

Class: Motor	
Responsibilities: The overall responsibility of this class is control of the motor and prevention of unsafe operation. It provides start/stop control as well as the ability to move the motor to a fixed angular location. The class can drive the motor through a predefined time sequence of angular locations. Because this class often needs to execute in a separate thread, many of its methods are synchronized. The class is also responsible for providing status on the motor in terms of current speed and angular position.	
Collaborators	
Uses: SpeedEncoder, MotorPowerSwitch, EmergencyAlarm, SystemTimer	Used by: MotorThread, InletWaterSupply, SolarPanelPositioner
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