## TASK\_MOTOR Start INIT Sets motor to run at 30% of **BRAKE** full power Turns on the brake by connecting both ends of the motor to ground Always enable\_brake() called **SCANNING** If position gets within ten degrees of zero from either side, set the motor to turn in the opposite direction disable\_brake() called move\_to\_target() called **MOVING TO TARGET** While in this state, run the PI controller to move the return\_to\_scanning() camera to a target position called and hold it there