1.7A 55Ncm 48mm Nema-17 Stepper Motor

A stepper motor to satisfy all your 3D-Printer, robotics, Linear Motion projects needs. This 4-wire bipolar stepper has 1.8° per step for smooth motion and a nice holding torque. This motor specified to have a max current of 1.5A/phase so that it could be driven easily with common motor shield for Arduino (or other motor driver) and a wall adapter or lead-acid battery.

SKU: FAM1049

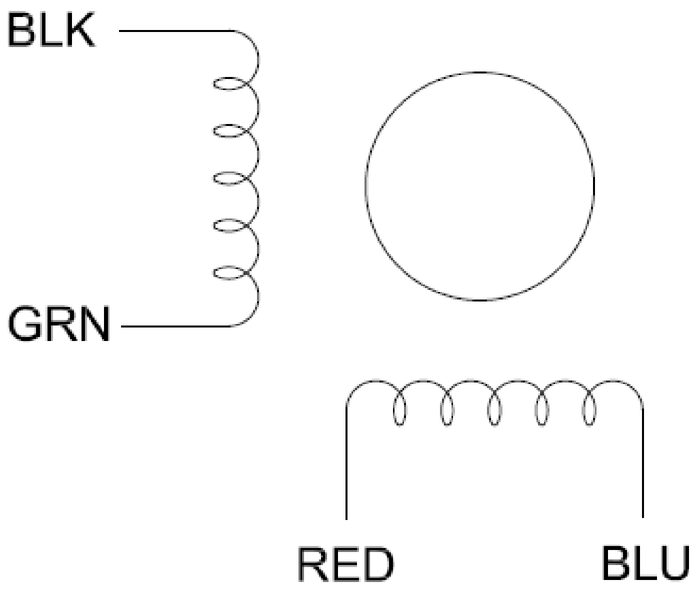
Brief Data:

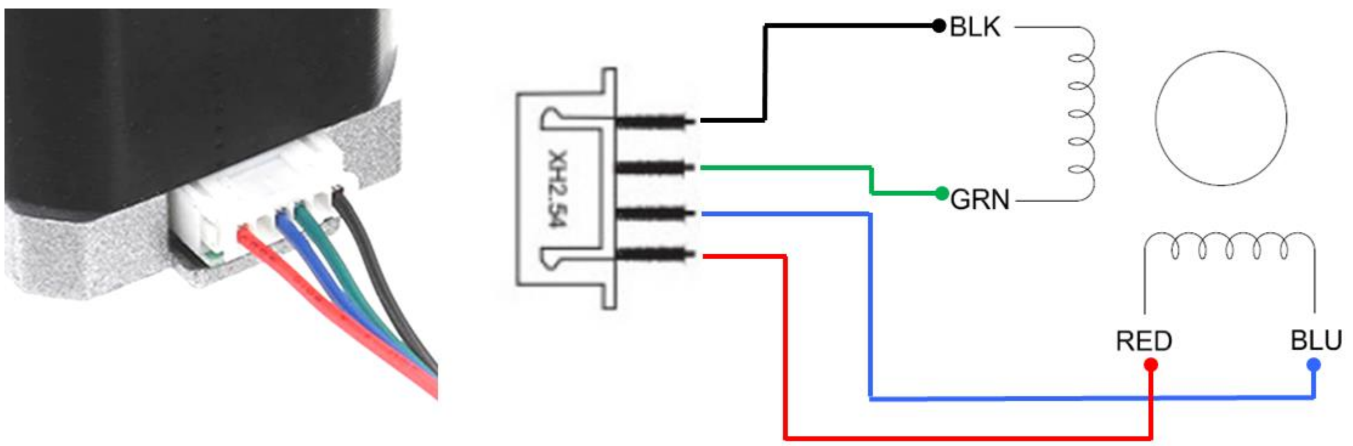
- Nema17 Bipolar 42BYGH48-4170.
- Number of Phase: 2.
- Step Angle: 1.8°.
- Phase Current: 1.7A.
- Resistance: 3.3Ω ±10%
- Inductance: 2.8mH ±20% (1KHz).
- Number of Wire: 4 (100cm Length).
- Motor Body Length: 48mm.
- Holding Torque: 55N.cm.
- Shaft Diameter: Ø5mm D-Shape.
- Rotor Inertia: 57gcm^2.
- Temperature rise: 80°C Max.
- Dielectric Strength: 500VAC/1-minute
- Mass: 300g

Application:

- 3D Printer
- CNC machines
- Linear actuators
- Prototyping machines
- Prototyping machines
- Precision Telescope
- Pick and place machines

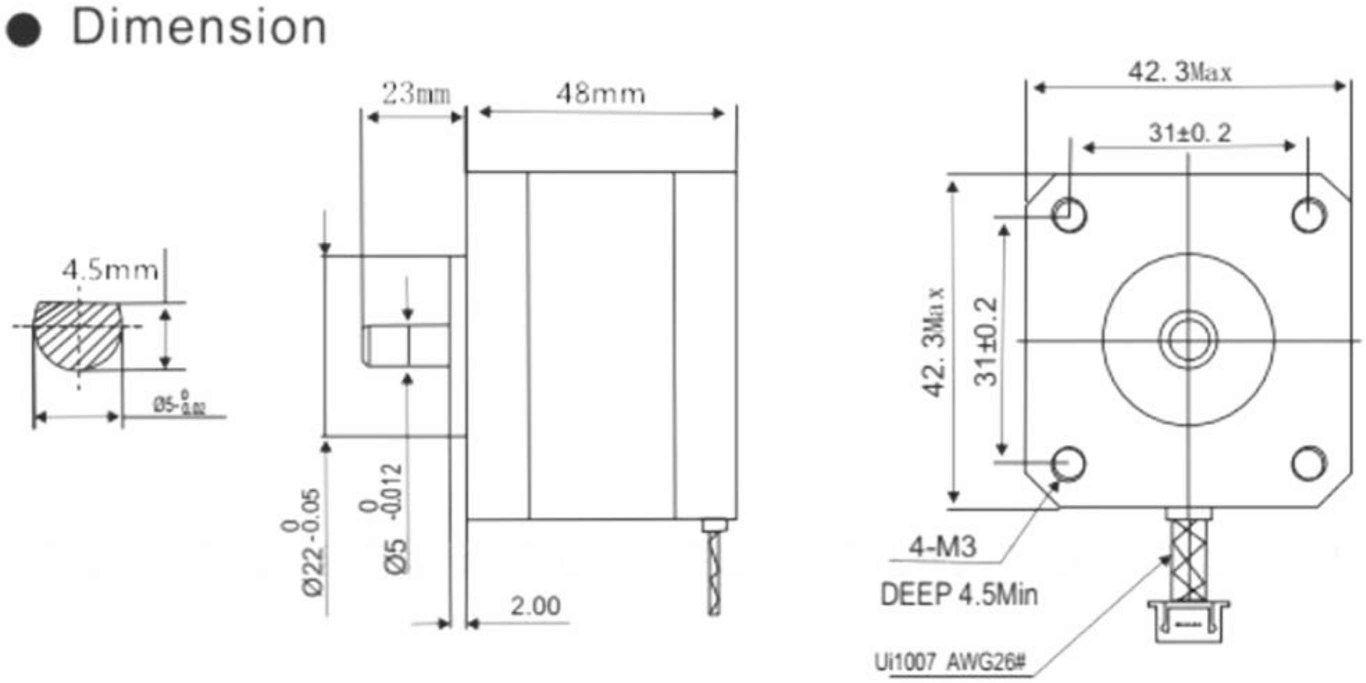
Connection Diagram:

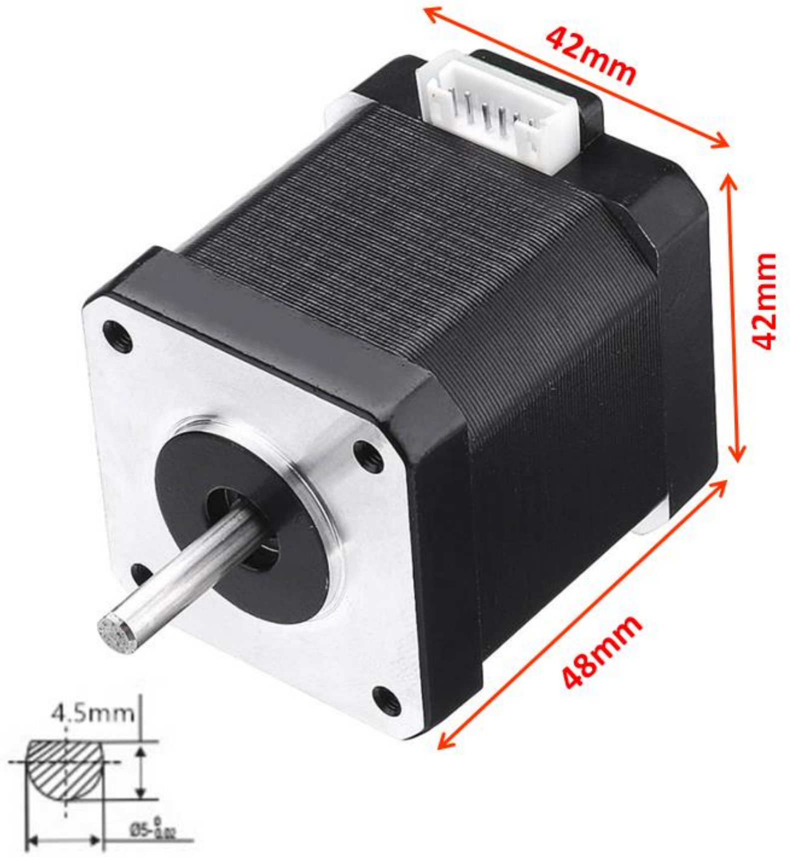




Mechanical Dimension:

Unit: mm





Application Note: Useful Motor/Torque Equations

Force (Newtons)
F = m x a
m = mass (kg)
a = acceleration (m/s2)

Motor Torque (Newton-meters)
T = F x d
F = force (Newtons)
d = moment arm (meters)

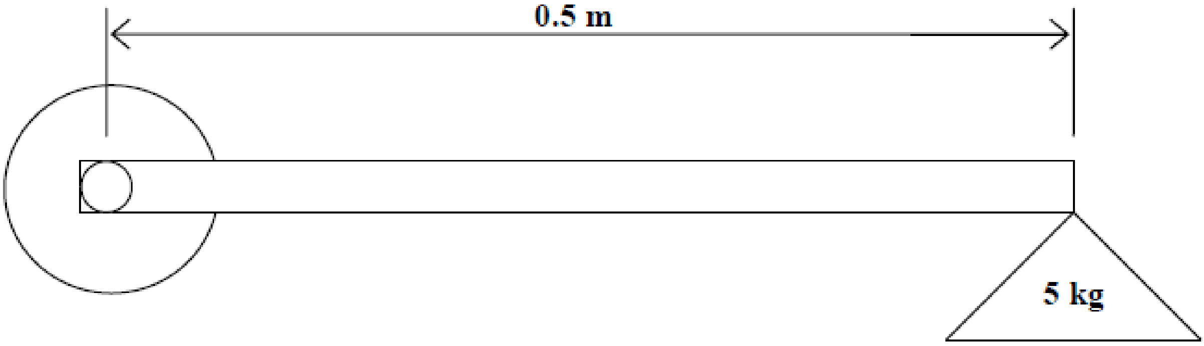
Power (Watts)
P = I x V
I = current (amps)
V = voltage (volts)

P = T x ω
T = torque (Newton-meters)
ω = angular velocity (radian/second)

Unit Conversions
Length (1 in = 0.0254 m)
Velocity (1 RPM = 0.105 rad/sec)
Torque (1 in-lb = 0.112985 N-m)
Power (1 HP = 745.7 W)

Example 1
Determine if the following motor can be used to lift a 5-kg load using a 0.5-m lever arm.

Merkle-Korff Gearmotor specifications
Stall Torque = 40 in-lb
Stall Current = 3.5 amps



Solution
Convert Stall Torque from in-lb to N-m

1 in-lb = 0.112985 N-m

40 in-lb = 40 x 0.112985 N-m = 4.5194 N-m

Calculate the Force required to lift the 5-kg load
F = m x a = 5 kg x 9.81 m/s2 = 49.05 N

Calculate the Torque required to lift the Force with the lever arm
T = F x d = 49.05 N x 0.5 m = 24.525 N-m

We cannot perform the lift with this set-up, because the stall torque is smaller than the torque required for the lift. We must either shorten the length of the lever arm, or we must choose another motor with a higher stall torque to perform this operation.

Example 2

Using the same motor as in Example 1 with a 12-V power supply:

a) Calculate the power used by the motor to rotate a 5-kg load at 50 RPM using a 3-inch lever arm.

b) Calculate the current draw from the battery to perform this operation.

Solution

Convert inches to meters:

1 in = 0.0254 m

3 in = 0.0762 m

Calculate the Force required to lift the 5-kg load:

F = m x a = 5 kg x 9.81 m/s2 = 49.05 N

Calculate the Torque required for this operation:

T = F x d = 49.05 N x 0.0762 m = 3.738 N-m

> Note- This toque is lower than the motor's stall torque, so this operation is possible using the specified motor, mass, and lever arm

Convert RPM to radians/second:

1 RPM x 2π rad/rev x 1 min/60 sec = 0.105 rad/sec

ω = 50 rev/min x 0.105 rad/sec/RPM = 5.25 rad/sec

Calculate the Power required for this operation:

P = T x ω = 3.738 N-m x 5.25 rad/sec = 19.622 W

Calculate the Current draw from the battery (use the supply voltage in this calculation):

I = P/V = 19.622 W/12 V = 1.635 Amps

Note- This current is smaller than the maximum allowable current draw of the motor.

Example 3
Determine the motor torque necessary to power the robot drive wheels.

Solution
The following approach is merely one way to solve this problem. Several exist.
Assume the robot will be powered by two powered drive wheels and supported by two freely rotating caster wheels. Robot weight is denoted by W and for this simple example we'll assume the weight is distributed evenly over all 4 wheels, as shown in Figure 1 below.

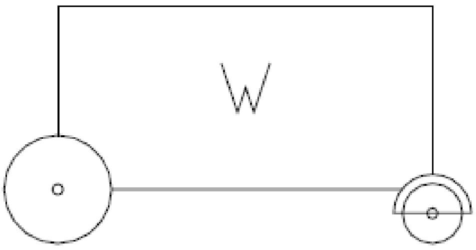


Figure 1

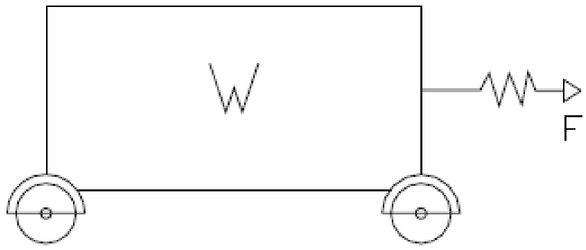


Figure 2

Thinking logically about the problem, we could model the robot as having 4 of the identical caster wheels (Figure 2) and the force required to propel the robot is simply the force needed to start the robot moving (this could be measured empirically with a force scale). The problem is we haven't yet built the robot so testing it in this manner is not an option. We need to calculate the force (and hence motor torque) required to move the robot **before** we build anything.
Looking closer at the caster wheel we can see the actual friction that must be overcome to put the robot in motion. Fw is the friction force between the wheel and the floor and Fa is the friction force between the wheel and the axle. Tw and Ta are the respective torques between the wheel and floor and the wheel and axle.

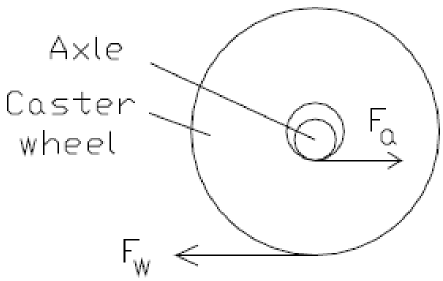


Figure 3

$Fa = W/2 * \mu a$
$Ta = Fa * Ra$
$Fw = W/2 * \mu w$
$Tw = Fw * Rw$
Tw is the *maximum* torque the wheel can transmit to the ground before it slips.

Our goal is to find a realistic range for Tm, the motor torque.
As calculated above, Tw would be the *maximum* amount of torque the motor could transfer to the ground before the wheel begins to slip (ie Tm, max).
Typically, we desire $\mu w > \mu a$, so the wheel does not slip/slide across the floor, but rather rolls. We can easily look up the μa value for the axle/wheel materials in contact. Knowing μa and the weight of the vehicle, Fa can be computed. This is the *minimum* amount of force we would have to provide at the wheel/axle interface to overcome the friction between the two. To relate the computed axle force Fa to the *minimum* amount of

wheel torque required to move the robot, we would use the "virtual radius" of the wheel/axle combination, which is computed as follows:

Rv = Rw – Ra

This is the fictitious radius about which Fa would act to rotate the wheel about the tangent point in contact with the ground at any instant, as shown in Figure 4 below.

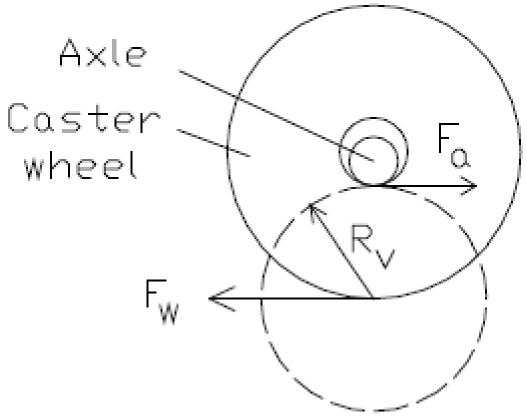


Figure 4

Therefore our equation for the *minimum* amount of torque the motor must transfer to the ground before the wheel begins to roll (thus causing the robot to move) would be:

Tm (min = Fa * Rv = Fa * (Rw – Ra)

In summation, Tm, min ≤ Tm ≤ Tm, max or alternatively, Fa * (Rw – Ra) ≤ Tm ≤ Fw * Rw

Motors, Fans and Accessories Selection

40x40x10 mm DC Brushless Cooling Fan

Ultra quiet powerful brushless DC fan, quiet sleeve-bearing design. Specialized design, professional made, stable performance. Operating Temperature: -10 C to +60C. Long Life Expectancy.

EMH-1071 **GDT4010S12B** **RM 6.50**

GA12-N20 Geared Mini DC Motor

This is a DC Mini Metal Gear Motor, ideal for making robots. Light weight, high torque and low RPM. Fine craftsmanship, durable, not easy to wear. Widely used on boat, model car, robotic, home appliances, linear motion control.

EMH-1176 **GA12-N20** **RM 18.50**

30x30x10 mm DC Brushless Cooling Fan

Ultra quiet powerful brushless DC fan, quiet sleeve-baring design. Specialized design, professional made, stable performance. Operating Temperature: -10 C to +60C. Long Life Expectancy.

EMH-1070 **GDT3010S12B** **RM 7.50**

Nema23 Bipolar/Unipolar Stepper Motor 1.0A

A stepper motor to satisfy all your 3D-Printer, robotics, Linear Motion projects needs! This 6-wire uni-polar/bipolar stepper motor has 1.8° per step for smooth motion and a nice holding torque.

EMH-1179 **23HS2610** **RM 110.00**

1.2A Nema 17 Stepper Motor

A stepper motor to satisfy all your 3D-Printer, robotics, Linear Motion projects needs! This 4-wire bipolar stepper has 1.8° per step for smooth motion and a nice holding torque.

EMH-1016 **42HS40-1204D** **RM 44.50**

1.7A Nema 17 Stepper Motor

A stepper motor to satisfy all your 3D-Printer, robotics, Linear Motion projects needs! This 4-wire bipolar stepper has 1.8° per step for smooth motion and a nice holding torque.

EMH-1181 **17HS-4401SD** **RM 47.00**

SG90 Tower Pro Gear Micro Servo Motor

Tiny and lightweight with high output power. Servo can rotate approximately 180 degrees (90 in each direction). Good for beginners who want to make stuff move without building a motor controller with feedback & gear box.

EMH-1140 **TPSG90S** **RM 7.40**

Nema-17 Planetary Geared Stepper Motor

This high precision NEMA17 Stepper motor has an integrated Planetary Gearbox with 1:5.18 gear ratio, the resolution can reach 0.35°step angle.

EMH-1173 **42BYGP40P** **RM 185.00**

HandsOn Technology provides a multimedia and interactive platform for everyone interested in electronics. From beginner to diehard, from student to lecturer. Information, education, inspiration and entertainment. Analog and digital, practical and theoretical; software and hardware.

open source hardware

Hands*On* Technology support Open Source Hardware (OSHW) Development Platform.

Learn : Design : Share

www.handsontec.com

The Face behind our product quality…

In a world of constant change and continuous technological development, a new or replacement product is never far away – and they all need to be tested.
Many vendors simply import and sell wihtout checks and this cannot be the ultimate interests of anyone, particularly the customer. Every part sell on Handsotec is fully tested. So when buying from Handsontec products range, you can be confident you're getting outstanding quality and value.

We keep adding the new parts so that you can get rolling on your next project.

Breakout Boards & Modules

Connectors

Electro-Mechanical Parts

Engineering Material

Mechanical Hardware

P

Electronics Components

Power Supply

Arduino Board & Shield

Tools & Accessory