```
#MPG Pendant
loadrt mux4 count=1
addf mux4.0 servo-thread

# For velocity mode, set to 1
# In velocity mode the axis stops when the dial is stopped
# even if that means the commanded motion is not completed,
# For position mode (the default), set to 0
# In position mode the axis will move exactly jog-scale
# units for each count, regardless of how long that might take,
setp axis.0.jog-vel-mode 1
setp axis.1.jog-vel-mode 1
setp axis.2.jog-vel-mode 1

# The output from the mux4 is sent to each axis jog scale
net encoder-counts  <= hm2_5i25.0.encoder.03.count
net encoder-counts => axis.0.jog-counts
net encoder-counts => axis.1.jog-counts
net encoder-counts => axis.2.jog-counts
#setp axis.0.jog-enable TRUE
#setp axis.0.jog-scale 0.001

# The inputs to the mux4 component
net scale1 mux4.0.sel0 <= parport.0.pin-13-in-not
net scale2 mux4.0.sel1 <= parport.0.pin-15-in-not
net scaleout  mux4.0.out => axis.0.jog-scale
net scaleout => axis.2.jog-scale

# This sets the scale that will be used based on the input to the mux4
setp mux4.0.in0 0
setp mux4.0.in1 0.00025
setp mux4.0.in2 0.0025
setp mux4.0.in3 0.025

# The Axis select inputs
net mpg-x axis.0.jog-enable <= hm2_5i25.0.gpio.031.in
net mpg-z axis.2.jog-enable <= hm2_5i25.0.gpio.033.in
```