MARLIN ADJUSTMENTS:

Platform.ini

Marlin 🡪 Src 🡪 Pins

* #include "stm32h7/pins\_BTT\_SKR\_SE\_BX\_V1\_0.h" // STM32H7 env:BTT\_SKR\_SE\_BX env:BTT\_SKR\_SE\_BX\_BOOT

Marlin/src/pins/stm32h7/pins\_BTT\_SKR\_SE\_BX\_V1\_0.h

Configuration.h

* #define STRING\_CONFIG\_H\_AUTHOR "(Luke Harrison, BIQU BX)" // Who made the changes.
* #define HEATER\_0\_MAXTEMP 275
* #define BED\_MAXTEMP 110
* #define PID\_EDIT\_MENU
* #define PID\_AUTOTUNE\_MENU
* //#define ENDSTOP\_NOISE\_THRESHOLD 2
* #define DEFAULT\_AXIS\_STEPS\_PER\_UNIT { 80\*2, 80\*2, 400\*2, 910 }
* #define DEFAULT\_MAX\_FEEDRATE { 200, 200, 10, 65 }
* #define DEFAULT\_ACCELERATION 1000 // X, Y, Z and E acceleration for
* #define DEFAULT\_RETRACT\_ACCELERATION 1000 // E acceleration for retracts
* #define DEFAULT\_TRAVEL\_ACCELERATION 1000 // X, Y, Z acceleration for travel
* //#define S\_CURVE\_ACCELERATION
* #define USE\_PROBE\_FOR\_Z\_HOMING
* #define XY\_PROBE\_SPEED (200\*60)
* #define Z\_PROBE\_SPEED\_FAST (HOMING\_FEEDRATE\_Z \* 2)
* #define MULTIPLE\_PROBING 2
* #define Z\_CLEARANCE\_DEPLOY\_PROBE 5 // Z Clearance for Deploy/Stow
* #define Z\_CLEARANCE\_BETWEEN\_PROBES 2 // Z Clearance between probe points
* #define Z\_CLEARANCE\_MULTI\_PROBE 3 // Z Clearance between multiple probes
* #define Z\_MIN\_PROBE\_REPEATABILITY\_TEST
* #define X\_MIN\_POS -13
* #define Y\_MIN\_POS -7
* #define Z\_SAFE\_HOMING
* #define Z\_SAFE\_HOMING\_X\_POINT 35// (X\_CENTER / 8) // X point for Z homing
* #define Z\_SAFE\_HOMING\_Y\_POINT 35// (Y\_CENTER / 8) // Y point for Z homing
* #define HOMING\_FEEDRATE\_XY (20\*60
* #define HOMING\_FEEDRATE\_Z (6\*60)
* #define PREHEAT\_1\_TEMP\_HOTEND 200
* #define PREHEAT\_1\_TEMP\_BED 60
* #define PREHEAT\_2\_LABEL "PETG"
* #define PREHEAT\_2\_TEMP\_BED 80
* #define PREHEAT\_3\_LABEL "TPU"
* #define PREHEAT\_3\_TEMP\_HOTEND 220
* #define PREHEAT\_3\_TEMP\_BED 60
* #define PREHEAT\_3\_FAN\_SPEED 0 // Value from 0 to 255
* #define PREHEAT\_4\_LABEL "ABS"
* #define PREHEAT\_4\_TEMP\_HOTEND 240
* #define PREHEAT\_4\_TEMP\_BED 110
* #define PREHEAT\_4\_FAN\_SPEED 0 // Value from 0 to 255
* #define NOZZLE\_PARK\_POINT { (X\_MIN\_POS + 10), (Y\_MIN\_POS + 10), 20 }

Configuration\_adv.h

* #define USE\_CONTROLLER\_FAN
* #define CONTROLLER\_FAN\_PIN FAN1\_PIN
* #define SENSORLESS\_BACKOFF\_MM { 3, 3 }
* #define Z\_STEPPER\_AUTO\_ALIGN
* #define ADAPTIVE\_STEP\_SMOOTHING
* #define BACKUP\_POWER\_SUPPLY // Backup power / UPS to move the steppers on power loss
* #define POWER\_LOSS\_PIN PD11
* #define POWER\_LOSS\_STATE HIGH
* #define POWER\_LOSS\_PULL
* #define BABYSTEP\_MULTIPLICATOR\_Z 10
* #define BABYSTEP\_ZPROBE\_OFFSET
* #define LIN\_ADVANCE
* #define LIN\_ADVANCE\_K 0
* #define BLOCK\_BUFFER\_SIZE 64
* #define BLOCK\_BUFFER\_SIZE 64
* #define BLOCK\_BUFFER\_SIZE 64
* #define BUFSIZE 32
* #define X\_CURRENT 1050
* #define X\_CURRENT\_HOME ((X\_CURRENT)/2)
* #define Y\_CURRENT 1150
* #define Y\_CURRENT\_HOME ((Y\_CURRENT)/2)
* #define Z\_CURRENT 800
* #define Z2\_CURRENT 800
* #define E0\_CURRENT 800
* #define X\_STALL\_SENSITIVITY 91
* #define Y\_STALL\_SENSITIVITY 92
* #define SQUARE\_WAVE\_STEPPING

#define X\_HOMING\_ACCELERATION 140

#define Y\_HOMING\_ACCELERATION 140

G28:

planner.settings.max\_acceleration\_mm\_per\_s2[X\_AXIS] = X\_HOMING\_ACCELERATION;

planner.settings.max\_acceleration\_mm\_per\_s2[Y\_AXIS] = Y\_HOMING\_ACCELERATION;