Pegasus Astro

DMFCv3 Serial Command Language

Firmware >= v.2.6 (April 2017)

Abbreviations used:
nnnn.. = one or more digits

Serial Connection Settings: 19200, 8N1
(All commands should be terminated by new line: \n)
(All responses are terminated by new line: \n)

Command	Description	Response
#	Status (Controller is operational)	OK_DMFCN
A	Consolidates printed values status: version: motor_mode: temperature: position: moving_status: led_status: reverse: disabled encoder: backlash value:	OK_DMFCN:2.6:1:22.4:50:0:1:1:0:100
B	Returns motor max speed	*B:nnn.nn*
C	Backlash compensation C:0 (Disables compensation) C:nnnn (Enables compensation and sets nnn steps) **Setting is stored in EEPROM**	-
E	Disables rotary encoder for manual operation E:1 (encoder is off) E:0 (encoder is on)	E:0 | E:1
V	Firmware version	n.n
T	Temperature in Celsius	nn.nn
P	Returns current position	nnnn
H	Halt Focuser (emergency stop)	-
I	Stepper motor moving status (0 = idle, 1 = is moving)	0 | 1
M	Move motor to new position E.g M:1100	-
G	Move motor +-steps from current position E.g G:-100 or G:100	-
S	Set motor max speed E.g. S:400 **Setting is stored in EEPROM**	-
L	Led status L:2 (Switch LED ON) L:1 (Switch LED OFF) L (Print LED Status)	L command returns L:0 | L:1 (0=Led is OFF, 1=Les is ON)
R	Select “motor type” Stepper: 1, DC: 0 **Setting is stored in EEPROM**	0 | 1 (Returns “motor type”)
N	Reverse motor direction N:0 (normal) or N:1 (reverse)	N:1 | N:0
W	Change existing motor position E.g W:1000 will set controller’s position to 1000 without moving the motor	-
X	Returns Rotary Encoder Position	nnn..