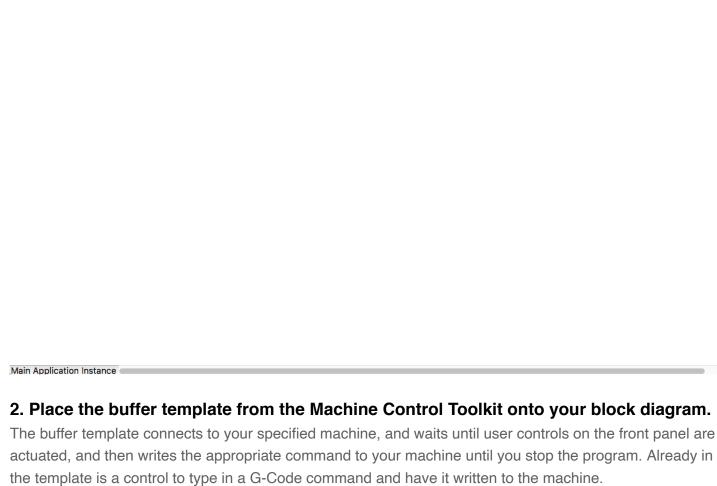
Getting Started

(step-by-step instructions below). 1. Open up a blank LabVIEW VI

Getting Started VI.vi Block Diagram *

Get started with the Machine Control Toolkit by building a simple machine interface

💠 👰 🧻 🔢 💡 🐫 🖶 🖶 🚅 12pt Dialog Font

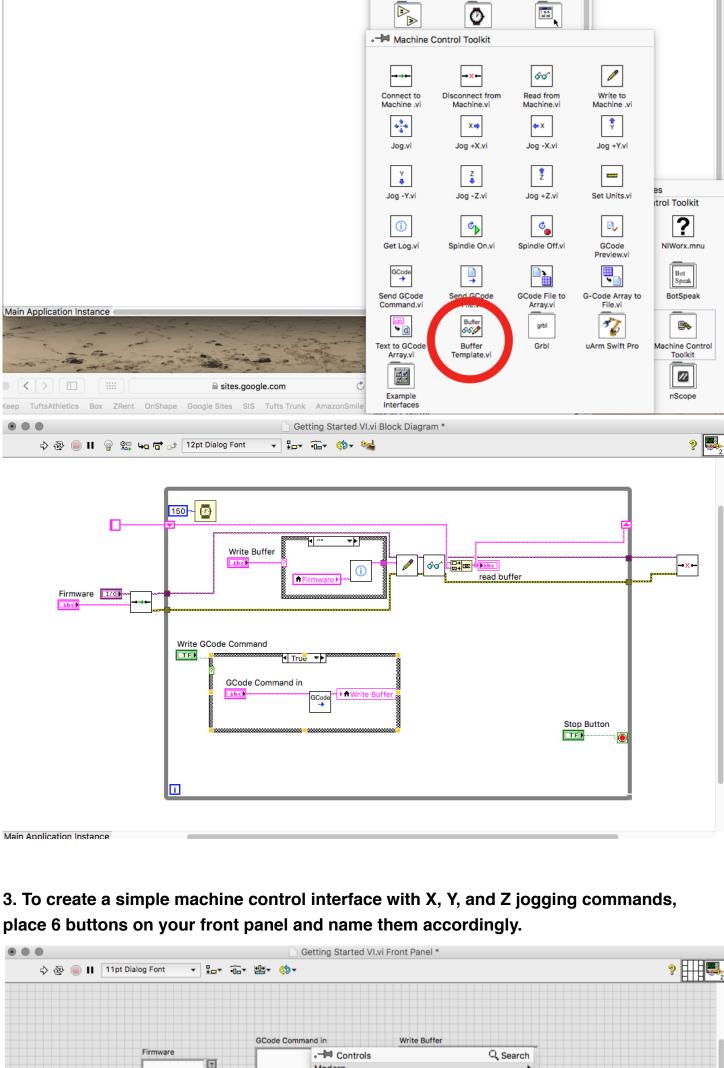


Getting Started VI. R 12 e 3 4 ? 💠 🚱 🦲 Ⅱ 💡 🕵 👆 📅 🚅 12pt Dialog Font Cluster, Class, & Variant abc a A Boolean String

Functions

Programming

Q Search



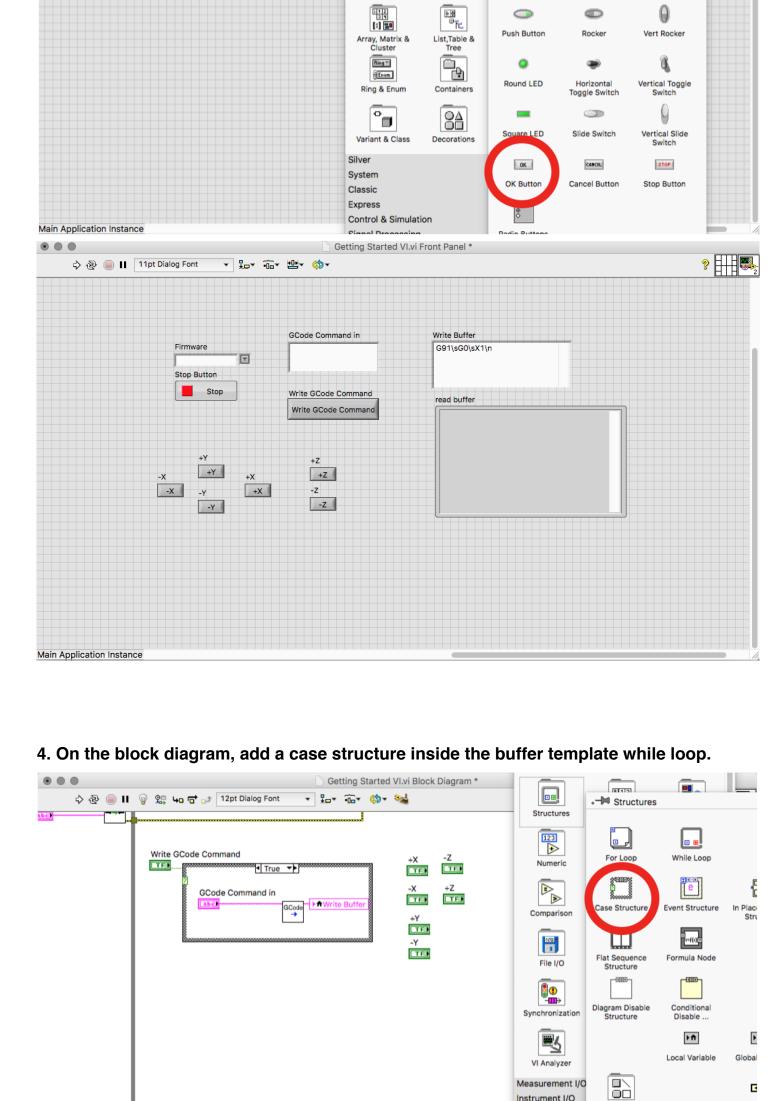
1.23

Write GCode Co

Write GCode C

₿o

Stop



abc

.−I≡ Boolean

Instrument I/O

Vision and Motion Mathematics Signal Processing **Data Communication**

Control & Simulation

Cluster, Class, & Variant

obc a A

String

ф Х

Jog -X.vi

† Z

Jog +Z.vi

ot_

Spindle Off.vi

GCode File to Array.vi

Write to Machine .vi

Ŷ

Jog +Y.vi

listatus.

Set Units.vi

• GCode Preview.vi

G-Code Array to File.vi

trol Toolkit ?

NIWorx.mnu

Bot Speak

BotSpeak

B 12 0 3 4

Array

Boolean

Jog +X.vi

Z .

Jog -Z.vi

७▶

Spindle On.vi

1

Send GCode File.vi

Feedba

?

Tank and and **O** GCode Command in →■ Machine Control Toolkit 60 →→← [®]◀ True ▼▶

5. Connect the case selector to the +X control button. From the Machine Control Toolkit,

Structures

123

Numeric

Jog.vi

Y

Jog -Y.vi

1

Get Log.vi

GCode →

Send GCode Command.vi

6. Create a control for the jogging step size so you can adjust it from the front panel.

String Out to the Write Buffer also using a local variable.

Write GCode Command

+Z

8. Add control over the machine's units.

Main Application Instance

Wire the firmware into the firmware input using a local variable, and connect the G-Code

Main Application Instance

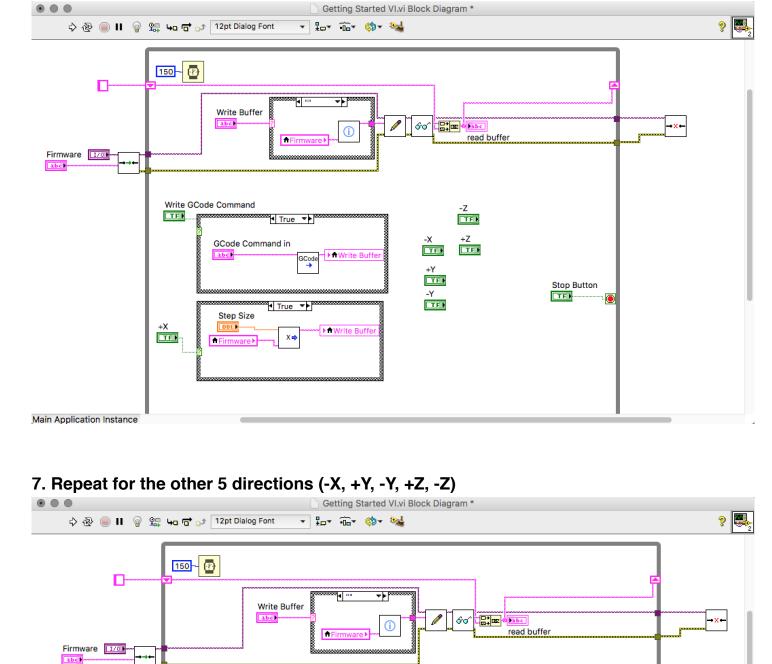
add the Jog +X VI inside the case structure.

💠 🔡 🥚 Ⅱ 💡 🔐 👆 🗗 🗗 12pt Dialog Font

+X

Main Application Instance

Write GCode Command



+X ⁸ True ▼▶ ⁴ True ▼▶ TF)... TF.

-Z

¹4 True ▼▶

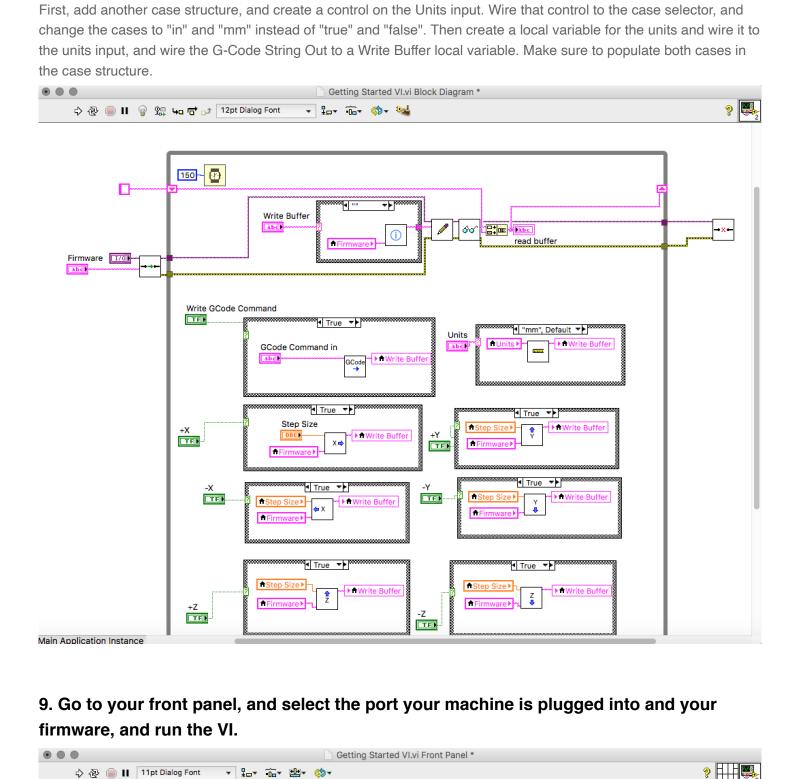
True ▼▶

"◀ True ▼▶

1 Z

GCode →

GCode Command in



Grbl Stop read buffer Write GCode Command

Step Size

GCode Command in

Write Buffer G91\sG0\sX1\n

^I⁄₀ COM3

+Y

Main Application Instance

and units!

10. You will now be able to jog your machine in all directions, and control the step size