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```
[fb]  firmware build            440.20
[fv]  firmware version            0.97
[hp]  hardware platform           1.00
[hv]  hardware version            8.00
[id]  TinyG ID                  3X3566-HJV
[ja]  junction acceleration 2000000 mm
[ct]  chordal tolerance           0.0100 mm
[sl]  soft limit enable           0
[st]  switch type                 1 [0=NO,1=NC]
[mt]  motor idle timeout          2.00 Sec
[ej]  enable json mode            0 [0=text,1=JSON]
[jv]  json verbosity              4 [0=silent,1=footer,2=messages,3=configs,4=linenum,5=verbose]
[js]  json serialize style        1 [0=relaxed,1=strict]
[tv]  text verbosity              1 [0=silent,1=verbose]
[qv]  queue report verbosity      1 [0=off,1=single,2=triple]
[sv]  status report verbosity     1 [0=off,1=filtered,2=verbose]
[si]  status interval           250 ms
[ec]  expand LF to CRLF on TX     0 [0=off,1=on]
[ee]  enable echo                 0 [0=off,1=on]
[ex]  enable flow control         1 [0=off,1=XON/XOFF, 2=RTS/CTS]
[baud] USB baud rate              5 [1=9600,2=19200,3=38400,4=57600,5=115200,6=230400]
[net] network mode                0 [0=master]
[gpl] default gcode plane         0 [0=G17,1=G18,2=G19]
[gun] default gcode units mode    1 [0=G20,1=G21]
[gco] default gcode coord system  1 [1-6 (G54-G59)]
[gpa] default gcode path control  2 [0=G61,1=G61.1,2=G64]
[gdi] default gcode distance mode 0 [0=G90,1=G91]
[1ma] m1 map to axis              0 [0=X,1=Y,2=Z...]
[1sa] m1 step angle             1.800 deg
[1tr] m1 travel per revolution   40.0000 mm
[1mi] m1 microsteps               8 [1,2,4,8]
[1po] m1 polarity                 0 [0=normal,1=reverse]
[1pm] m1 power management         2 [0=disabled,1=always on,2=in cycle,3=when moving]
[2ma] m2 map to axis              1 [0=X,1=Y,2=Z...]
[2sa] m2 step angle             1.800 deg
[2tr] m2 travel per revolution   40.0000 mm
[2mi] m2 microsteps               8 [1,2,4,8]
[2po] m2 polarity                 0 [0=normal,1=reverse]
[2pm] m2 power management         2 [0=disabled,1=always on,2=in cycle,3=when moving]
[3ma] m3 map to axis              2 [0=X,1=Y,2=Z...]
[3sa] m3 step angle             1.800 deg
```

[3tr] m3 travel per revolution 1.2500 mm
[3mi] m3 microsteps 4 [1,2,4,8]
[3po] m3 polarity 0 [0=normal,1=reverse]
[3pm] m3 power management 2 [0=disabled,1=always on,2=in cycle,3=when moving]
[4ma] m4 map to axis 2 [0=X,1=Y,2=Z...]
[4sa] m4 step angle 1.800 deg
[4tr] m4 travel per revolution 2.1166 mm
[4mi] m4 microsteps 8 [1,2,4,8]
[4po] m4 polarity 0 [0=normal,1=reverse]
[4pm] m4 power management 2 [0=disabled,1=always on,2=in cycle,3=when moving]
[xam] x axis mode 1 [standard]
[xvm] x velocity maximum 16000 mm/min
[xfr] x feedrate maximum 16000 mm/min
[xtn] x travel minimum 0.000 mm
[xtm] x travel maximum 220.000 mm
[xjm] x jerk maximum 5000 mm/min^3 * 1 million
[xjh] x jerk homing 10000 mm/min^3 * 1 million
[xjd] x junction deviation 0.0100 mm (larger is faster)
[xsn] x switch min 1 [0=off,1=homing,2=limit,3=limit+homing]
[xsx] x switch max 0 [0=off,1=homing,2=limit,3=limit+homing]
[xsv] x search velocity 3000 mm/min
[xlv] x latch velocity 100 mm/min
[xlb] x latch backoff 20.000 mm
[xzb] x zero backoff 3.000 mm
[yam] y axis mode 1 [standard]
[yvm] y velocity maximum 16000 mm/min
[yfr] y feedrate maximum 16000 mm/min
[ytn] y travel minimum 0.000 mm
[ytm] y travel maximum 220.000 mm
[yjm] y jerk maximum 5000 mm/min^3 * 1 million
[yjh] y jerk homing 10000 mm/min^3 * 1 million
[yjd] y junction deviation 0.0100 mm (larger is faster)
[ysn] y switch min 1 [0=off,1=homing,2=limit,3=limit+homing]
[ysx] y switch max 0 [0=off,1=homing,2=limit,3=limit+homing]
[ysv] y search velocity 3000 mm/min
[ylv] y latch velocity 100 mm/min
[ylb] y latch backoff 20.000 mm
[yzb] y zero backoff 3.000 mm
[zam] z axis mode 1 [standard]
[zvm] z velocity maximum 800 mm/min
[zfr] z feedrate maximum 800 mm/min
[ztn] z travel minimum 0.000 mm
[ztm] z travel maximum 100.000 mm

[zjm] z jerk maximum 50 mm/min^3 * 1 million
[zjh] z jerk homing 1000 mm/min^3 * 1 million
[zjd] z junction deviation 0.0100 mm (larger is faster)
[zsn] z switch min 0 [0=off,1=homing,2=limit,3=limit+homing]
[zsx] z switch max 1 [0=off,1=homing,2=limit,3=limit+homing]
[zsv] z search velocity 3000 mm/min
[zlv] z latch velocity 100 mm/min
[zlb] z latch backoff 10.000 mm
[zzb] z zero backoff 3.000 mm
[aam] a axis mode 3 [radius]
[avm] a velocity maximum 25920 deg/min
[afr] a feedrate maximum 12960 deg/min
[atn] a travel minimum -1.000 deg
[atm] a travel maximum -1.000 deg
[ajm] a jerk maximum 324000 deg/min^3 * 1 million
[ajh] a jerk homing 324000 deg/min^3 * 1 million
[ajd] a junction deviation 0.1000 deg (larger is faster)
[ara] a radius value 5.3052 deg
[asn] a switch min 1 [0=off,1=homing,2=limit,3=limit+homing]
[asx] a switch max 0 [0=off,1=homing,2=limit,3=limit+homing]
[asv] a search velocity 2000 deg/min
[alv] a latch velocity 2000 deg/min
[alb] a latch backoff 5.000 deg
[azb] a zero backoff 2.000 deg
[bam] b axis mode 0 [disabled]
[bvm] b velocity maximum 3600 deg/min
[bfr] b feedrate maximum 3600 deg/min
[btn] b travel minimum -1.000 deg
[btm] b travel maximum -1.000 deg
[bjm] b jerk maximum 20 deg/min^3 * 1 million
[bjd] b junction deviation 0.0100 deg (larger is faster)
[bra] b radius value 1.0000 deg
[cam] c axis mode 0 [disabled]
[cvm] c velocity maximum 3600 deg/min
[cfr] c feedrate maximum 3600 deg/min
[ctn] c travel minimum -1.000 deg
[ctm] c travel maximum -1.000 deg
[cjm] c jerk maximum 20 deg/min^3 * 1 million
[cjd] c junction deviation 0.0100 deg (larger is faster)
[cra] c radius value 1.0000 deg
[p1frq] pwm frequency 5000 Hz
[p1csl] pwm cw speed lo 0 RPM
[p1csh] pwm cw speed hi 10000 RPM

[p1cpl] pwm cw phase lo 0.000 [0..1]
[p1cph] pwm cw phase hi 1.000 [0..1]
[p1wsl] pwm ccw speed lo 1000 RPM
[p1wsh] pwm ccw speed hi 2000 RPM
[p1wpl] pwm ccw phase lo 0.125 [0..1]
[p1wph] pwm ccw phase hi 0.200 [0..1]
[p1pof] pwm phase off 0.000 [0..1]
[g54x] g54 x offset 0.000 mm
[g54y] g54 y offset 0.000 mm
[g54z] g54 z offset 0.000 mm
[g54a] g54 a offset 0.000 deg
[g54b] g54 b offset 0.000 deg
[g54c] g54 c offset 0.000 deg
[g55x] g55 x offset 145.000 mm
[g55y] g55 y offset 160.000 mm
[g55z] g55 z offset 0.000 mm
[g55a] g55 a offset 0.000 deg
[g55b] g55 b offset 0.000 deg
[g55c] g55 c offset 0.000 deg
[g56x] g56 x offset 0.000 mm
[g56y] g56 y offset 0.000 mm
[g56z] g56 z offset 0.000 mm
[g56a] g56 a offset 0.000 deg
[g56b] g56 b offset 0.000 deg
[g56c] g56 c offset 0.000 deg
[g57x] g57 x offset 0.000 mm
[g57y] g57 y offset 0.000 mm
[g57z] g57 z offset 0.000 mm
[g57a] g57 a offset 0.000 deg
[g57b] g57 b offset 0.000 deg
[g57c] g57 c offset 0.000 deg
[g58x] g58 x offset 0.000 mm
[g58y] g58 y offset 0.000 mm
[g58z] g58 z offset 0.000 mm
[g58a] g58 a offset 0.000 deg
[g58b] g58 b offset 0.000 deg
[g58c] g58 c offset 0.000 deg
[g59x] g59 x offset 0.000 mm
[g59y] g59 y offset 0.000 mm
[g59z] g59 z offset 0.000 mm
[g59a] g59 a offset 0.000 deg
[g59b] g59 b offset 0.000 deg
[g59c] g59 c offset 0.000 deg

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[g92x] g92 x offset              0.000 mm
[g92y] g92 y offset              0.000 mm
[g92z] g92 z offset              0.000 mm
[g92a] g92 a offset              0.000 deg
[g92b] g92 b offset              0.000 deg
[g92c] g92 c offset              0.000 deg
[g28x] g28 x position            0.000 mm
[g28y] g28 y position            0.000 mm
[g28z] g28 z position            0.000 mm
[g28a] g28 a position            0.000 deg
[g28b] g28 b position            0.000 deg
[g28c] g28 c position            0.000 deg
[g30x] g30 x position            0.000 mm
[g30y] g30 y position            0.000 mm
[g30z] g30 z position            0.000 mm
[g30a] g30 a position            0.000 deg
[g30b] g30 b position            0.000 deg
[g30c] g30 c position            0.000 deg
tinyg [mm] ok>
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```
[fb]  firmware build            440.20
[fv]  firmware version            0.97
[hp]  hardware platform           1.00
[hv]  hardware version            8.00
[id]  TinyG ID                  3X3566-HJV
[ja]  junction acceleration 2000000 mm
[ct]  chordal tolerance           0.0100 mm
[sl]  soft limit enable           0
[st]  switch type                 1 [0=NO,1=NC]
[mt]  motor idle timeout          2.00 Sec
[ej]  enable json mode            0 [0=text,1=JSON]
[jv]  json verbosity              4 [0=silent,1=footer,2=messages,3=configs,4=linenum,5=verbose]
[js]  json serialize style        1 [0=relaxed,1=strict]
[tv]  text verbosity              1 [0=silent,1=verbose]
[qv]  queue report verbosity      1 [0=off,1=single,2=triple]
[sv]  status report verbosity     1 [0=off,1=filtered,2=verbose]
[si]  status interval           250 ms
```

[ec] expand LF to CRLF on TX   0 [0=off,1=on]
[ee] enable echo   0 [0=off,1=on]
[ex] enable flow control   1 [0=off,1=XON/XOFF, 2=RTS/CTS]
[baud] USB baud rate   5 [1=9600,2=19200,3=38400,4=57600,5=115200,6=230400]
[net] network mode   0 [0=master]
[gpl] default gcode plane   0 [0=G17,1=G18,2=G19]
[gun] default gcode units mode   1 [0=G20,1=G21]
[gco] default gcode coord system 1 [1-6 (G54-G59)]
[gpa] default gcode path control 2 [0=G61,1=G61.1,2=G64]
[gdi] default gcode distance mode 0 [0=G90,1=G91]
[1ma] m1 map to axis   0 [0=X,1=Y,2=Z...]
[1sa] m1 step angle   1.800 deg
[1tr] m1 travel per revolution   40.0000 mm
[1mi] m1 microsteps   8 [1,2,4,8]
[1po] m1 polarity   0 [0=normal,1=reverse]
[1pm] m1 power management   2 [0=disabled,1=always on,2=in cycle,3=when moving]
[2ma] m2 map to axis   1 [0=X,1=Y,2=Z...]
[2sa] m2 step angle   1.800 deg
[2tr] m2 travel per revolution   40.0000 mm
[2mi] m2 microsteps   8 [1,2,4,8]
[2po] m2 polarity   0 [0=normal,1=reverse]
[2pm] m2 power management   0 [0=disabled,1=always on,2=in cycle,3=when moving]
[3ma] m3 map to axis   2 [0=X,1=Y,2=Z...]
[3sa] m3 step angle   1.800 deg
[3tr] m3 travel per revolution   1.2500 mm
[3mi] m3 microsteps   4 [1,2,4,8]
[3po] m3 polarity   0 [0=normal,1=reverse]
[3pm] m3 power management   0 [0=disabled,1=always on,2=in cycle,3=when moving]
[4ma] m4 map to axis   3 [0=X,1=Y,2=Z...]
[4sa] m4 step angle   1.800 deg
[4tr] m4 travel per revolution   360.0000 mm
[4mi] m4 microsteps   8 [1,2,4,8]
[4po] m4 polarity   0 [0=normal,1=reverse]
[4pm] m4 power management   0 [0=disabled,1=always on,2=in cycle,3=when moving]
[xam] x axis mode   1 [standard]
[xvm] x velocity maximum   16000 mm/min
[xfr] x feedrate maximum   16000 mm/min
[xtn] x travel minimum   0.000 mm
[xtm] x travel maximum   290.000 mm
[xjm] x jerk maximum   5000 mm/min^3 * 1 million
[xjh] x jerk homing   10000 mm/min^3 * 1 million
[xjd] x junction deviation   0.0100 mm (larger is faster)
[xsn] x switch min   0 [0=off,1=homing,2=limit,3=limit+homing]

[xsx] x switch max 0 [0=off,1=homing,2=limit,3=limit+homing]
[xsv] x search velocity 3000 mm/min
[xlv] x latch velocity 100 mm/min
[xlb] x latch backoff 10.000 mm
[xzb] x zero backoff 2.000 mm
[yam] y axis mode 1 [standard]
[yvm] y velocity maximum 16000 mm/min
[yfr] y feedrate maximum 16000 mm/min
[ytn] y travel minimum 0.000 mm
[ytm] y travel maximum 320.000 mm
[yjm] y jerk maximum 5000 mm/min^3 * 1 million
[yjh] y jerk homing 10000 mm/min^3 * 1 million
[yjd] y junction deviation 0.0100 mm (larger is faster)
[ysn] y switch min 0 [0=off,1=homing,2=limit,3=limit+homing]
[ysx] y switch max 0 [0=off,1=homing,2=limit,3=limit+homing]
[ysv] y search velocity 3000 mm/min
[ylv] y latch velocity 100 mm/min
[ylb] y latch backoff 10.000 mm
[yzb] y zero backoff 2.000 mm
[zam] z axis mode 1 [standard]
[zvm] z velocity maximum 1000 mm/min
[zfr] z feedrate maximum 1000 mm/min
[ztn] z travel minimum -120.000 mm
[ztm] z travel maximum 0.000 mm
[zjm] z jerk maximum 20 mm/min^3 * 1 million
[zjh] z jerk homing 1000 mm/min^3 * 1 million
[zjd] z junction deviation 0.0100 mm (larger is faster)
[zsn] z switch min 0 [0=off,1=homing,2=limit,3=limit+homing]
[zsx] z switch max 0 [0=off,1=homing,2=limit,3=limit+homing]
[zsv] z search velocity 1000 mm/min
[zlv] z latch velocity 100 mm/min
[zlb] z latch backoff 10.000 mm
[zzb] z zero backoff 3.000 mm
[aam] a axis mode 3 [radius]
[avm] a velocity maximum 25920 deg/min
[afr] a feedrate maximum 12960 deg/min
[atn] a travel minimum -1.000 deg
[atm] a travel maximum -1.000 deg
[ajm] a jerk maximum 324000 deg/min^3 * 1 million
[ajh] a jerk homing 324000 deg/min^3 * 1 million
[ajd] a junction deviation 0.1000 deg (larger is faster)
[ara] a radius value 5.3052 deg
[asn] a switch min 0 [0=off,1=homing,2=limit,3=limit+homing]

[asx] a switch max 0 [0=off,1=homing,2=limit,3=limit+homing]
[asv] a search velocity 2000 deg/min
[alv] a latch velocity 2000 deg/min
[alb] a latch backoff 5.000 deg
[azb] a zero backoff 2.000 deg
[bam] b axis mode 0 [disabled]
[bvm] b velocity maximum 3600 deg/min
[bfr] b feedrate maximum 3600 deg/min
[btn] b travel minimum -1.000 deg
[btm] b travel maximum -1.000 deg
[bjm] b jerk maximum 20 deg/min^3 * 1 million
[bjd] b junction deviation 0.0100 deg (larger is faster)
[bra] b radius value 1.0000 deg
[cam] c axis mode 0 [disabled]
[cvm] c velocity maximum 3600 deg/min
[cfr] c feedrate maximum 3600 deg/min
[ctn] c travel minimum -1.000 deg
[ctm] c travel maximum -1.000 deg
[cjm] c jerk maximum 20 deg/min^3 * 1 million
[cjd] c junction deviation 0.0100 deg (larger is faster)
[cra] c radius value 1.0000 deg
[p1frq] pwm frequency 5000 Hz
[p1csl] pwm cw speed lo 1000 RPM
[p1csh] pwm cw speed hi 10000 RPM
[p1cpl] pwm cw phase lo 0.125 [0..1]
[p1cph] pwm cw phase hi 0.200 [0..1]
[p1wsl] pwm ccw speed lo 1000 RPM
[p1wsh] pwm ccw speed hi 2000 RPM
[p1wpl] pwm ccw phase lo 0.125 [0..1]
[p1wph] pwm ccw phase hi 0.200 [0..1]
[p1pof] pwm phase off 0.000 [0..1]
[g54x] g54 x offset 0.000 mm
[g54y] g54 y offset 0.000 mm
[g54z] g54 z offset 0.000 mm
[g54a] g54 a offset 0.000 deg
[g54b] g54 b offset 0.000 deg
[g54c] g54 c offset 0.000 deg
[g55x] g55 x offset 145.000 mm
[g55y] g55 y offset 160.000 mm
[g55z] g55 z offset 0.000 mm
[g55a] g55 a offset 0.000 deg
[g55b] g55 b offset 0.000 deg
[g55c] g55 c offset 0.000 deg

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[g56x] g56 x offset          0.000 mm
[g56y] g56 y offset          0.000 mm
[g56z] g56 z offset          0.000 mm
[g56a] g56 a offset          0.000 deg
[g56b] g56 b offset          0.000 deg
[g56c] g56 c offset          0.000 deg
[g57x] g57 x offset          0.000 mm
[g57y] g57 y offset          0.000 mm
[g57z] g57 z offset          0.000 mm
[g57a] g57 a offset          0.000 deg
[g57b] g57 b offset          0.000 deg
[g57c] g57 c offset          0.000 deg
[g58x] g58 x offset          0.000 mm
[g58y] g58 y offset          0.000 mm
[g58z] g58 z offset          0.000 mm
[g58a] g58 a offset          0.000 deg
[g58b] g58 b offset          0.000 deg
[g58c] g58 c offset          0.000 deg
[g59x] g59 x offset          0.000 mm
[g59y] g59 y offset          0.000 mm
[g59z] g59 z offset          0.000 mm
[g59a] g59 a offset          0.000 deg
[g59b] g59 b offset          0.000 deg
[g59c] g59 c offset          0.000 deg
[g92x] g92 x offset          0.000 mm
[g92y] g92 y offset          0.000 mm
[g92z] g92 z offset          0.000 mm
[g92a] g92 a offset          0.000 deg
[g92b] g92 b offset          0.000 deg
[g92c] g92 c offset          0.000 deg
[g28x] g28 x position        0.000 mm
[g28y] g28 y position        0.000 mm
[g28z] g28 z position        0.000 mm
[g28a] g28 a position        0.000 deg
[g28b] g28 b position        0.000 deg
[g28c] g28 c position        0.000 deg
[g30x] g30 x position        0.000 mm
[g30y] g30 y position        0.000 mm
[g30z] g30 z position        0.000 mm
[g30a] g30 a position        0.000 deg
[g30b] g30 b position        0.000 deg
[g30c] g30 c position        0.000 deg
tinyg [mm] ok>
```