

Roller485 Unit, New Robot Motor by M5Stack

Code

```
C
#include <Wire.h>

#define I2C_ADDRESS 0x64 // Unit Roller485 I2C address

void setup() {
  Wire.begin();
  Serial.begin(115200);
  delay(1000);

  // init Unit Roller485
  initRoller485();
}

void loop() {
  // speed 100 RPM
  setMotorSpeed(100);
  delay(10000);

  // stop
  setMotorSpeed(0);
  delay(5000); // Stop for 5 seconds and then restart
}

void initRoller485() {
  Wire.beginTransmission(I2C_ADDRESS);
  Wire.write(0x00); // Mode Switch
  Wire.endTransmission();
  delay(100);
}

void setMotorSpeed(int speed) {
  Wire.beginTransmission(I2C_ADDRESS);
  Wire.write(0x01); // Mode Setting
  Wire.write(speed & 0xFF); // speed low
```

```
Wire.write((speed >> 8) & 0xFF); // speed high
byte error = Wire.endTransmission();

if (error == 0) {
  Serial.println("Motor speed set successfully");
} else {
  Serial.print("Error setting motor speed: ");
  Serial.println(error);
}
}
```