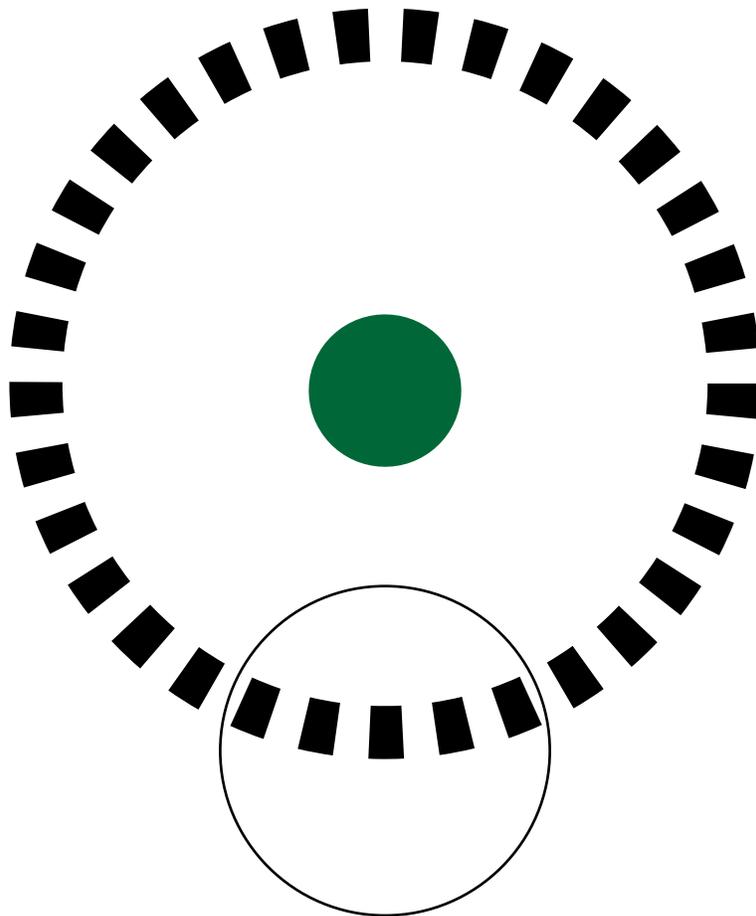


MYO CIRCUIT BOARDS

INDEX BY MYOSTAT MOTION CONTROL INC.

CREATING INNOVATION WITH MOTION CONTROL



MYO CIRCUIT BOARDS INDEX

CM1

MYO19 - 24 - EIP

SRL module used for the CM1 motors. It can be used as SRLM or SRLS.

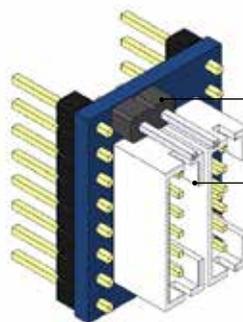


- Ethernet Connector RJ45
- GND
- Supply Voltage

MYO21 DIN RAIL ETHERNET MODULE

MYO21 is an interface which allows the CM1 motor to be run from a 3D printer controller. The MYO21 was designed to interface alongside the Panucatt Azteeg X3 Pro 3D printer controller.

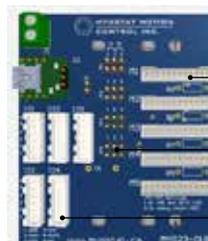
The MYO21 replaces the Panucatt SD8825 stepper driver, allowing the CM1 to be run in step/direction mode directly from the printer controller. The jumper on the MYO21 is used to allow the use of the 'enable' input, or disable if not used. The "Decay" pin and "external Vref" pin from the SD8825 are present but not used. The Fault output follows the same functionality as the SD8825.



- Jump to activate enable
- Mating Cable CM1ORD1-XXXX

MYO 23 USB AXIS NETWORK CARD WITH IO

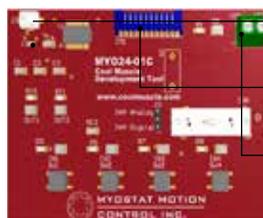
The MYO23 allows you to easily daisy chain multiple CM1 motors while giving you access to the inputs and outputs for each motor, as well as USB communications.



- CM1 Motor Connectors CABLE P/N: CM1SRL1
- Jumper settings
- I/O Connectors

MYO24 MYOSTAT CM1 DEVELOPMENT AND SALES BUTTON

The MYO24 development tool helps users quickly test I/O functionality on the CM1 motors. The MYO24 also provides a USB interface for easy connection to a PC.



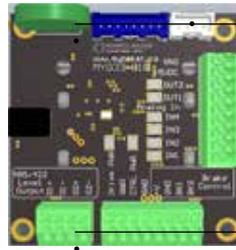
- Micro B USB
- CM1 SRL1 MATING CABLE: CM1 SRL Boardside Connector: S12B-PH-K-S
- Supply Power

CM1-T

MYO33 CM1-T I/O BREAKOUT BOARD

The MYO33 is a breakout board for the CM1-T. This provides convenient terminals with indicator LEDs for each input and output. The MYO33 also features two additional RS485 level output which follow the operation of outputs one and two on the motor.

The MYO33 also features a convenient terminal for a brake to be controlled by the CM1-T. The brake terminal requires a brake power in, and a switched brake power out which follows the operation of output two. The MYO33 may be mounted using either the DIN rail mounting feet on the board, or by using the corner mounting holes.



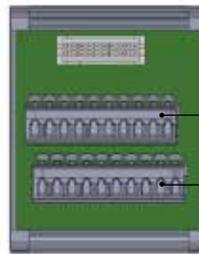
Mating Cables:
MYO23XX-XXXX

Phoenix PTSA 1.5 Push-In Terminals

CM2

MYO17 CM2 IO BREAKOUT BOARD

This board was developed to take a variety of different terminal blocks.



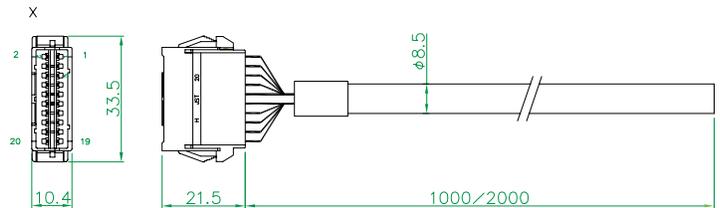
B20B-XADSS-N (JST)
Mating cable: CM2IO2-2000W

10 Position terminal block (WAGO)
Push tab with 28~12 gauge wire

CABLE: CM2IO2-XXXX

CM2, 20 Conductor I/O Cable

xxxx = length in mm



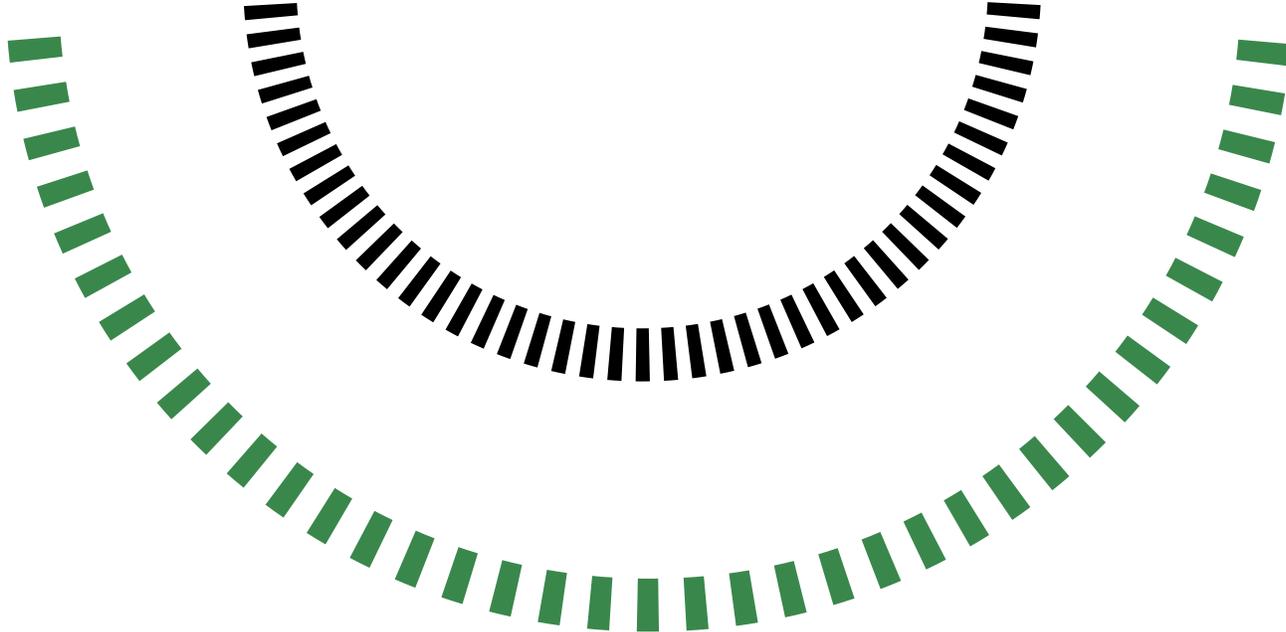
CM1 & CM2

ETHERCAT BRIDGE

The EtherCAT Cool Muscle Bridge is Muscle Corporation, new 4-axis interface for EtherCAT networks. Four CM1, CM2, or CM3 motors can be connected to each bridge allowing for control of the Cool Muscles as an EtherCAT slave from an EtherCAT Master across a high performance network.

The application layer conforms to the CiA402 Drive Profile, with unique operation modes including Cyclic Synchronous Position mode (cpm) and Homing mode (hm). The EtherCAT Master sends position commands to, and receives feedback from the EtherCAT Slave at a communications frequency of 1msec.





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*Specifications subject to change without notice

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Manufactured in Japan by

