

## Controller

```
+AZ_DEGREES_PER_TICK: float
+EL_DEGREES_PER_TICK: float
+directionAZ: byte = 0
+directionEL: int = 0
+currentAZ: float
+currentEL: float
+statusAZ: int
+statusEL: int
+targetAZ: float
+targetEL: float
+ser: Serial
```

```
+connect(port:string): string
+disconnect(): void
+moveHome(): void
+move(RA:float,DEC:float): void
+__parseFeedback(line:string): void
+__sendCommand(command:string): void
+__checkFeedback(): void
```



```
+AZ_TICKS_PER_DEGREE: float = 11.7
+EL_TICKS_PER_DEGREE: float = 11.7
+AZ_HOME: float = 0
+EL_HOME: float = 0
+STATION_LAT: double = 36.381355
+STATION_LON: float = -82.4155
+STATION_ALT: float = 453
+MotionStatus: string[] = ['Stopped','M
+CONTROLLER_PORT: string = /dev/ttyACM0
```

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## Constants

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'Moving', 'Homing', 'Stopped/Unverified', Dis  
3

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| sconnected'] |
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