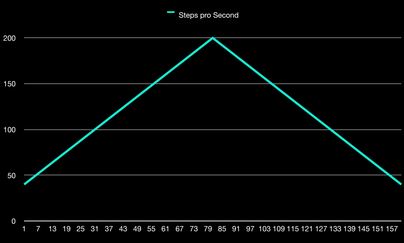
180 Deg Steps

Steps	Steps pro Second
1	40
2	42
3	44
4	46
5	48
6	50
7	52
8	54
9	56
10	58
11	60
12	62
13	64
14	66
15	68
16	70
17	72
18	74
19	76
20	78
21	80
22	82
23	84
24	86
25	88
26	90
27	92
28	94
29	96
30	98
31	100
32	102
33	104
34	106
35	108
36	110
37	112
38	114
39	116
40	118
41	120
42	122
43	124
44	126
45	128
46	130
47	132
48	134
49	136
50	138
51	140
52	142
53	144
54	146
55	148
56	150
57	152
58	154
59	156
60	158
61	160
62	162
63	164
64	166
65	168
66	170
67	172
68	174
69	176
70	178
71	180
72	182
73	184
74	186
75	188
76	190
77	192
78	194
79	196
80	198
81	200
82	198
83	196
84	194
85	192
86	190
87	188
88	186
89	184
90	182
91	180
92	178
93	176
94	174
95	172
96	170
97	168
98	166
99	164
100	162
101	160
102	158
103	156
104	154
105	152
106	150
107	148
108	146
109	144
110	142
111	140
112	138
113	136
114	134
115	132
116	130
117	128
118	126
119	124
120	122
121	120
122	118
123	116
124	114
125	112
126	110
127	108
128	106
129	104
130	102
131	100
132	98
133	96
134	94
135	92
136	90
137	88
138	86
139	84
140	82
141	80
142	78
143	76
144	74
145	72
146	70
147	68
148	66
149	64
150	62
151	60
152	58
153	56
154	54
155	52
156	50
157	48
158	46
159	44
160	42
161	40



Every half-step is 0.9, therefore 0.9 * 180 = 161 Steps needed for a 180 Degree rotation.
The speed is being controlled by the input parameter >>step_frequency<< where the minimum is 1 and maximum is 255 steps pro Second. Therefore the data below shows that the speed should increase linear to the the step. After the motor reach 161/2 = 81 Steps it should decrease its speed until it goes back into 40 Steps pro seconds and should therefore stop.

When the steps == 161 and the direction change, the steps should be reseted into 0

entity Crane_Control
port: