Man Machine Interface
POCXXXX
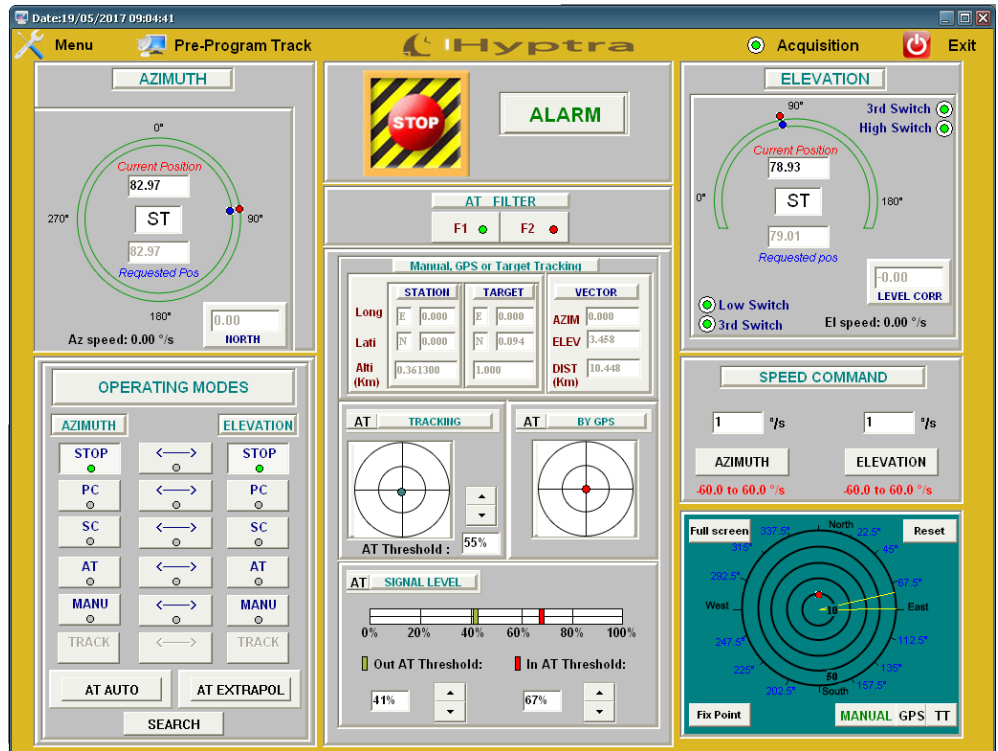
Operating mode	Description
STOP	Stop on El. and/or Az. brakes are switched on. The pedestal stops on the selected axis
PC	**Position Command**, The pedestal reaches the desired angular position
SC	**Speed Command**, The pedestal rotates at the desired angular speed
Manual	The pedestal reaches El. and/or Az. angles computed with the target and pedestal GPS informations entered manually.
GPS	The pedestal elaborates El. and/or Az. angles through the target GPS information received by RS232 or IP link under NMEA0183 standard. The target range is calculated and displayed on the screen.
TLE	The pedestal computes the El. and/or Az. angles of the target using a Two Line Element file
AT	**Auto Tracking**, the target is followed using tracking data, with tracking error angle criteria or HF signal level criteria.
AT supported by GPS	Automatically switch between GPS and AT modes when the target enter or exit the –3dB aperture angle of the antenna
Extrapolation	When auto tracking is lost, the pedestal continues traveling with extrapolated speeds
Program Track	Tracking following a predicted trajectory download from computer
Fixed points	Store El. and Az. angles in an array
Survival	The pedestal reaches 90° on El. Both axis are stopped