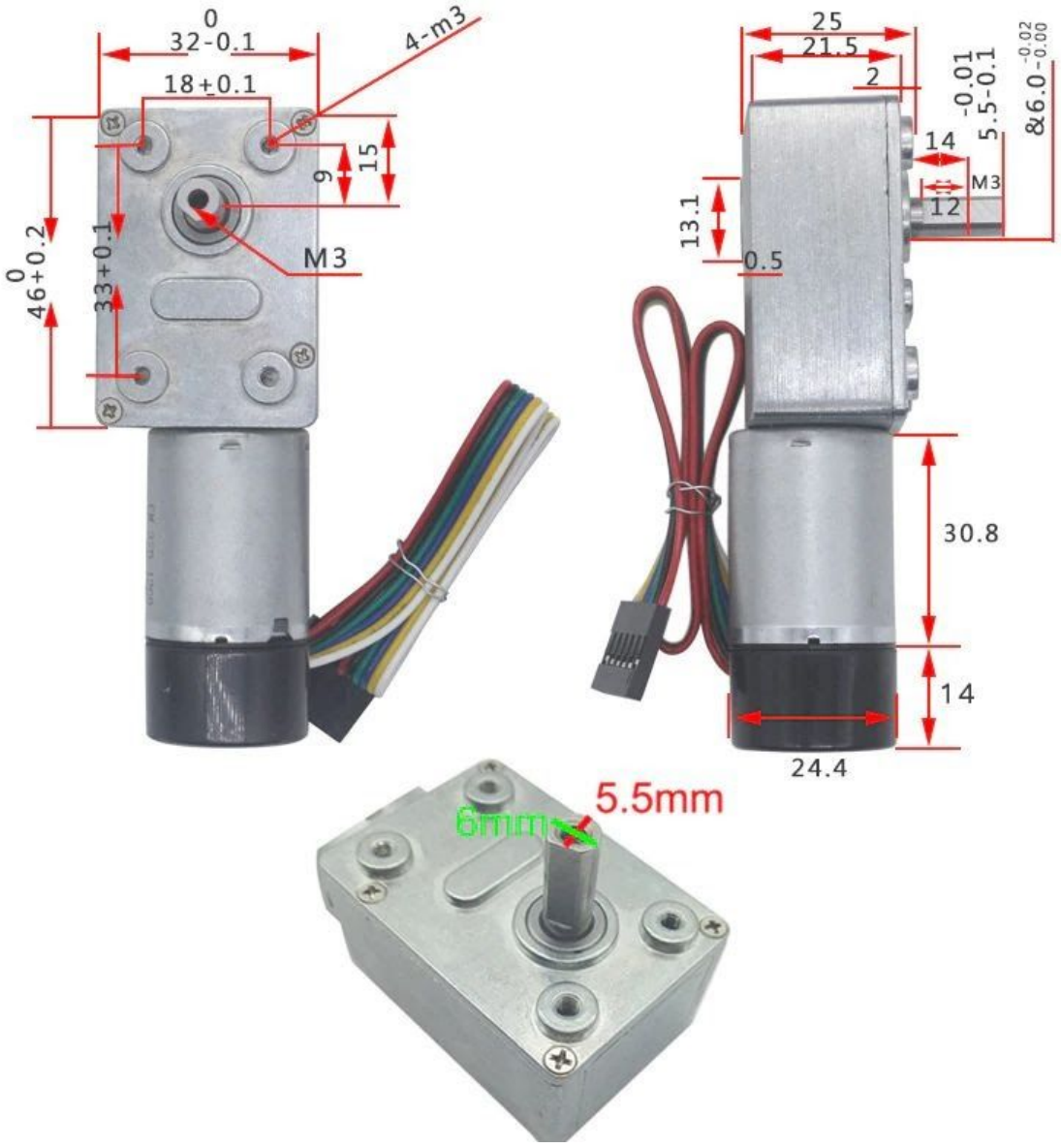








Mechanical Dimensions



Parameters

Reduction ratio (коэффициент уменьшения)	Rated voltage (Номинальное напряжение)	No load		Load (Рабочая нагрузка)			Stall (Maximum)	
		Speed	Current	Speed	Current	Rated torque (крутящий момент)	Torque (крутящий момент)	Current
(1 :00)	(V)	r/min (±10%)	(MA)	r/min (±10%)	(A)	(kg.cm)	(kg.cm)	(A)
1000	6	6	≤100	4	≤0.6	26.5	45	3.3
600	6	10	≤100	7.5	≤0.6	15.9	30	3.3
340	6	18	≤100	15	≤0.6	9	18	3.3
260	6	23	≤100	18	≤0.6	6.7	13	3.3
200	6	30	≤100	22	≤0.6	5.3	10	3.3
150	6	40	≤100	30	≤0.6	2	7.5	3.3
90	6	66	≤100	51	≤0.6	0.7	2	3.3
65	6	90	≤100	70	≤0.6	0.5	1.6	3.3
40	6	150	≤100	120	≤0.6	0.2	0.9	3.3
1000	12	6	≤60	4	≤0.6	26.5	45	1.7
600	12	10	≤60	7.5	≤0.6	15.9	30	1.7
340	12	18	≤60	15	≤0.6	9	18	1.7
260	12	23	≤60	18	≤0.6	6.7	13	1.7
200	12	30	≤60	22	≤0.6	5.3	10	1.7
150	12	40	≤60	30	≤0.6	2	7.5	1.7
90	12	66	≤60	51	≤0.6	0.7	2	1.7
65	12	90	≤60	70	≤0.6	0.5	1.6	1.7
40	12	150	≤60	120	≤0.6	0.2	0.9	1.7
1000	24	6	≤40	4	≤0.3	26.5	45	0.85
600	24	10	≤40	7.5	≤0.3	15.9	30	0.85
340	24	18	≤40	15	≤0.3	9	18	0.85
260	24	23	≤40	18	≤0.3	6.7	13	0.85
200	24	30	≤40	22	≤0.3	5.3	10	0.85
150	24	40	≤40	30	≤0.3	2	7.5	0.85
90	24	66	≤40	51	≤0.3	0.7	2	0.85
65	24	90	≤40	70	≤0.3	0.5	1.6	0.85
40	24	150	≤40	120	≤0.3	0.2	0.9	0.85

Sincere reminder
Your project load should not exceed the rated torque of the motor load, otherwise the life of the motor will be reduced.

Искреннее напоминание
Ваша проектная нагрузка не должна превышать номинальный крутящий момент нагрузки двигателя,в противном случае срок службы двигателя будет сокращен.