

MKS EAGLE User Manual

This document is the basic hardware and firmware description of MKS EAGLE, which is convenient for beginners or users who are not familiar with 3D printing. If your question is deeper, or the documentation doesn't mention it.

*Please don't worry, you can contact us through **Makerbase.store** information or email service@makerbase.store, we will try our best to help you solve the problem.*

This document is divided into 3 parts

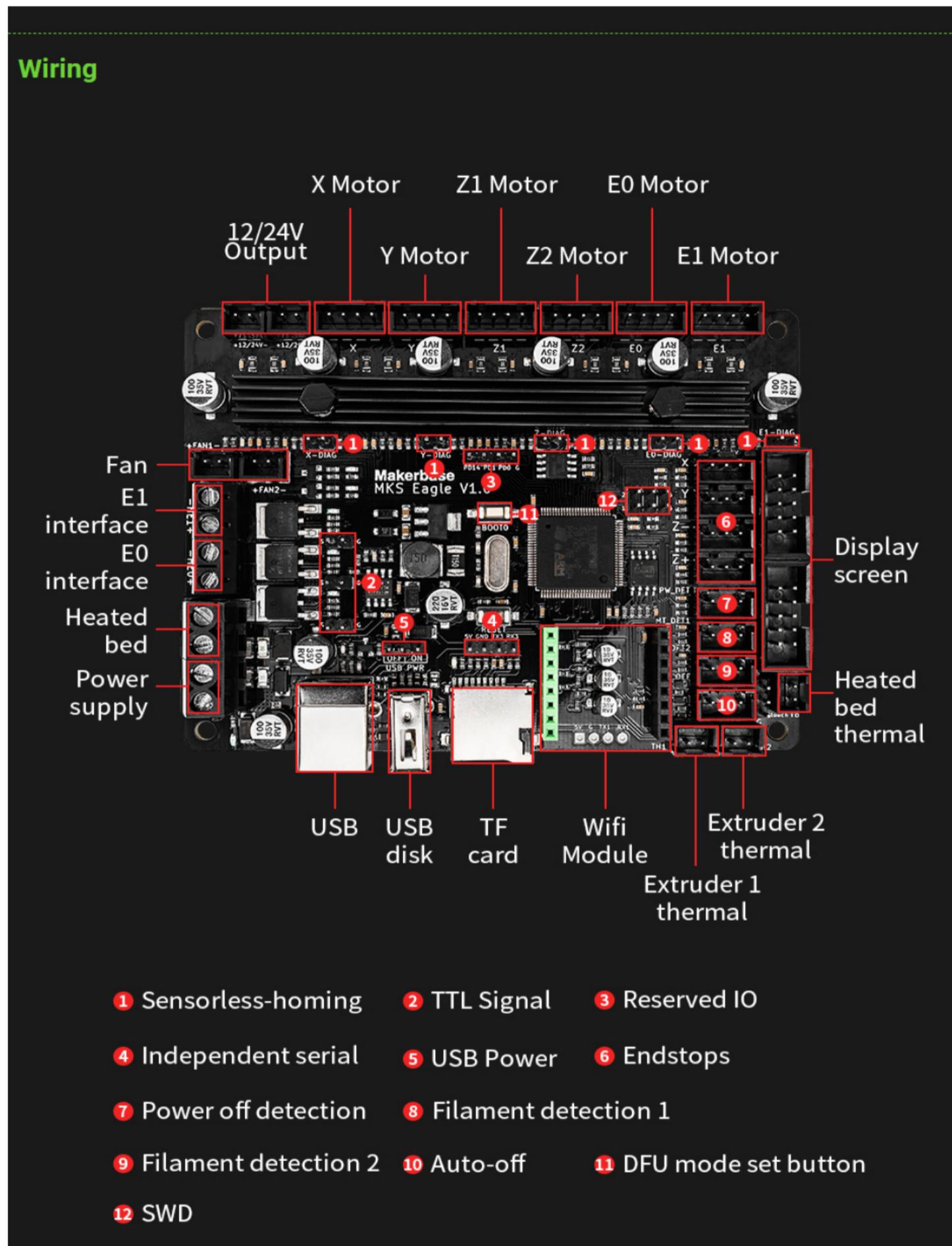
MKS EAGLE Hardware Interface

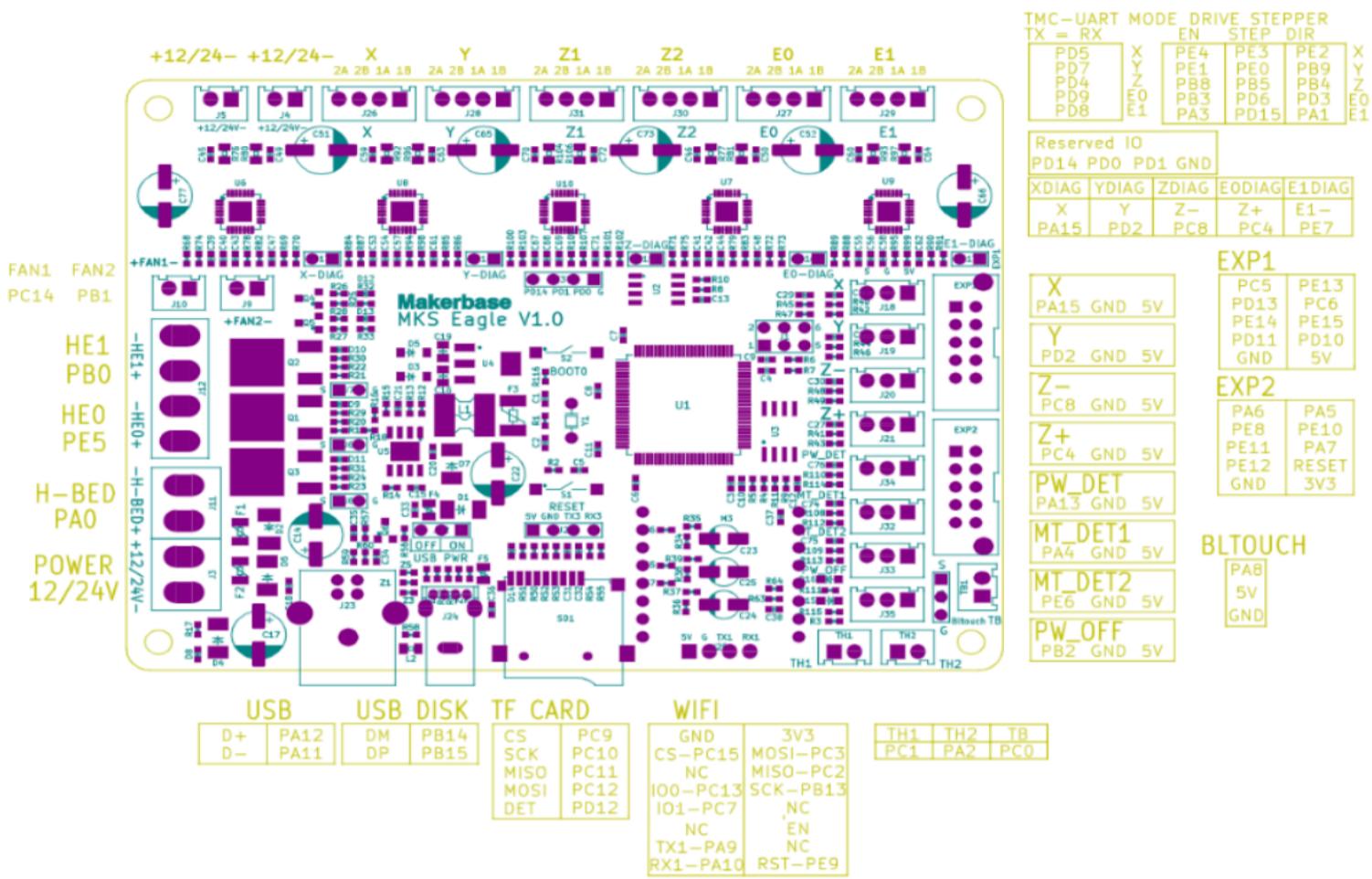
MKS EAGLE Configuration and update of firmware

Q&A of MKS EAGLE

MKS EAGLE Hardware Interface

Wiring :





After you receive the motherboard, first check whether the appearance of the motherboard is complete. Then you can connect according to the interface marked in the picture according to the wiring of your printer.

Note:

1. During the connection process, you need to pay attention to the power supply, hotbed, hotend, fan and other interfaces, all of which have a distinction between "+" and "-", so you must pay attention to the wiring process to prevent the positive and negative connections from being reversed, resulting in damage to the motherboard.
2. By default, the motherboard needs to update the marlin firmware before it can be used normally. Therefore, you can also perform wiring after updating the firmware of your own parameters.
3. Any wiring or adjustment operation, please do it when the power is off.

If you need information such as the schematic diagram of MKS EAGLE, you can download it from this website:

<https://github.com/makerbase-mks/MKS-EAGLE>

MKS EAGLE Configuration and update of firmware

Download Marlin

MKS EAGLE uses Marlin2.0 firmware.

You can go to our MKS github to download:

<https://github.com/makerbase-mks/Mks-Robin-Nano-Marlin2.0-Firmware>

Or download it from the official github of marlin. (recommended marlin2.0.9 and above)

Install Visual Studio Code

Before starting to edit Marlin, we recommend that you install a good code editor - Visual Studio Code. You can even compile Marlin directly from it.

Visual Studio Code can be freely downloaded, after you have edited Marlin and the necessary parameters, you can compile it and upload your new firmware to the printer.

How to install Visual Studio Code and PlatformIO, edit and compile marlin, you can find from :

https://marlinfw.org/docs/basics/install_platformio_vscode.html

Configure and compile

For parameter configuration of MKS EAGLE

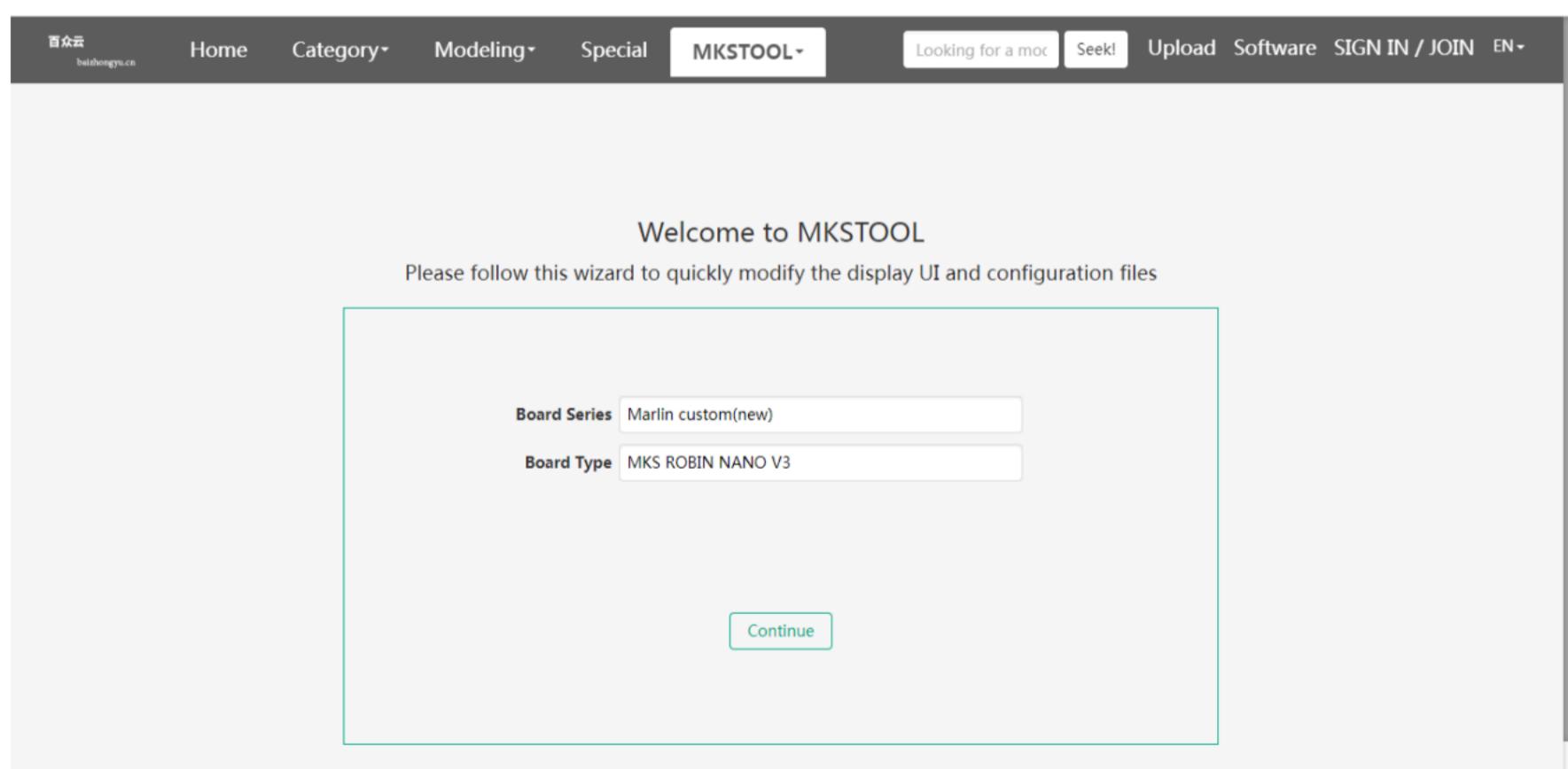
You can refer to [github-wiki](#) for settings:

https://github.com/makerbase-mks/MKS-Robin-Nano-V3.X/wiki/Marlin_firmware

The hardware and interfaces of the MKS EAGLE motherboard are basically the same as those of the MKS ROBIN NANO V3. The firmware settings are basically universal.

For quick configuration, you can use our MKS TOOL for configuration. (MKS TOOL can only perform common parameter configuration, and special function configuration still needs to be modified in vscode)

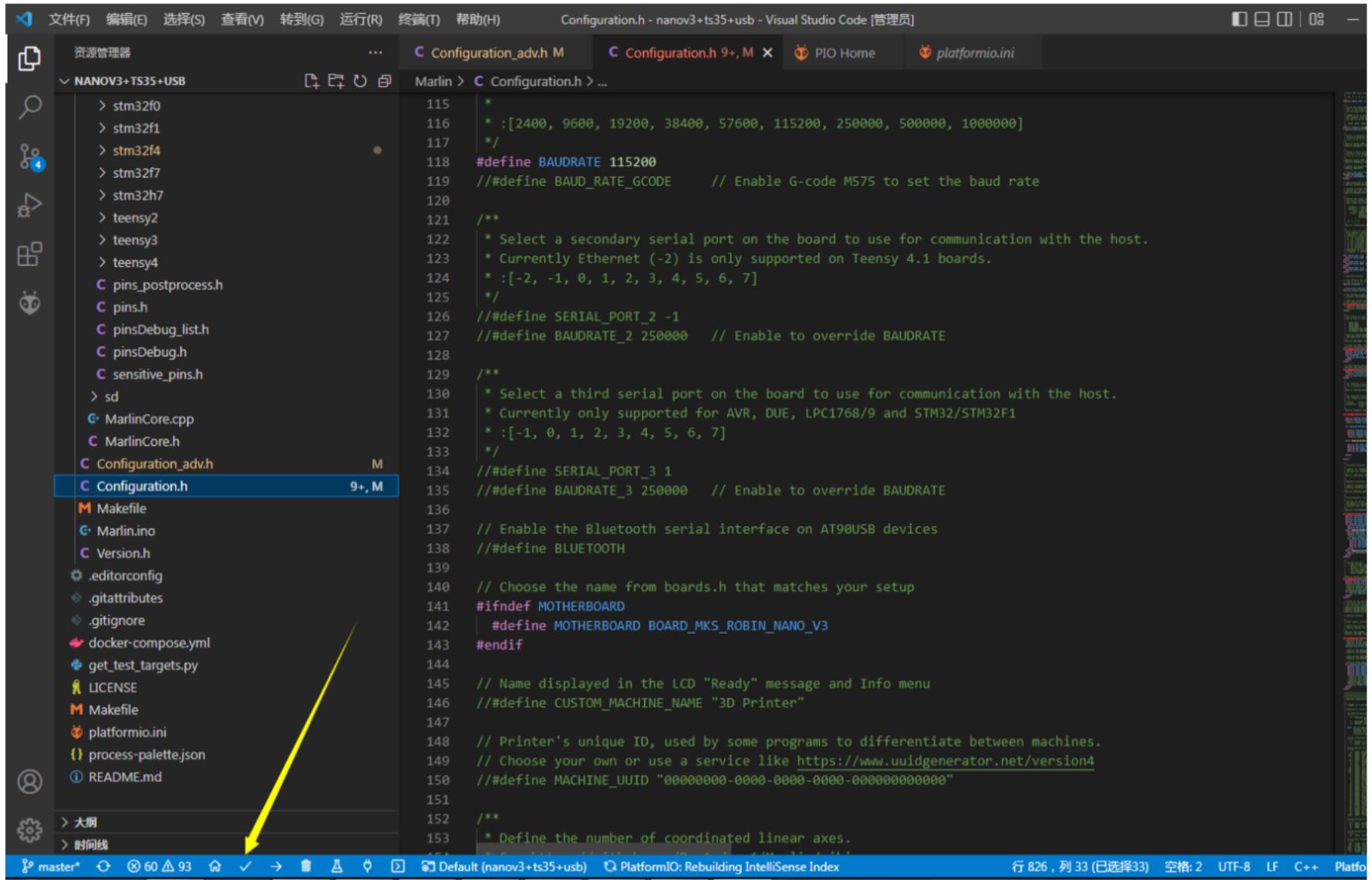
<https://www.baizhongyun.cn/home/mkstoolview>



MKS TOOL tutorial can refer to youtube:

<https://www.youtube.com/watch?v=8-90xcU-tuY>

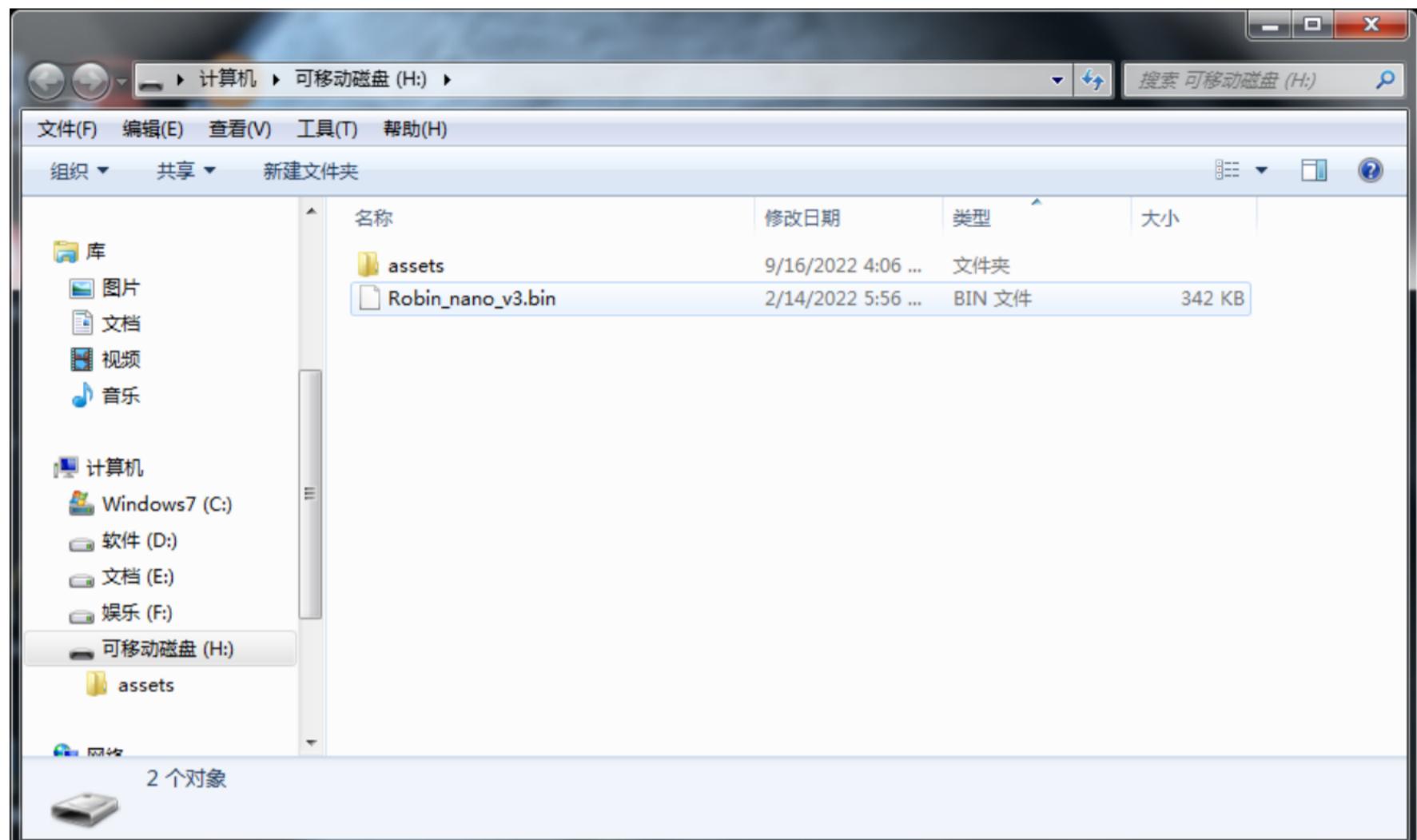
After the parameter modification is completed, it is to compile



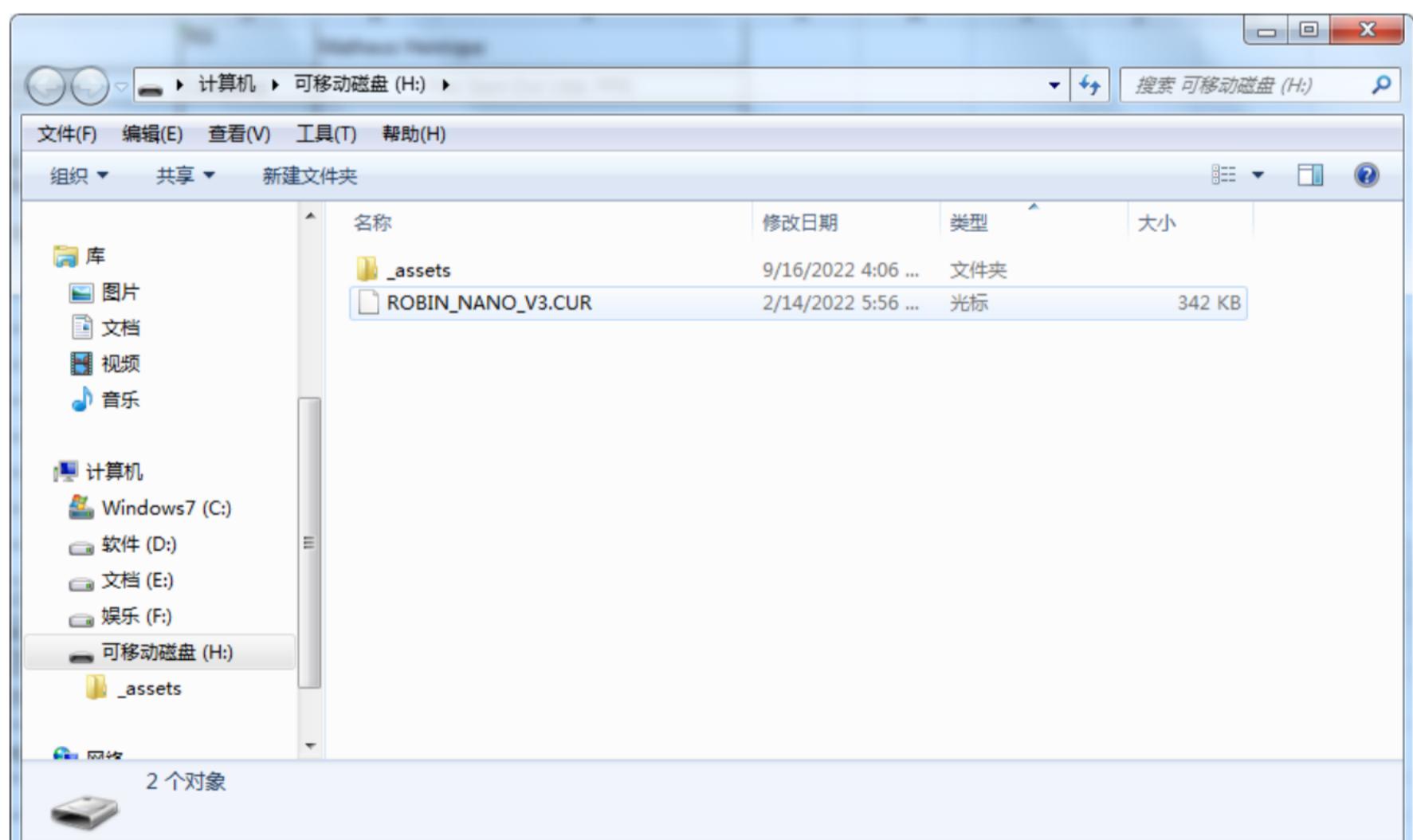
```

115 *:[2400, 9600, 19200, 38400, 57600, 115200, 250000, 500000, 1000000]
116 */
117 #define BAUDRATE 115200 // Enable G-code M575 to set the baud rate
118 //#[define BAUD_RATE_GCODE
119 // Select a secondary serial port on the board to use for communication with the host.
120 // Currently Ethernet (-2) is only supported on Teensy 4.1 boards.
121 //:[-2, -1, 0, 1, 2, 3, 4, 5, 6, 7]
122 //#[define SERIAL_PORT_2 -1
123 //#[define BAUDRATE_2 250000 // Enable to override BAUDRATE
124 // Select a third serial port on the board to use for communication with the host.
125 // Currently only supported for AVR, DUE, LPC1768/9 and STM32/STM32F1
126 //:[-1, 0, 1, 2, 3, 4, 5, 6, 7]
127 //#[define SERIAL_PORT_3 1
128 //#[define BAUDRATE_3 250000 // Enable to override BAUDRATE
129 // Enable the Bluetooth serial interface on AT90USB devices
130 //#[define BLUETOOTH
131 // Choose the name from boards.h that matches your setup
132 //#[ifndef MOTHERBOARD
133 //#[define MOTHERBOARD BOARD_MKS_ROBIN_NANO_V3
134 //#[endif
135 // Name displayed in the LCD "Ready" message and Info menu
136 //#[define CUSTOM_MACHINE_NAME "3D Printer"
137 // Printer's unique ID, used by some programs to differentiate between machines.
138 //#[define MACHINE_UUID "00000000-0000-0000-0000-000000000000"
139 // Define the number of coordinated linear axes.
140 //#[define COORDINATED_AXES 3
141 //#[define LINEAR_AXES 3
142 //#[define XY_AXES 2
143 //#[define Z_AXIS 1
144 //#[define X_AXIS 0
145 //#[define Y_AXIS 1
146 //#[define Z_AXIS 2
147 //#[define XY_AXES 3
148 //#[define COORDINATED_AXES 4
149 //#[define LINEAR_AXES 4
150 //#[define X_AXIS 0
151 //#[define Y_AXIS 1
152 //#[define Z_AXIS 2
153 //#[define XY_AXES 3
154 //#[define COORDINATED_AXES 5
155 //#[define LINEAR_AXES 5
156 //#[define X_AXIS 0
157 //#[define Y_AXIS 1
158 //#[define Z_AXIS 2
159 //#[define XY_AXES 4
160 //#[define COORDINATED_AXES 6
161 //#[define LINEAR_AXES 6
162 //#[define X_AXIS 0
163 //#[define Y_AXIS 1
164 //#[define Z_AXIS 2
165 //#[define XY_AXES 5
166 //#[define COORDINATED_AXES 7
167 //#[define LINEAR_AXES 7
168 //#[define X_AXIS 0
169 //#[define Y_AXIS 1
170 //#[define Z_AXIS 2
171 //#[define XY_AXES 6
172 //#[define COORDINATED_AXES 8
173 //#[define LINEAR_AXES 8
174 //#[define X_AXIS 0
175 //#[define Y_AXIS 1
176 //#[define Z_AXIS 2
177 //#[define XY_AXES 7
178 //#[define COORDINATED_AXES 9
179 //#[define LINEAR_AXES 9
180 //#[define X_AXIS 0
181 //#[define Y_AXIS 1
182 //#[define Z_AXIS 2
183 //#[define XY_AXES 8
184 //#[define COORDINATED_AXES 10
185 //#[define LINEAR_AXES 10
186 //#[define X_AXIS 0
187 //#[define Y_AXIS 1
188 //#[define Z_AXIS 2
189 //#[define XY_AXES 9
190 //#[define COORDINATED_AXES 11
191 //#[define LINEAR_AXES 11
192 //#[define X_AXIS 0
193 //#[define Y_AXIS 1
194 //#[define Z_AXIS 2
195 //#[define XY_AXES 10
196 //#[define COORDINATED_AXES 12
197 //#[define LINEAR_AXES 12
198 //#[define X_AXIS 0
199 //#[define Y_AXIS 1
200 //#[define Z_AXIS 2
201 //#[define XY_AXES 11
202 //#[define COORDINATED_AXES 13
203 //#[define LINEAR_AXES 13
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205 //#[define Y_AXIS 1
206 //#[define Z_AXIS 2
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209 //#[define LINEAR_AXES 14
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211 //#[define Y_AXIS 1
212 //#[define Z_AXIS 2
213 //#[define XY_AXES 13
214 //#[define COORDINATED_AXES 15
215 //#[define LINEAR_AXES 15
216 //#[define X_AXIS 0
217 //#[define Y_AXIS 1
218 //#[define Z_AXIS 2
219 //#[define XY_AXES 14
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221 //#[define LINEAR_AXES 16
222 //#[define X_AXIS 0
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233 //#[define LINEAR_AXES 18
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235 //#[define Y_AXIS 1
236 //#[define Z_AXIS 2
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239 //#[define LINEAR_AXES 19
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260 //#[define Z_AXIS 2
261 //#[define XY_AXES 21
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263 //#[define LINEAR_AXES 23
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265 //#[define Y_AXIS 1
266 //#[define Z_AXIS 2
267 //#[define XY_AXES 22
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269 //#[define LINEAR_AXES 24
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272 //#[define Z_AXIS 2
273 //#[define XY_AXES 23
274 //#[define COORDINATED_AXES 25
275 //#[define LINEAR_AXES 25
276 //#[define X_AXIS 0
277 //#[define Y_AXIS 1
278 //#[define Z_AXIS 2
279 //#[define XY_AXES 24
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290 //#[define Z_AXIS 2
291 //#[define XY_AXES 26
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295 //#[define Y_AXIS 1
296 //#[define Z_AXIS 2
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299 //#[define LINEAR_AXES 29
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300 //#[define Y_AXIS 1
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304 //#[define LINEAR_AXES 30
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306 //#[define Y_AXIS 1
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312 //#[define Y_AXIS 1
313 //#[define Z_AXIS 2
314 //#[define XY_AXES 30
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316 //#[define LINEAR_AXES 32
317 //#[define X_AXIS 0
318 //#[define Y_AXIS 1
319 //#[define Z_AXIS 2
320 //#[define XY_AXES 31
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322 //#[define LINEAR_AXES 33
323 //#[define X_AXIS 0
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328 //#[define LINEAR_AXES 34
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378 //#[define Y_AXIS 1
379 //#[define Z_AXIS 2
380 //#[define XY_AXES 41
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384 //#[define Y_AXIS 1
385 //#[define Z_AXIS 2
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514 //#[define LINEAR_AXES 65
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520 //#[define LINEAR_AXES 66
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643 //#[define Z_AXIS 2
644 //#[define XY_AXES 85
645 //#[define COORDINATED_AXES 87
646 //#[define LINEAR_AXES 87
647 //#[define X_AXIS 0
648 //#[define Y_AXIS 1
649 //#[define Z_AXIS 2
650 //#[define XY_AXES 86
651 //#[define COORDINATED_AXES 88
652 //#[define LINEAR_AXES 88
653 //#[define X_AXIS 0
654 //#[define Y_AXIS 1
655 //#[define Z_AXIS 2
656 //#[define XY_AXES 87
657 //#[define COORDINATED_AXES 89
658 //#[define LINEAR_AXES 89
659 //#[define X_AXIS 0
660 //#[define Y_AXIS 1
661 //#[define Z_AXIS 2
662 //#[define XY_AXES 88
663 //#[define COORDINATED_AXES 90
664 //#[define LINEAR_AXES 89
665 //#[define X_AXIS 0
666 //#[define Y_AXIS 1
667 //#[define Z_AXIS 2
668 //#[define XY_AXES 89
669 //#[define COORDINATED_AXES 91
670 //#[define LINEAR_AXES 90
671 //#[define X_AXIS 0
672 //#[define Y_AXIS 1
673 //#[define Z_AXIS 2
674 //#[define XY_AXES 90
675 //#[define COORDINATED_AXES 92
676 //#[define LINEAR_AXES 91
677 //#[define X_AXIS 0
678 //#[define Y_AXIS 1
679 //#[define Z_AXIS 2
680 //#[define XY_AXES 91
681 //#[define COORDINATED_AXES 93
682 //#[define LINEAR_AXES 92
683 //#[define X_AXIS 0
684 //#[define Y_AXIS 1
685 //#[define Z_AXIS 2
686 //#[define XY_AXES 92
687 //#[define COORDINATED_AXES 94
688 //#[define LINEAR_AXES 93
689 //#[define X_AXIS 0
690 //#[define Y_AXIS 1
691 //#[define Z_AXIS 2
692 //#[define XY_AXES 93
693 //#[define COORDINATED_AXES 95
694 //#[define LINEAR_AXES 94
695 //#[define X_AXIS 0
696 //#[define Y_AXIS 1
697 //#[define Z_AXIS 2
```

The directory of the sd card before the update, Rename the robin-nano v3.bin file to mks eagle.bin



The directory of the sd card after the update completed, mks eagle.bin become the mks eagle.cur



Q&A of MKS EAGLE

Q1: Why does the TS35 display a white screen after powering on?

A1: The reason why the TS35 displays a white screen may be that the firmware update is incorrect, or the screen is not enabled in the firmware. Check the firmware settings, then recompile and upload the firmware.

Q2: Why didn't the file format change after updating the bin file and asset folder of the firmware? (update unsuccessful)

A2 : Replace the sd card or reformat the sd card. Update again. (The format required by the SD card is fat32)

Q3: Why is connecting usb cable to pc not recognized

A3:Check the jumper cap setting in front of the usb interface. It needs to be set to yes, and the usb interface will supply power to the motherboard. If you select "no", the motherboard needs to be connected to 12-24v for power supply.

Q4: Why after connecting the motor, the motor can only have noise and vibration, but does not rotate?

A4:1.In this case, the phase wiring of the motor may be incorrect, you can try to adjust the order of the motor wires .

2.The MKS EAGLE motherboard integrates the tmc2209 driver. The driver type you set in the marlin firmware must be TMC2209. If the driver signal you set does not match the actual one, tmc err may occur and the motor cannot be controlled normally.

Q5: what if my question is not covered in this one?

A5:You can contact us directly through makerbase.store.

Or send questions to our email, or leave a message on our github

Email: service@makerbase.store

Github : <https://github.com/makerbase-mks>