**Motor Notes**

N=number of steps

*Full-stepping mode:*

* 200 steps = 1 rotation
* 1 step = 1.8 degrees

Not enough resolution…set to half stepping

*Half-stepping mode:*

* 400 steps = 1 rotation 🡪 stay within this boundary
* 1 step = 0.9 degrees
* Need to handle case where N=400
  + Let’s say that the normal direction of operation is CW for 0 to 360 degrees
  + Change direction using “<” for CCW
  + Change speed to a fast value
  + Travel 400 steps to reset position
  + Continue tracking
  + This should never happen though…
  + Works both ways, don’t travel CCW past 0 degrees