Pegasus Astro

Prodigy Microfocuser Serial Command Language
Firmware >= v.1.4 (Nov 2021)

Abbreviations used:

nnnn.. = one or more digits

b = boolean (0 or 1)

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_PRDG
A	Consolidates printed values status: version: motor_mode: temperature: position: moving_status: led_status: (for this product always 0) reverse: (for this product always 0) disabled encoder: (for this product always 0) backlash value:	Example: OK_PRDG:2.6:1:22.4:50:0:1:1:0:100
B	Returns motor max speed (steps per sec)	*B:nnnn*
C	Backlash compensation C:0 (Disables compensation) C:nnnn (Enables compensation and sets nnn steps) **Setting is stored in EEPROM**	C:nnnn
D	Status of Power and Data (USB) ports. (Power Port 1: Power Port 2: USB 1: USB 2) (0 = OFF, 1 = ON)	D:b:b:b:b E.g: D:1:1:0:1
V	Firmware version	n.n
T	Temperature in Celsius degrees	nn.nn
P	Returns current position	nnnn
H	Halt Focuser (emergency stop)	0
I	Stepper motor moving status (0 = idle, 1 = is moving)	0 | 1
U	Disable / Enable USB Port 1 (0 = OFF, 1 = ON)	U:b
J	Disable / Enable USB Port 2 (0 = OFF, 1 = ON)	J:b
M	Move motor to new absolute position E.g M:1100	M:nnnn
G	Move motor +-steps from current position E.g G:-100 or G:100	G:nnnn
S	Set motor max speed (unsigned int) E.g. S:400 **Setting is stored in EEPROM**	S:nnnn
X	Disable / Enable Power Port 1 (0 = OFF, 1 = ON)	X:b
Y	Disable / Enable Power Port 2 (0 = OFF, 1 = ON)	Y:b
N	Reverse motor direction Report always normal (0) / cannot change value	N:0
W	Change existing motor position E.g W:1000 will set controller's position to 1000 without moving the motor	W:nnnn
Q	Device reboot /reset	-
Z	Park Focuser to zero position (until it reached zero encoder)	Z:1