

双H桥直流电机驱动板

L298 Dual H-Bridge Motor Driver

用户手册
User's Guide

HEX

DC motor

5.5-16v
DC



all jumps plug in

In3 In4 ENB no connection

EA=H I1=H,I2=L MOTOR A corotation
I1=L,I2=H MOTOR A reversal
I1=I2 MOTOR A STOP
EA=L I1=X,I2=I1 MOTOR A STOP

motor B is as same as motor A
H:high level
L:low level
X:H or L

this jump plug in

双H桥直流电机驱动板

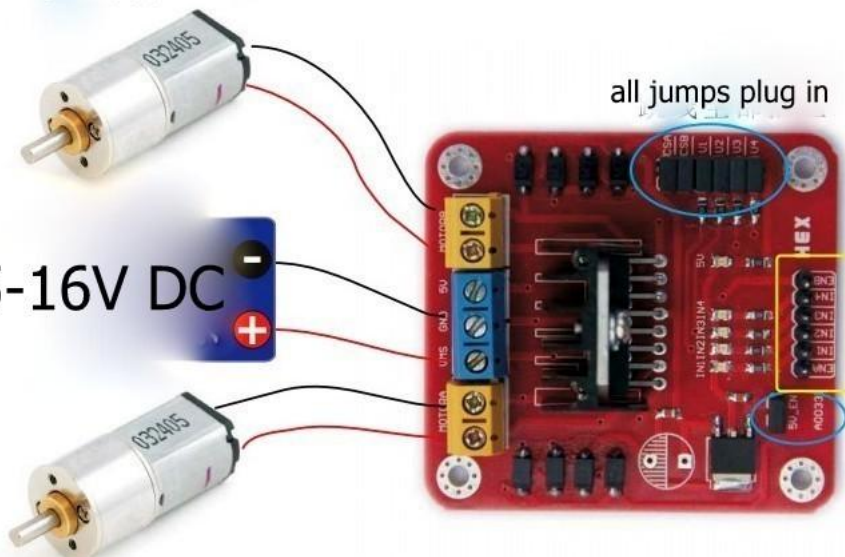
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2 DC motor

5.5-16V DC



EA=H I1=H,I2=L MOTOR A corotation
I1=L,I2=H MOTOR A reversal
I1=I2 MOTOR A STOP
EA=L I1=X,I2=I1 MOTOR A STOP

motor B is as same as motor A
H:high level
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this jump plug in

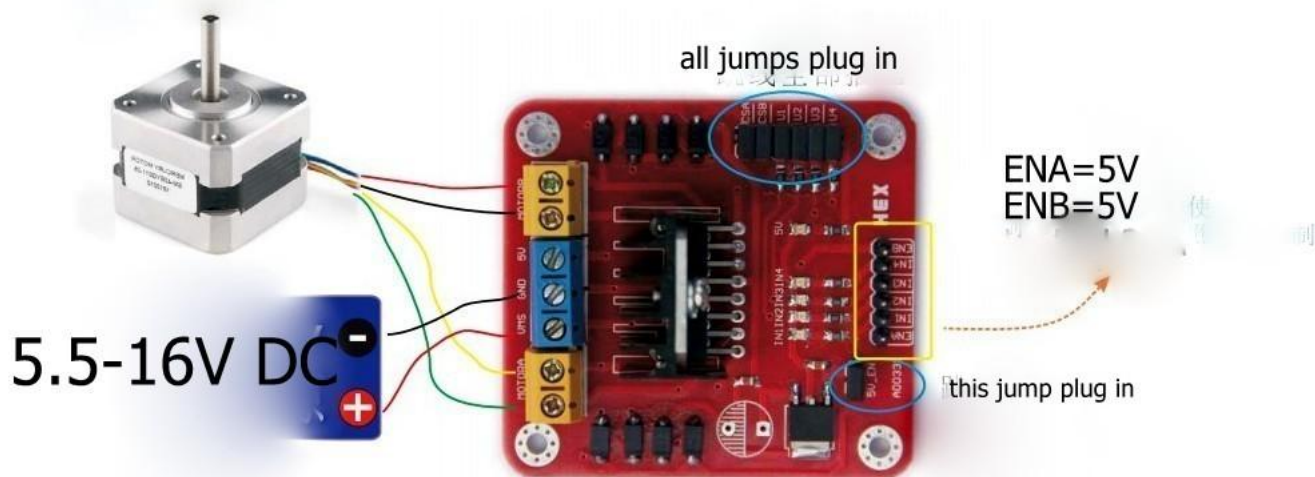
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stepping motor



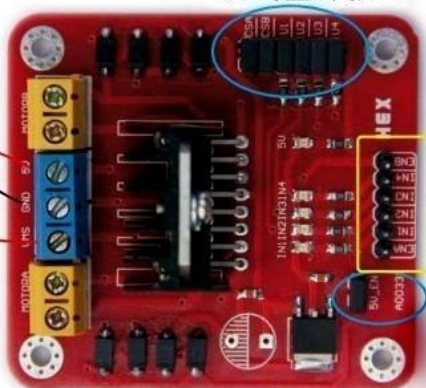
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4v-5.5v dc



all jumps plug in

when using motor A
In3 In4 ENB no connection

EA=H I1=H,I2=L MOTOR A corotation
I1=L,I2=H MOTOR A reversal
I1=I2 MOTOR A STOP
EA=L I1=X,I2=I1 MOTOR A STOP

motor B is as same as motor A
H:high level
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this jump plug out

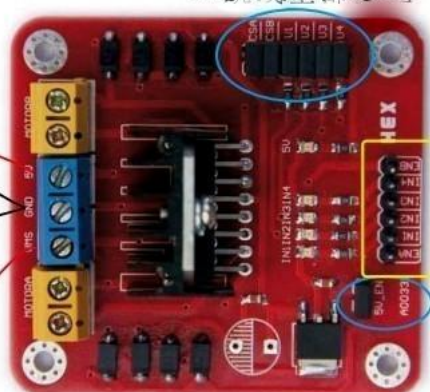
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TWO POWER SUPPLY



when using motor A
In3 In4 ENB no connection

EA=H I1=H,I2=L MOTOR A corotation
I1=L,I2=H MOTOR A reversal
I1=I2 MOTOR A STOP
EA=L I1=X,I2=I1 MOTOR A STOP

motor B is as same as motor A
H:high level
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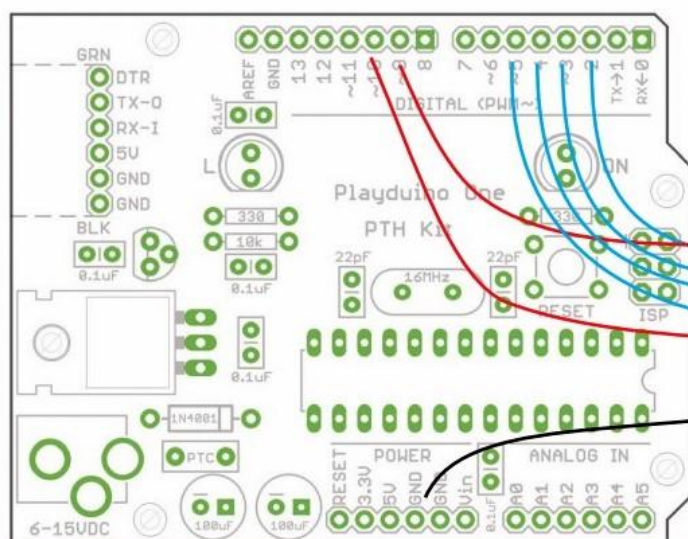
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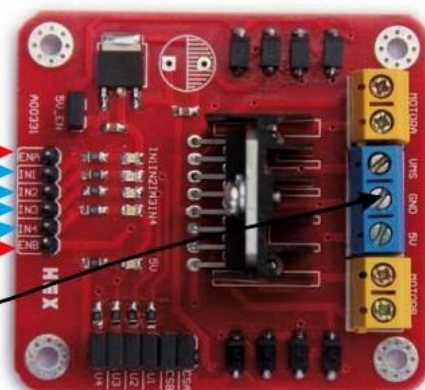
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与Arduino的连接：



L298n模块供电参见前面几页介绍



注：红色线可以使用PWM进行直流电机调速，不需要调速或者步进电机可以去掉不接。

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4线2相步进电机Arduino例程： Four line two phase motor arduino routine

```
#include <Stepper.h>
//ENA--9 IN1--2 IN2--3 IN3--4 IN4--5 ENB--10
// change this to the number of steps on your motor
#define STEPS 200
// create an instance of the stepper class, specifying
// the number of steps of the motor and the pins it's
// attached to
Stepper stepper(STEPS, 2, 3, 4, 5);
void setup()
{
  stepper.setSpeed(300);
  pinMode(10, OUTPUT);
  pinMode(9, OUTPUT);
}
void loop()
{
  digitalWrite(8, HIGH);
  digitalWrite(9, HIGH);
  stepper.step(50);
  delay(500);
  stepper.step(-50);
  delay(500);
  stepper.step(200);
  delay(500);
  stepper.step(-200);
  delay(500);
}
```



直流电机Arduino例程： DC motor arduino routine

```
// motor A
int dir1PinA = 2;
int dir2PinA = 3;
int speedPinA = 9;
// motor B
int dir1PinB = 4;
int dir2PinB = 5;
int speedPinB = 10;
unsigned long time;
int speed;
int dir;

void setup() {
  pinMode(dir1PinA, OUTPUT);
  pinMode(dir2PinA, OUTPUT);
  pinMode(speedPinA, OUTPUT);
  pinMode(dir1PinB, OUTPUT);
  pinMode(dir2PinB, OUTPUT);
  pinMode(speedPinB, OUTPUT);
  time = millis();
  speed = 0;
  dir = 1;
}

void loop() {
  analogWrite(speedPinA, speed);
  analogWrite(speedPinB, 255 - speed);
  // set direction
  if (1 == dir) {
    digitalWrite(dir1PinA, LOW);
    digitalWrite(dir2PinA, HIGH);
    digitalWrite(dir1PinB, HIGH);
    digitalWrite(dir2PinB, LOW);
  } else {
    digitalWrite(dir1PinA, HIGH);
    digitalWrite(dir2PinA, LOW);
    digitalWrite(dir1PinB, LOW);
    digitalWrite(dir2PinB, HIGH);
  }
  if (millis() - time > 5000) {
    time = millis();
    speed += 20;
    if (speed > 255) {
      speed = 0;
    }
  }
  if (1 == dir) {
    dir = 0;
  } else {
    dir = 1;
  }
}
```



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电路原理图：

