
HVL Common Code Base Documentation

Release 0.14.3

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CONTENTS:

1	HVL Common Code Base	1
1.1	Features	1
1.2	Documentation	5
1.3	Credits	5
2	Installation	7
2.1	Stable release	7
2.2	From sources	7
2.3	Additional system libraries	8
3	Usage	9
4	API Documentation	11
4.1	hvl_ccb	11
5	Contributing	205
5.1	Types of Contributions	205
5.2	Get Started!	206
5.3	Merge Request Guidelines	207
5.4	Tips	207
5.5	Deploying	208
6	Credits	211
6.1	Active Maintainers	211
6.2	Authors and Contributors	211
7	History	213
7.1	0.14.3 (2023-11-17)	213
7.2	0.14.2 (2023-09-07)	213
7.3	0.14.1 (2023-08-21)	213
7.4	0.14.0 (2023-07-28)	214
7.5	0.13.3 (2023-03-31)	214
7.6	0.13.2 (2023-03-17)	214
7.7	0.13.1 (2023-03-03)	214
7.8	0.13.0 (2023-01-27)	215
7.9	0.12.3 (2022-12-27)	215
7.10	0.12.2 (2022-11-29)	215
7.11	0.12.1 (2022-10-31)	215
7.12	0.12.0 (2022-10-17)	216
7.13	0.11.1 (2022-09-15)	216
7.14	0.11.0 (2022-06-22)	216

7.15	0.10.3 (2022-03-21)	216
7.16	0.10.2 (2022-02-28)	217
7.17	0.10.1 (2022-01-24)	217
7.18	0.10.0 (2022-01-17)	217
7.19	0.9.0 (2022-01-07)	218
7.20	0.8.5 (2021-11-05)	218
7.21	0.8.4 (2021-10-22)	219
7.22	0.8.3 (2021-09-27)	219
7.23	0.8.2 (2021-08-27)	219
7.24	0.8.1 (2021-08-13)	219
7.25	0.8.0 (2021-07-02)	219
7.26	0.7.1 (2021-06-04)	220
7.27	0.7.0 (2021-05-25)	220
7.28	0.6.1 (2021-05-08)	220
7.29	0.6.0 (2021-04-23)	221
7.30	0.5.0 (2020-11-11)	221
7.31	0.4.0 (2020-07-16)	222
7.32	0.3.5 (2020-02-18)	222
7.33	0.3.4 (2019-12-20)	223
7.34	0.3.3 (2019-05-08)	223
7.35	0.3.2 (2019-05-08)	223
7.36	0.3.1 (2019-05-02)	223
7.37	0.3 (2019-05-02)	223
7.38	0.2.1 (2019-04-01)	224
7.39	0.2.0 (2019-03-31)	224
7.40	0.1.0 (2019-02-06)	224
8	Indices and tables	225
	Python Module Index	227
	Index	229

HVL COMMON CODE BASE

Python common code base (CCB) to control devices, which are used in high-voltage research. All implemented devices are used and tested in the High Voltage Laboratory ([HVL](#)) of the Federal Institute of Technology Zurich (ETH Zurich).

- Free software: GNU General Public License v3
- Copyright (c) 2019-2023 ETH Zurich, SIS ID and HVL D-ITET

1.1 Features

For managing multi-device experiments instantiate the `ExperimentManager` utility class.

1.1.1 Devices

The device wrappers in `hvl_ccb` provide a standardised API with configuration dataclasses, various settings and options, as well as start/stop methods. Currently wrappers are available to control the following devices:

Function/Type	Devices
Bench Multimeter	Fluke 8845A and 8846A 6.5 Digit Precision Multimeter
Data acquisition	LabJack (T4, T7, T7-PRO; requires LJM Library) Pico Technology PT-104 Platinum Resistance Data Logger (requires PicoSDK/libusbpt104)
Digital Delay Generator	Highland T560
Digital IO	LabJack (T4, T7, T7-PRO; requires LJM Library)
Experiment control	HVL Cube with and without Power Inverter
Gas Analyser	MBW 973-SF6 gas dew point mirror analyzer Pfeiffer Vacuum TPG (25x, 26x and 36x) controller for compact pressure gauges SST Luminox oxygen sensor
Laser	CryLaS pulsed laser CryLaS laser attenuator
Oscilloscope	Rhode & Schwarz RTO 1024 TiePie (HS5, HS6, WS5)
Power supply	Elektro-Automatik PSI9000 FuG Elektronik Heinzinger PNC Technix capacitor charger
Stepper motor drive	Newport SMC100PP Schneider Electric ILS2T
Temperature control	Lauda PRO RP 245 E circulation thermostat
Waveform generator	TiePie (HS5, WS5)

Each device uses at least one standardised communication protocol wrapper.

1.1.2 Communication protocols

In `hvl_ccb` by “communication protocol” we mean different levels of communication standards, from the low level actual communication protocols like serial communication to application level interfaces like VISA TCP standard. There are also devices in `hvl_ccb` that use a dummy communication protocol; this is because these devices are build on proprietary manufacturer libraries that communicate with the corresponding devices, as in the case of TiePie or LabJack devices.

The communication protocol wrappers in `hvl_ccb` provide a standardised API with configuration dataclasses, as well as open/close and read/write/query methods. Currently, wrappers for the following communication protocols are available:

Communication protocol	Devices using
Modbus TCP	Schneider Electric ILS2T stepper motor drive
OPC UA	HVL Cube with and without Power Inverter
Serial	<p>CryLaS pulsed laser and laser attenuator</p> <p>FuG Elektronik power supply (e.g. capacitor charger HCK) using the Probus V protocol</p> <p>Heinzinger PNC power supply using Heinzinger Digital Interface I/II</p> <p>SST Luminos oxygen sensor</p> <p>MBW 973-SF6 gas dew point mirror analyzer</p> <p>Newport SMC100PP single axis driver for 2-phase stepper motors</p> <p>Pfeiffer Vacuum TPG (25x, 26x and 36x) controller for compact pressure gauges</p> <p>Technix capacitor charger</p>
TCP	Lauda PRO RP 245 E circulation thermostat
Telnet	<p>Technix capacitor charger</p> <p>Fluke 8845A and 8846</p>
VISA TCP	<p>Elektro-Automatik PSI9000 DC power supply</p> <p>Rhode & Schwarz RTO 1024 oscilloscope</p>
<i>propriety</i>	<p>LabJack (T4, T7, T7-PRO) devices, which communicate via LJM Library</p> <p>Pico Technology PT-104 Platinum Resistance Data Logger, which communicate via PicoSDK/libusbpt104</p> <p>TiePie (HS5, HS6, WS5) oscilloscopes and generators, which communicate via LibTiePie SDK</p>

1.1.3 Sensor and Unit Conversion Utility

The Conversion Utility is a submodule that allows on the one hand a unified implementation of hardware-sensors and on the other hand provides a unified way to convert units. Furthermore it is possible to map two ranges on to each other. This can be useful to convert between for example 4 - 20 mA and 0 - 10 V, both of them are common as sensor out- or input. Moreover, a subclass allows the mapping of a bit-range to any other range. For example a 12 bit number (0-4095) to 0 - 10. All utilities can be used with single numbers (`int`, `float`) as well as array-like structures containing single numbers (`np.array()`, `list`, `dict`, `tuple`).

Currently the following sensors are implemented:

- LEM LT 4000S
- LMT 70A

The following unit conversion classes are implemented:

- Temperature (Kelvin, Celsius, Fahrenheit)
- Pressure (Pascal, Bar, Atmosphere, Psi, Torr, Millimeter Mercury)

1.2 Documentation

Note: if you're planning to contribute to the `hvl_ccb` project read the **Contributing** section in the HVL CCB documentation.

Do either:

- read [HVL CCB documentation at RTD](#),

or

- build and read HVL CCB documentation locally; install first [Graphviz](#) (make sure to have the `dot` command in the executable search path) and the Python build requirements for documentation:

```
$ pip install docs/requirements.txt
```

and then either on Windows in Git BASH run:

```
$ ./make.sh docs
```

or from any other shell with GNU Make installed run:

```
$ make docs
```

The target index HTML ("`docs/_build/html/index.html`") should open automatically in your Web browser.

1.3 Credits

This package was created with [Cookiecutter](#) and the [audreyr/cookiecutter-pypackage](#) project template.

INSTALLATION

2.1 Stable release

To install HVL Common Code Base, run this command in your terminal:

```
$ pip install hvl_ccb
```

To install HVL Common Code Base with optional Python libraries that require manual installations of additional system libraries, you need to specify on installation extra requirements corresponding to these controllers. For instance, to install Python requirements for LabJack and TiePie devices, run:

```
$ pip install "hvl_ccb[tielie,labjack]"
```

See below for the info about additional system libraries and the corresponding extra requirements.

To install all extra requirements run:

```
$ pip install "hvl_ccb[all]"
```

This is the preferred method to install HVL Common Code Base, as it will always install the most recent stable release. If you don't have [pip](#) installed, this [Python installation guide](#) can guide you through the process.

2.2 From sources

The sources for HVL Common Code Base can be downloaded from the [GitLab repo](#).

You can either clone the repository:

```
$ git clone git@gitlab.com:ethz_hvl/hvl_ccb.git
```

Or download the [tarball](#):

```
$ curl -OL https://gitlab.com/ethz_hvl/hvl_ccb/-/archive/master/hvl_ccb.tar.gz
```

Once you have a copy of the source, you can install it with:

```
$ pip install .
```

2.3 Additional system libraries

If you have installed *hvl_ccb* with any of the extra features corresponding to device controllers, you must additionally install respective system library; these are:

Extra feature	Additional system library
labjack	LJM Library
picotech	PicoSDK (Windows) / libusbpt104 (Ubuntu/Debian)

For more details on installation of the libraries see docstrings of the corresponding *hvl_ccb* modules.

CHAPTER THREE

USAGE

To use HVL Common Code Base in a project:

```
import hvl_ccb
```


API DOCUMENTATION

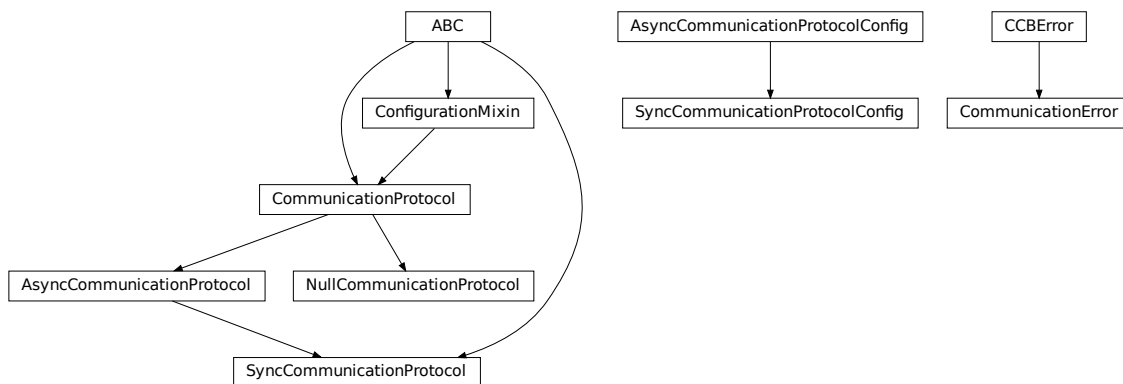
4.1 hvl_ccb

4.1.1 Subpackages

`hvl_ccb.comm`

Submodules

`hvl_ccb.comm.base`



Module with base classes for communication protocols.

class `AsyncCommunicationProtocol`(*config*)

Bases: `CommunicationProtocol`

Abstract base class for asynchronous communication protocols

static `config_cls()` → `type[AsyncCommunicationProtocolConfig]`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

read() → str

Read a single line of text as *str* from the communication.

Returns

text as *str* including the terminator, which can also be empty ""

read_all(*n_attempts_max*: int | None = None, *attempt_interval_sec*: int | float | None = None) → str | None

Read all lines of text from the connection till nothing is left to read.

Parameters

- **n_attempts_max** – Amount of attempts how often a non-empty text is tried to be read
- **attempt_interval_sec** – time between the reading attempts

Returns

A multi-line *str* including the terminator internally

abstract read_bytes() → bytes

Read a single line as *bytes* from the communication.

This method uses *self.access_lock* to ensure thread-safety.

Returns

a single line as *bytes* containing the terminator, which can also be empty b""

read_nonempty(*n_attempts_max*: int | None = None, *attempt_interval_sec*: int | float | None = None) → str | None

Try to read a non-empty single line of text as *str* from the communication. If the host does not reply or reply with white space only, it will return None.

Returns

a non-empty text as a *str* or None in case of an empty string

Parameters

- **n_attempts_max** – Amount of attempts how often a non-empty text is tried to be read
- **attempt_interval_sec** – time between the reading attempts

read_text() → str

Read one line of text from the serial port. The input buffer may hold additional data afterwards, since only one line is read.

NOTE: backward-compatibility proxy for *read* method; to be removed in v1.0

Returns

String read from the serial port; '' if there was nothing to read.

Raises

SerialCommunicationIOError – when communication port is not opened

read_text_nonempty(*n_attempts_max*: int | None = None, *attempt_interval_sec*: int | float | None = None) → str | None

Reads from the serial port, until a non-empty line is found, or the number of attempts is exceeded.

NOTE: backward-compatibility proxy for *read* method; to be removed in v1.0

Attention: in contrast to *read_text*, the returned answer will be stripped of a whitespace newline terminator at the end, if such terminator is set in the initial configuration (default).

Parameters

- **n_attempts_max** – maximum number of read attempts

- **attempt_interval_sec** – time between the reading attempts

Returns

String read from the serial port; '' if number of attempts is exceeded or serial port is not opened.

write(*text: str*)

Write text as *str* to the communication.

Parameters

text – text as a *str* to be written

abstract write_bytes(*data: bytes*) → int

Write data as *bytes* to the communication.

This method uses *self.access_lock* to ensure thread-safety.

Parameters

data – data as *bytes*-string to be written

Returns

number of bytes written

write_text(*text: str*)

Write text to the serial port. The text is encoded and terminated by the configured terminator.

NOTE: backward-compatibility proxy for *read* method; to be removed in v1.0

Parameters

text – Text to send to the port.

Raises

SerialCommunicationIOError – when communication port is not opened

```
class AsyncCommunicationProtocolConfig(terminator: bytes = b'\n', encoding: str = 'utf-8',
                                       encoding_error_handling: str = 'strict',
                                       wait_sec_read_text_nonempty: int | float = 0.5,
                                       default_n_attempts_read_text_nonempty: int = 10)
```

Bases: object

Base configuration data class for asynchronous communication protocols

clean_values()

default_n_attempts_read_text_nonempty: int = 10

default number of attempts to read a non-empty text

encoding: str = 'utf-8'

Standard encoding of the connection. Typically this is *utf-8*, but can also be *latin-1* or something from here: <https://docs.python.org/3/library/codecs.html#standard-encodings>

encoding_error_handling: str = 'strict'

Encoding error handling scheme as defined here: <https://docs.python.org/3/library/codecs.html#error-handlers> By default strict error handling that raises *UnicodeError*.

force_value(*fieldname, value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

terminator: bytes = b'\r\n'

The terminator character. Typically this is b'\r\n' or b'\n', but can also be b'\r' or other combinations. This defines the end of a single line.

wait_sec_read_text_nonempty: int | float = 0.5

time to wait between attempts of reading a non-empty text

exception CommunicationError

Bases: *CSError*

class CommunicationProtocol(*config*)

Bases: *ConfigurationMixin*, ABC

Communication protocol abstract base class.

Specifies the methods to implement for communication protocol, as well as implements some default settings and checks.

access_lock

Access lock to use with context manager when accessing the communication protocol (thread safety)

abstract close()

Close the communication protocol

abstract open()

Open communication protocol

class NullCommunicationProtocol(*config*)

Bases: *CommunicationProtocol*

Communication protocol that does nothing.

close() → *None*

Void close function.

static config_cls() → type[*EmptyConfig*]

Empty configuration

Returns

EmptyConfig

open() → *None*

Void open function.

class SyncCommunicationProtocol(*config*)

Bases: *AsyncCommunicationProtocol*, ABC

Abstract base class for synchronous communication protocols with *query()*

static config_cls() → type[*SyncCommunicationProtocolConfig*]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

query(*command: str, n_attempts_max: int | None = None, attempt_interval_sec: int | float | None = None*)
→ str | *None*

Send a command to the interface and handle the status message. Possibly raises an exception.

Parameters

- **command** – Command to send
- **n_attempts_max** – Amount of attempts how often a non-empty text is tried to be read as answer
- **attempt_interval_sec** – time between the reading attempts

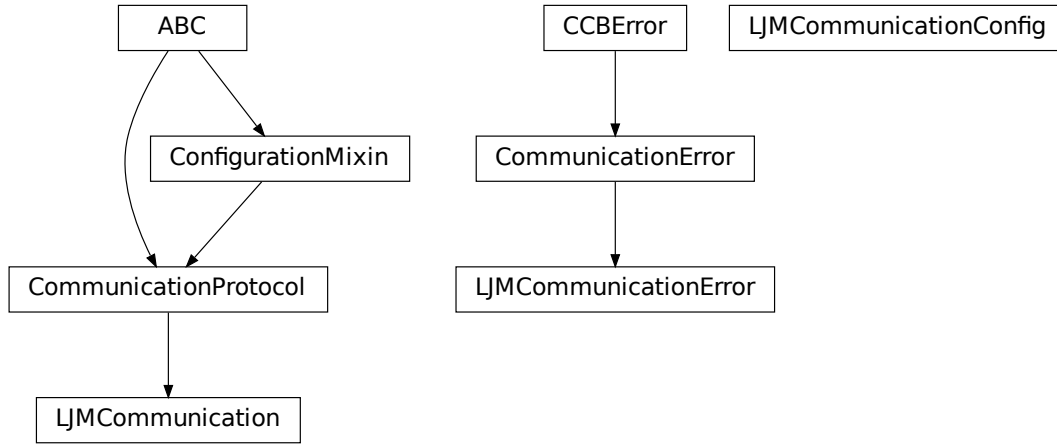
Returns

Answer from the interface, which can be None instead of an empty reply

class SyncCommunicationProtocolConfig(*terminator: bytes = b'\r\n', encoding: str = 'utf-8',
encoding_error_handling: str = 'strict',
wait_sec_read_text_nonempty: int | float = 0.5,
default_n_attempts_read_text_nonempty: int = 10*)

Bases: *AsyncCommunicationProtocolConfig*

Base configuration data class for synchronous communication protocols

hvl_ccb.comm.labjack_ljm

Communication protocol for LabJack using the LJM Library. Originally developed and tested for LabJack T7-PRO.

Makes use of the LabJack LJM Library Python wrapper. This wrapper needs an installation of the LJM Library for Windows, Mac OS X or Linux. Go to: <https://labjack.com/support/software/installers/ljm> and <https://labjack.com/support/software/examples/ljm/python>

class `LJMCommunication(configuration)`

Bases: `CommunicationProtocol`

Communication protocol implementing the LabJack LJM Library Python wrapper.

close() → *None*

Close the communication port.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

property is_open: bool

Flag indicating if the communication port is open.

Returns

True if the port is open, otherwise *False*

open() → *None*

Open the communication port.

read_name(*names: str, return_num_type: type[~numbers.Real] = <class 'float'>) → Real | Sequence[Real]

Read one or more input numeric values by name.

Parameters

- **names** – one or more names to read out from the LabJack
- **return_num_type** – optional numeric type specification for return values; by default *float*.

Returns

answer of the LabJack, either single number or multiple numbers in a sequence, respectively, when one or multiple names to read were given

Raises

TypeError – if read value of type not compatible with *return_num_type*

write_name(*name: str, value: Real*) → *None*

Write one value to a named output.

Parameters

- **name** – String or with name of LabJack IO
- **value** – is the value to write to the named IO port

write_names(*name_value_dict: dict[str, Real]*) → *None*

Write more than one value at once to named outputs.

Parameters

name_value_dict – is a dictionary with string names of LabJack IO as keys and corresponding numeric values

```
class LJMCommunicationConfig(device_type: str | DeviceType = 'ANY', connection_type: str | ConnectionType = 'ANY', identifier: str = 'ANY')
```

Bases: object

Configuration dataclass for *LJMCommunication*.

```
class ConnectionType(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)
```

Bases: *AutoNumberNameEnum*

LabJack connection type.

ANY = 1

ETHERNET = 4

TCP = 3

USB = 2

WIFI = 5

```
class DeviceType(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)
```

Bases: *AutoNumberNameEnum*

LabJack device types.

Can be also looked up by ambiguous Product ID (*p_id*) or by instance name: ``python LabJackDeviceType(4) is LabJackDeviceType('T4')``

ANY = 1

T4 = 2

T7 = 3

T7_PRO = 4

classmethod `get_by_p_id(p_id: int) → DeviceType | list[DeviceType]`

Get LabJack device type instance via LabJack product ID.

Note: Product ID is not unambiguous for LabJack devices.

Parameters

p_id – Product ID of a LabJack device

Returns

Instance or list of instances of *LabJackDeviceType*

Raises

ValueError – when Product ID is unknown

clean_values() → *None*

Performs value checks on `device_type` and `connection_type`.

connection_type: `str | ConnectionType = 'ANY'`

Can be either string or of enum *ConnectionType*.

device_type: `str | DeviceType = 'ANY'`

Can be either string 'ANY', 'T7_PRO', 'T7', 'T4', or of enum *DeviceType*.

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

identifier: `str = 'ANY'`

The identifier specifies information for the connection to be used. This can be an IP address, serial number, or device name. See the LabJack docs (<https://labjack.com/support/software/api/ljm/function-reference/ljmopens/identifier-parameter>) for more information.

is_configdataclass = True

classmethod `keys()` → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod `optional_defaults()` → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod `required_keys()` → Sequence[str]

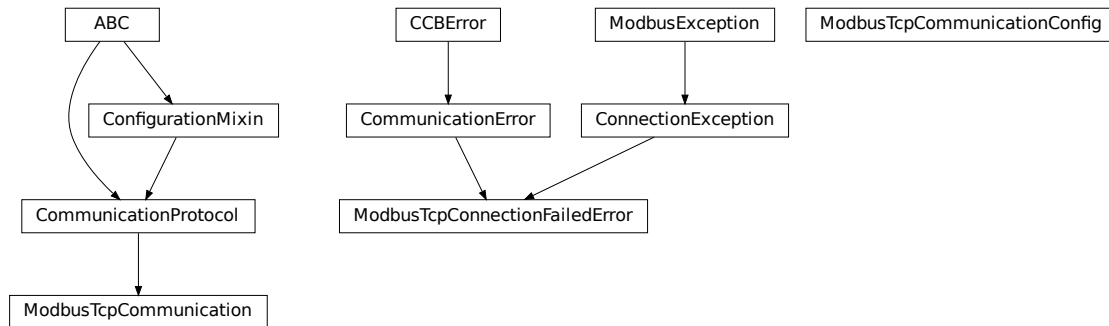
Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

exception LJMCommunicationErrorBases: *CommunicationError*

Errors coming from LJMCommunication.

hvl_ccb.comm.modbus_tcp

Communication protocol for modbus TCP ports. Makes use of the *pymodbus* library.

class ModbusTcpCommunication(configuration)Bases: *CommunicationProtocol*

Implements the Communication Protocol for modbus TCP.

close()

Close the Modbus TCP connection.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

open() → *None*

Open the Modbus TCP connection.

Raises*ModbusTcpConnectionFailedError* – if the connection fails.**read_holding_registers(address: int, count: int)** → list[int]

Read specified number of register starting with given address and return the values from each register.

Parameters

- **address** – address of the first register
- **count** – count of registers to read

Returnslist of *int* values**read_input_registers(address: int, count: int)** → list[int]

Read specified number of register starting with given address and return the values from each register in a list.

Parameters

- **address** – address of the first register
- **count** – count of registers to read

Returns

list of *int* values

write_registers(*address: int, values: list[int] | int*)

Write values from the specified address forward.

Parameters

- **address** – address of the first register
- **values** – list with all values

class ModbusTcpCommunicationConfig(*host: str | IPv4Address | IPv6Address, unit: int, port: int = 502*)

Bases: object

Configuration dataclass for *ModbusTcpCommunication*.

clean_values()

force_value(*fieldname, value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

host: str | IPv4Address | IPv6Address

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

port: int = 502

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

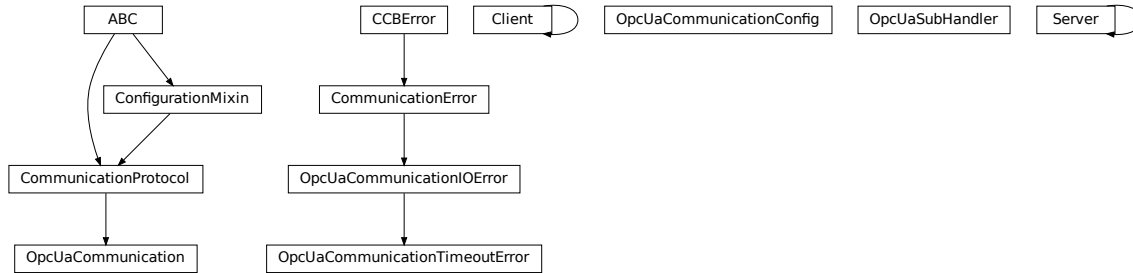
unit: int

exception ModbusTcpConnectionFailedError(string="")

Bases: `ConnectionException`, `CommunicationError`

Error raised when the connection failed.

hvl_ccb.comm.opc



Communication protocol implementing an OPC UA connection. This protocol is used to interface with the “Cube” PLC from Siemens.

class Client(url: str, timeout: int = 4)

Bases: `Client`

disconnect()

get_objects_node()

Get Objects node of client. Returns a Node object.

property is_open

send_hello(*args, **kwargs)

class OpcUaCommunication(config)

Bases: `CommunicationProtocol`

Communication protocol implementing an OPC UA connection. Makes use of the package python-opcua.

close() → *None*

Close the connection to the OPC UA server.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

init_monitored_nodes(node_id: object | Iterable, ns_index: int) → *None*

Initialize monitored nodes.

Parameters

- **node_id** – one or more strings of node IDs; node IDs are always casted via `str()` method here, hence do not have to be strictly string objects.

- **ns_index** – the namespace index the nodes belong to.

Raises

OpcUaCommunicationIOError – when protocol was not opened or can't communicate with a OPC UA server

property is_open: **bool**

Flag indicating if the communication port is open. —DEPRECATED! DO NOT USE!!!—

Returns

True if the port is open, otherwise *False*

open() → *None*

Open the communication to the OPC UA server.

Raises

OpcUaCommunicationIOError – when communication port cannot be opened.

read(*node_id*, *ns_index*)

Read a value from a node with id and namespace index.

Parameters

- **node_id** – the ID of the node to read the value from
- **ns_index** – the namespace index of the node

Returns

the value of the node object.

Raises

OpcUaCommunicationIOError – when protocol was not opened or can't communicate with a OPC UA server

write(*node_id*, *ns_index*, *value*) → *None*

Write a value to a node with name **name**.

Parameters

- **node_id** – the id of the node to write the value to.
- **ns_index** – the namespace index of the node.
- **value** – the value to write.

Raises

OpcUaCommunicationIOError – when protocol was not opened or can't communicate with a OPC UA server

```
class OpcUaCommunicationConfig(host: str | ~ipaddress.IPv4Address | ~ipaddress.IPv6Address,  
                               endpoint_name: str, port: int = 4840, sub_handler:  
                               ~hvl_ccb.comm.opc.OpcUaSubHandler =  
                               <hvl_ccb.comm.opc.OpcUaSubHandler object>, update_parameter:  
                               ~asyncua.ua.uaproto.protocol_auto.CreateSubscriptionParameters =  
                               CreateSubscriptionParameters(RequestedPublishingInterval=1000,  
                                                             RequestedLifetimeCount=300, RequestedMaxKeepAliveCount=22,  
                                                             MaxNotificationsPerPublish=10000, PublishingEnabled=True, Priority=0),  
                               wait_timeout_retry_sec: int | float = 1, max_timeout_retry_nr: int = 5)
```

Bases: object

Configuration dataclass for OPC UA Communciation.

clean_values()

endpoint_name: str

Endpoint of the OPC server, this is a path like 'OPCUA/SimulationServer'

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

host: str | IPv4Address | IPv6Address

Hostname or IP-Address of the OPC UA server.

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

max_timeout_retry_nr: int = 5

Maximal number of call re-tries on underlying OPC UA client timeout error

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

port: int = 4840

Port of the OPC UA server to connect to.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

sub_handler: *OpcUaSubHandler* = <hvl_ccb.comm.opc.OpcUaSubHandler object>

object to use for handling subscriptions.

update_parameter: CreateSubscriptionParameters = CreateSubscriptionParameters(RequestedPublishingInterval=1000, RequestedLifetimeCount=300, RequestedMaxKeepAliveCount=22, MaxNotificationsPerPublish=10000, PublishingEnabled=True, Priority=0)

Values are given as a *ua.CreateSubscriptionParameters* as these parameters are requested by the OPC server. Other values will lead to an automatic revision of the parameters and a warning in the opc-logger, cf. MR !173

```
wait_timeout_retry_sec: int | float = 1
```

Wait time between re-trying calls on underlying OPC UA client timeout error

```
exception OpcUaCommunicationIOError
```

Bases: `OSError`, `CommunicationError`

OPC-UA communication I/O error.

```
exception OpcUaCommunicationTimeoutError
```

Bases: `OpcUaCommunicationIOError`

OPC-UA communication timeout error.

```
class OpcUaSubHandler
```

Bases: `object`

Base class for subscription handling of OPC events and data change events. Override methods from this class to add own handling capabilities.

To receive events from server for a subscription data_change and event methods are called directly from receiving thread. Do not do expensive, slow or network operation there. Create another thread if you need to do such a thing.

```
datachange_notification(node, val, data)
```

```
event_notification(event)
```

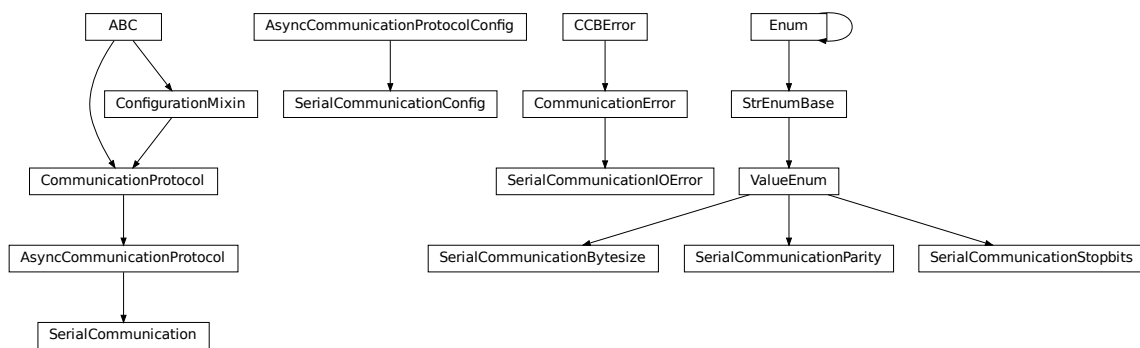
```
class Server(shelf_file=None, tloop=None, sync_wrapper_timeout: float | None = 120)
```

Bases: `Server`

```
get_objects_node()
```

Get Objects node of server. Returns a Node object.

hvl_ccb.comm.serial



Communication protocol for serial ports. Makes use of the `pySerial` library.

```
class SerialCommunication(configuration)
```

Bases: `AsyncCommunicationProtocol`

Implements the Communication Protocol for serial ports.

close()

Close the serial connection.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

property is_open: bool

Flag indicating if the serial port is open.

Returns

True if the serial port is open, otherwise *False*

open()

Open the serial connection.

Raises

SerialCommunicationIOError – when communication port cannot be opened.

read_bytes() → bytes

Read the bytes from the serial port till the terminator is found. The input buffer may hold additional lines afterwards.

This method uses *self.access_lock* to ensure thread-safety.

Returns

Bytes read from the serial port; *b''* if there was nothing to read.

Raises

SerialCommunicationIOError – when communication port is not opened

read_single_bytes(size: int = 1) → bytes

Read the specified number of bytes from the serial port. The input buffer may hold additional data afterwards.

Returns

Bytes read from the serial port; *b''* if there was nothing to read.

write_bytes(data: bytes) → int

Write bytes to the serial port.

This method uses *self.access_lock* to ensure thread-safety.

Parameters

data – data to write to the serial port

Returns

number of bytes written

Raises

SerialCommunicationIOError – when communication port is not opened

```
class SerialCommunicationBytesize(value=<no_arg>, names=None, module=None, qualname=None,
                                   type=None, start=1, boundary=None)
```

Bases: *ValueEnum*

Serial communication bytesize.

EIGHTBITS = 8

FIVEBITS = 5

SEVENBITS = 7

SIXBITS = 6

```
class SerialCommunicationConfig(terminator: bytes = b'\r\n', encoding: str = 'utf-8',
                                encoding_error_handling: str = 'strict', wait_sec_read_text_nonempty: int
                                | float = 0.5, default_n_attempts_read_text_nonempty: int = 10, port: str |
                                None = None, baudrate: int = 9600, parity: str |
                                SerialCommunicationParity = SerialCommunicationParity.NONE,
                                stopbits: int | float | SerialCommunicationStopbits =
                                SerialCommunicationStopbits.ONE, bytesize: int |
                                SerialCommunicationBytesize =
                                SerialCommunicationBytesize.EIGHTBITS, timeout: int | float = 2)
```

Bases: [AsyncCommunicationProtocolConfig](#)

Configuration dataclass for [SerialCommunication](#).

Bytesize

alias of [SerialCommunicationBytesize](#)

Parity

alias of [SerialCommunicationParity](#)

Stopbits

alias of [SerialCommunicationStopbits](#)

baudrate: int = 9600

Baudrate of the serial port

bytesize: int | [SerialCommunicationBytesize](#) = 8

Size of a byte, 5 to 8

clean_values()

create_serial_port() → Serial

Create a serial port instance according to specification in this configuration

Returns

Closed serial port instance

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

parity: str | *SerialCommunicationParity* = 'N'

Parity to be used for the connection.

port: str | *None* = None

Port is a string referring to a COM-port (e.g. 'COM3') or a URL. The full list of capabilities is found on [the pyserial documentation](#).

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

stopbits: int | float | *SerialCommunicationStopbits* = 1

Stopbits setting, can be 1, 1.5 or 2.

terminator_str() → str

timeout: int | float = 2

Timeout in seconds for the serial port

exception SerialCommunicationIOError

Bases: OSError, *CommunicationError*

Serial communication related I/O errors.

class SerialCommunicationParity(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: *ValueEnum*

Serial communication parity.

EVEN = 'E'

MARK = 'M'

NAMES = {'E': 'Even', 'M': 'Mark', 'N': 'None', 'O': 'Odd', 'S': 'Space'}

NONE = 'N'

ODD = 'O'

SPACE = 'S'

class SerialCommunicationStopbits(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: *ValueEnum*

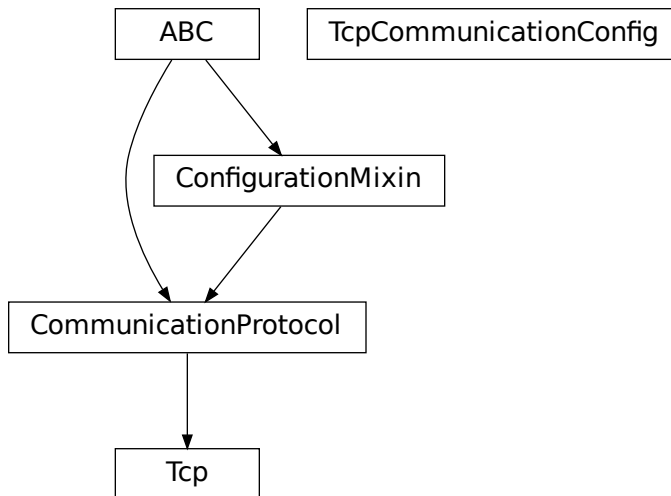
Serial communication stopbits.

ONE = 1

```
ONE_POINT_FIVE = 1.5
```

```
TWO = 2
```

`hvl_ccb.comm.tcp`



TCP communication protocol.

Makes use of the socket library.

```
class Tcp(configuration)
```

Bases: `CommunicationProtocol`

Tcp Communication Protocol.

```
close() → None
```

Close TCP connection.

```
static config_cls() → type[TcpCommunicationConfig]
```

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
open() → None
```

Open TCP connection.

```
read() → str
```

TCP read function :return: information read from TCP buffer formatted as string

```
write(command: str = "") → None
```

TCP write function :param command: command string to be sent :return: none


```
class TcpCommunicationConfig(host: str | IPv4Address | IPv6Address, port: int = 54321, bufsize: int = 1024)
```

Bases: object

Configuration dataclass for TcpCommunication.

```
bufsize:  int = 1024
```

```
clean_values()
```

```
force_value(fieldname, value)
```

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

```
host:  str | IPv4Address | IPv6Address
```

```
is_configdataclass = True
```

```
classmethod keys() → Sequence[str]
```

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

```
classmethod optional_defaults() → dict[str, object]
```

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

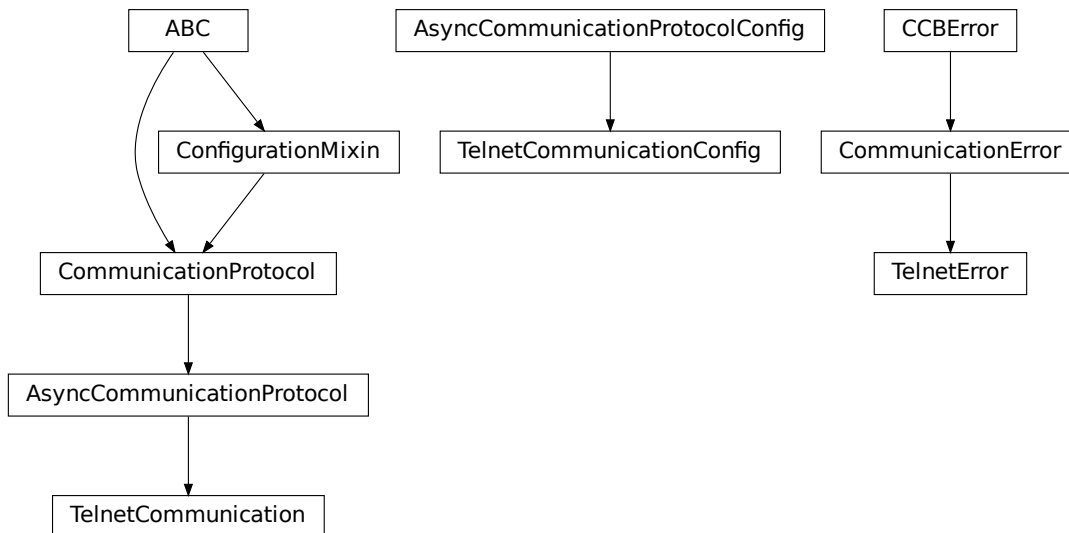
```
port:  int = 54321
```

```
classmethod required_keys() → Sequence[str]
```

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

hvl_ccb.comm.telnet

Communication protocol for telnet. Makes use of the [telnetlib](#) library.

class `TelnetCommunication(configuration)`

Bases: [AsyncCommunicationProtocol](#)

Implements the Communication Protocol for telnet.

close()

Close the telnet connection unless it is not closed.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

property is_open: bool

Is the connection open?

Returns

True for an open connection

open()

Open the telnet connection unless it is not yet opened.

read_bytes() → bytes

Read data as *bytes* from the telnet connection.

Returns

data from telnet connection

Raises

[TelnetError](#) – when connection is not open, raises an Error during the communication

write_bytes(data: bytes)

Write the data as *bytes* to the telnet connection.

Parameters

data – Data to be sent.

Raises

TelnetError – when connection is not open, raises an Error during the communication

```
class TelnetCommunicationConfig(terminator: bytes = b'\r\n', encoding: str = 'utf-8',
                                encoding_error_handling: str = 'strict', wait_sec_read_text_nonempty: int
                                | float = 0.5, default_n_attempts_read_text_nonempty: int = 10, host: str |
                                IPv4Address | IPv6Address | None = None, port: int = 0, timeout: int |
                                float = 0.2)
```

Bases: *AsyncCommunicationProtocolConfig*

Configuration dataclass for *TelnetCommunication*.

clean_values()

create_telnet() → Telnet | *None*

Create a telnet client :return: Opened Telnet object or None if connection is not possible

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

host: str | IPv4Address | IPv6Address | *None* = *None*

Host to connect to can be localhost or

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

port: int = 0

Port at which the host is listening

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

timeout: int | float = 0.2

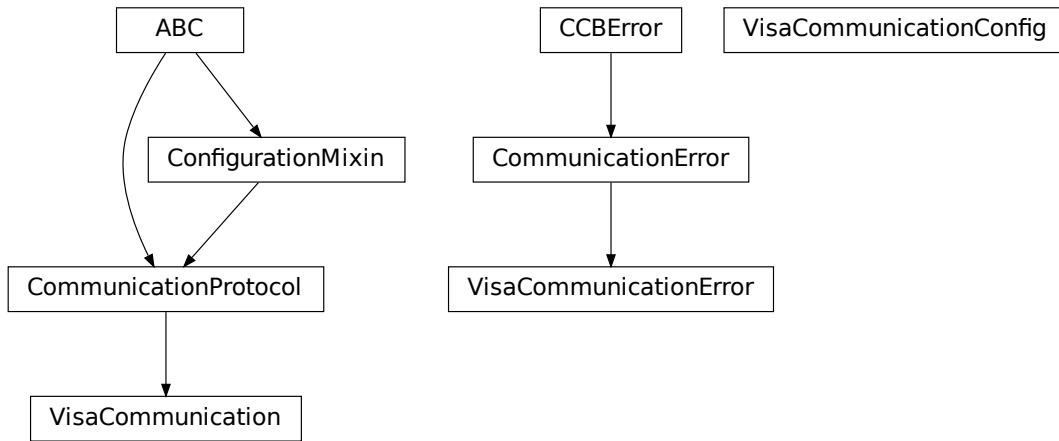
Timeout for reading a line

exception TelnetError

Bases: `OSError`, `CommunicationError`

Telnet communication related errors.

hvl_ccb.comm.visa



Communication protocol for VISA. Makes use of the pyvisa library. The backend can be NI-Visa or pyvisa-py.

Information on how to install a VISA backend can be found here: https://pyvisa.readthedocs.io/en/master/getting_nivisa.html

So far only TCPIP SOCKET and TCPIP INSTR interfaces are supported.

class VisaCommunication(configuration)

Bases: `CommunicationProtocol`

Implements the Communication Protocol for VISA / SCPI.

MULTI_COMMANDS_MAX = 5

The maximum of commands that can be sent in one round is 5 according to the VISA standard.

MULTI_COMMANDS_SEPARATOR = ';' ;

The character to separate two commands is ; according to the VISA standard.

WAIT_AFTER_WRITE = 0.08

Small pause in seconds to wait after write operations, allowing devices to really do what we tell them before continuing with further tasks.

close() → `None`

Close the VISA connection and invalidates the handle.

static config_cls() → type[*VisaCommunicationConfig*]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

open() → *None*

Open the VISA connection and create the resource.

query(*commands: str) → str | tuple[str, ...]

A combination of write(message) and read.

Parameters

commands – list of commands

Returns

list of values

Raises

VisaCommunicationError – when connection was not started, or when trying to issue too many commands at once.

spoll() → int

Execute serial poll on the device. Reads the status byte register STB. This is a fast function that can be executed periodically in a polling fashion.

Returns

integer representation of the status byte

Raises

VisaCommunicationError – when connection was not started

write(*commands: str) → *None*

Write commands. No answer is read or expected.

Parameters

commands – one or more commands to send

Raises

VisaCommunicationError – when connection was not started

```
class VisaCommunicationConfig(host: str | IPv4Address | IPv6Address, interface_type: str | InterfaceType,
                              board: int = 0, port: int = 5025, timeout: int = 5000, chunk_size: int =
                              204800, open_timeout: int = 1000, write_termination: str = '\n',
                              read_termination: str = '\n', visa_backend: str = "")
```

Bases: object

VisaCommunication configuration dataclass.

```
class InterfaceType(value=<no_arg>, names=None, module=None, qualname=None, type=None,
                    start=1, boundary=None)
```

Bases: *AutoNumberNameEnum*

Supported VISA Interface types.

TCPIP_INSTR = 2

VXI-11 protocol

TCPIP_SOCKET = 1

VISA-RAW protocol

address(*host*: str, *port*: int | None = None, *board*: int | None = None) → str

Address string specific to the VISA interface type.

Parameters

- **host** – host IP address
- **port** – optional TCP port
- **board** – optional board number

Returns

address string

property address: str

Address string depending on the VISA protocol's configuration.

Returns

address string corresponding to current configuration

board: int = 0

Board number is typically 0 and comes from old bus systems.

chunk_size: int = 204800

Chunk size is the allocated memory for read operations. The standard is 20kB, and is increased per default here to 200kB. It is specified in bytes.

clean_values()

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

host: str | IPv4Address | IPv6Address

interface_type: str | *InterfaceType*

Interface type of the VISA connection, being one of *InterfaceType*.

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

open_timeout: int = 1000

Timeout for opening the connection, in milli seconds.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

port: `int = 5025`

TCP port, standard is 5025.

read_termination: `str = '\n'`

Read termination character.

classmethod `required_keys()` \rightarrow `Sequence[str]`

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

timeout: `int = 5000`

Timeout for commands in milli seconds.

visa_backend: `str = ''`

Specifies the path to the library to be used with PyVISA as a backend. Defaults to None, which is NI-VISA (if installed), or pyvisa-py (if NI-VISA is not found). To force the use of pyvisa-py, specify '@py' here.

write_termination: `str = '\n'`

Write termination character.

exception `VisaCommunicationError`

Bases: `OSError`, `CommunicationError`

Base class for VisaCommunication errors.

Module contents

Communication protocols subpackage.

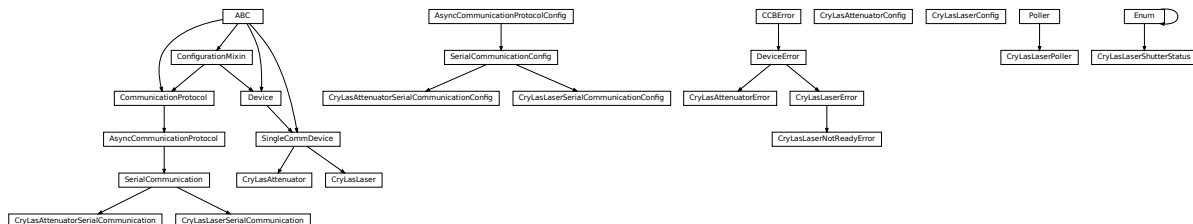
`hvl_ccb.dev`

Subpackages

`hvl_ccb.dev.crylas`

Submodules

`hvl_ccb.dev.crylas.crylas`



Device classes for a CryLas pulsed laser controller and a CryLas laser attenuator, using serial communication.

There are three modes of operation for the laser 1. Laser-internal hardware trigger (default): fixed to 20 Hz and max energy per pulse. 2. Laser-internal software trigger (for diagnosis only). 3. External trigger: required for arbitrary pulse energy or repetition rate. Switch to “external” on the front panel of laser controller for using option 3.

After switching on the laser with `laser_on()`, the system must stabilize for some minutes. Do not apply abrupt changes of pulse energy or repetition rate.

Manufacturer homepage: https://www.crylas.de/products/pulsed_laser.html

class CryLasAttenuator(*com, dev_config=None*)

Bases: *SingleCommDevice*

Device class for the CryLas laser attenuator.

property attenuation: `int | float`

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

set_attenuation(*percent: int | float*) → *None*

Set the percentage of attenuated light (inverse of `set_transmission`). :param percent: percentage of attenuation, number between 0 and 100 :raises ValueError: if param percent not between 0 and 100 :raises SerialCommunicationIOError: when communication port is not opened :raises CryLasAttenuatorError: if the device does not confirm success

set_init_attenuation()

Sets the attenuation to its configured initial/default value

Raises

SerialCommunicationIOError – when communication port is not opened

set_transmission(*percent: int | float*) → *None*

Set the percentage of transmitted light (inverse of `set_attenuation`). :param percent: percentage of transmitted light :raises ValueError: if param percent not between 0 and 100 :raises SerialCommunicationIOError: when communication port is not opened :raises CryLasAttenuatorError: if the device does not confirm success

start() → *None*

Open the com, apply the config value ‘init_attenuation’

Raises

SerialCommunicationIOError – when communication port cannot be opened

property transmission: `int | float`

class CryLasAttenuatorConfig(*init_attenuation: int | float = 0, response_sleep_time: int | float = 1*)

Bases: object

Device configuration dataclass for CryLas attenuator.

clean_values()

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

init_attenuation: `int | float = 0`

is_configdataclass = `True`

classmethod keys() → `Sequence[str]`

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → `dict[str, object]`

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → `Sequence[str]`

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

response_sleep_time: `int | float = 1`

exception CryLasAttenuatorError

Bases: *DeviceError*

General error with the CryLas Attenuator.

class CryLasAttenuatorSerialCommunication(*configuration*)

Bases: *SerialCommunication*

Specific communication protocol implementation for the CryLas attenuator. Already predefines device-specific protocol parameters in config.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class CryLasAttenuatorSerialCommunicationConfig(terminator: bytes = b'', encoding: str = 'utf-8',
                                                encoding_error_handling: str = 'strict',
                                                wait_sec_read_text_nonempty: Union[int, float] =
                                                0.5, default_n_attempts_read_text_nonempty: int =
                                                10, port: Optional[str] = None, baudrate: int = 9600,
                                                parity: Union[str,
                                                hvl_ccb.comm.serial.SerialCommunicationParity] =
                                                <SerialCommunicationParity.NONE: 'N'>, stopbits:
                                                Union[int,
                                                hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                                <SerialCommunicationStopbits.ONE: 1>, bytesize:
                                                Union[int,
                                                hvl_ccb.comm.serial.SerialCommunicationBytesize]
                                                = <SerialCommunicationBytesize.EIGHTBITS: 8>,
                                                timeout: Union[int, float] = 3)
```

Bases: [SerialCommunicationConfig](#)

baudrate: `int = 9600`

Baudrate for CryLas attenuator is 9600 baud

bytesize: `int | SerialCommunicationBytesize = 8`

One byte is eight bits long

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

parity: `str | SerialCommunicationParity = 'N'`

CryLas attenuator does not use parity

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

stopbits: `int` | `SerialCommunicationStopbits` = 1

CryLas attenuator uses one stop bit

terminator: `bytes` = `b''`

No terminator

timeout: `int` | `float` = 3

use 3 seconds timeout as default

class CryLasLaser(*com, dev_config=None*)

Bases: `SingleCommDevice`

CryLas laser controller device class.

class AnswersShutter(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: `Enum`

Standard answers of the CryLas laser controller to 'Shutter' command passed via *com*.

CLOSED = `'Shutter inaktiv'`

OPENED = `'Shutter aktiv'`

class AnswersStatus(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: `Enum`

Standard answers of the CryLas laser controller to 'STATUS' command passed via *com*.

ACTIVE = `'STATUS: Laser active'`

HEAD = `'STATUS: Head ok'`

INACTIVE = `'STATUS: Laser inactive'`

READY = `'STATUS: System ready'`

TEC1 = `'STATUS: TEC1 Regulation ok'`

TEC2 = `'STATUS: TEC2 Regulation ok'`

class LaserStatus(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: `Enum`

Status of the CryLas laser

READY_ACTIVE = 2

READY_INACTIVE = 1

UNREADY_INACTIVE = 0

property `is_inactive`

property `is_ready`

class RepetitionRates(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: `IntEnum`

Repetition rates for the internal software trigger in Hz

HARDWARE = 0

SOFTWARE_INTERNAL_SIXTY = 60

SOFTWARE_INTERNAL_TEN = 10

SOFTWARE_INTERNAL_TWENTY = 20

ShutterStatus

alias of `CryLasLaserShutterStatus`

close_shutter() → *None*

Close the laser shutter.

Raises

- `SerialCommunicationIOError` – when communication port is not opened
- `CryLasLaserError` – if success is not confirmed by the device

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

get_pulse_energy_and_rate() → `tuple[int, int]`

Use the debug mode, return the measured pulse energy and rate.

Returns

(energy in micro joule, rate in Hz)

Raises

- `SerialCommunicationIOError` – when communication port is not opened
- `CryLasLaserError` – if the device does not answer the query

laser_off() → *None*

Turn the laser off.

Raises

- `SerialCommunicationIOError` – when communication port is not opened
- `CryLasLaserError` – if success is not confirmed by the device

laser_on() → *None*

Turn the laser on.

Raises

- **`SerialCommunicationIOError`** – when communication port is not opened
- **`CryLasLaserNotReadyError`** – if the laser is not ready to be turned on
- **`CryLasLaserError`** – if success is not confirmed by the device

`open_shutter()` → *None*

Open the laser shutter.

Raises

- **`SerialCommunicationIOError`** – when communication port is not opened
- **`CryLasLaserError`** – if success is not confirmed by the device

`set_init_shutter_status()` → *None*

Open or close the shutter, to match the configured shutter_status.

Raises

- **`SerialCommunicationIOError`** – when communication port is not opened
- **`CryLasLaserError`** – if success is not confirmed by the device

`set_pulse_energy(energy: int)` → *None*

Sets the energy of pulses (works only with external hardware trigger). Proceed with small energy steps, or the regulation may fail.

Parameters

energy – energy in micro joule

Raises

- **`SerialCommunicationIOError`** – when communication port is not opened
- **`CryLasLaserError`** – if the device does not confirm success

`set_repetition_rate(rate: int | RepetitionRates)` → *None*

Sets the repetition rate of the internal software trigger.

Parameters

rate – frequency (Hz) as an integer

Raises

- **`ValueError`** – if rate is not an accepted value in RepetitionRates Enum
- **`SerialCommunicationIOError`** – when communication port is not opened
- **`CryLasLaserError`** – if success is not confirmed by the device

`start()` → *None*

Opens the communication protocol and configures the device.

Raises

`SerialCommunicationIOError` – when communication port cannot be opened

`stop()` → *None*

Stops the device and closes the communication protocol.

Raises

- **`SerialCommunicationIOError`** – if com port is closed unexpectedly
- **`CryLasLaserError`** – if `laser_off()` or `close_shutter()` fail

property target_pulse_energy

update_laser_status() → *None*

Update the laser status to *LaserStatus.NOT_READY* or *LaserStatus.INACTIVE* or *LaserStatus.ACTIVE*.

Note: laser never explicitly says that it is not ready (*LaserStatus.NOT_READY*) in response to ‘STATUS’ command. It only says that it is ready (heated-up and implicitly inactive/off) or active (on). If it’s not either of these then the answer is *Answers.HEAD*. Moreover, the only time the laser explicitly says that its status is inactive (*Answers.INACTIVE*) is after issuing a ‘LASER OFF’ command.

Raises

SerialCommunicationIOError – when communication port is not opened

update_repetition_rate() → *None*

Query the laser repetition rate.

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *CryLasLaserError* – if success is not confirmed by the device

update_shutter_status() → *None*

Update the shutter status (OPENED or CLOSED)

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *CryLasLaserError* – if success is not confirmed by the device

update_target_pulse_energy() → *None*

Query the laser pulse energy.

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *CryLasLaserError* – if success is not confirmed by the device

wait_until_ready() → *None*

Block execution until the laser is ready

Raises

CryLasLaserError – if the polling thread stops before the laser is ready

```
class CryLasLaserConfig(calibration_factor: int | float = 4.35, polling_period: int | float = 12, polling_timeout:
    int | float = 300, auto_laser_on: bool = True, init_shutter_status: int |
    CryLasLaserShutterStatus = CryLasLaserShutterStatus.CLOSED)
```

Bases: object

Device configuration dataclass for the CryLas laser controller.

ShutterStatus

alias of *CryLasLaserShutterStatus*

auto_laser_on: bool = True

calibration_factor: int | float = 4.35

clean_values()

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

init_shutter_status: `int` | `CryLasLaserShutterStatus` = 0

is_configdataclass = `True`

classmethod keys() → `Sequence[str]`

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → `dict[str, object]`

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

polling_period: `int` | `float` = 12

polling_timeout: `int` | `float` = 300

classmethod required_keys() → `Sequence[str]`

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

exception CryLasLaserError

Bases: `DeviceError`

General error with the CryLas Laser.

exception CryLasLaserNotReadyError

Bases: `CryLasLaserError`

Error when trying to turn on the CryLas Laser before it is ready.

class CryLasLaserPoller(*spoll_handler: Callable*, *check_handler: Callable*, *check_laser_status_handler: Callable*, *polling_delay_sec: int* | *float* = 0, *polling_interval_sec: int* | *float* = 1, *polling_timeout_sec: int* | *float* | `None` = `None`)

Bases: `Poller`

Poller class for polling the laser status until the laser is ready.

Raises

- `CryLasLaserError` – if the timeout is reached before the laser is ready
- `SerialCommunicationIOError` – when communication port is closed.

class CryLasLaserSerialCommunication(*configuration*)

Bases: *SerialCommunication*

Specific communication protocol implementation for the CryLas laser controller. Already predefines device-specific protocol parameters in config.

READ_TEXT_SKIP_PREFIXES = ('>', 'MODE:')

Prefixes of lines that are skipped when read from the serial port.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

query(*cmd: str, prefix: str, post_cmd: str | None = None*) → str

Send a command, then read the com until a line starting with prefix, or an empty line, is found. Returns the line in question.

Parameters

- **cmd** – query message to send to the device
- **prefix** – start of the line to look for in the device answer
- **post_cmd** – optional additional command to send after the query

Returns

line in question as a string

Raises

SerialCommunicationIOError – when communication port is not opened

query_all(*cmd: str, prefix: str*)

Send a command, then read the com until a line starting with prefix, or an empty line, is found. Returns a list of successive lines starting with prefix.

Parameters

- **cmd** – query message to send to the device
- **prefix** – start of the line to look for in the device answer

Returns

line in question as a string

Raises

SerialCommunicationIOError – when communication port is not opened

read() → str

Read first line of text from the serial port that does not start with any of *self.READ_TEXT_SKIP_PREFIXES*.

Returns

String read from the serial port; '' if there was nothing to read.

Raises

SerialCommunicationIOError – when communication port is not opened


```
class CryLasLaserSerialCommunicationConfig(terminator: bytes = b'\n', encoding: str = 'utf-8',
                                           encoding_error_handling: str = 'strict',
                                           wait_sec_read_text_nonempty: Union[int, float] = 0.5,
                                           default_n_attempts_read_text_nonempty: int = 10, port:
                                           Optional[str] = None, baudrate: int = 19200, parity:
                                           Union[str,
                                           hvl_ccb.comm.serial.SerialCommunicationParity] =
                                           <SerialCommunicationParity.NONE: 'N'>, stopbits:
                                           Union[int,
                                           hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                           <SerialCommunicationStopbits.ONE: 1>, bytesize:
                                           Union[int,
                                           hvl_ccb.comm.serial.SerialCommunicationBytesize] =
                                           <SerialCommunicationBytesize.EIGHTBITS: 8>, timeout:
                                           Union[int, float] = 10)
```

Bases: [SerialCommunicationConfig](#)

baudrate: int = 19200

Baudrate for CryLas laser is 19200 baud

bytesize: int | [SerialCommunicationBytesize](#) = 8

One byte is eight bits long

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

parity: str | [SerialCommunicationParity](#) = 'N'

CryLas laser does not use parity

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

stopbits: `int` | `SerialCommunicationStopbits` = 1

CryLas laser uses one stop bit

terminator: `bytes` = `b'\n'`

The terminator is LF

timeout: `int` | `float` = 10

use 10 seconds timeout as default (a long timeout is needed!)

class CryLasLaserShutterStatus(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: Enum

Status of the CryLas laser shutter

CLOSED = 0

OPENED = 1

Module contents

Device classes for a CryLas pulsed laser controller and a CryLas laser attenuator, using serial communication.

There are three modes of operation for the laser 1. Laser-internal hardware trigger (default): fixed to 20 Hz and max energy per pulse. 2. Laser-internal software trigger (for diagnosis only). 3. External trigger: required for arbitrary pulse energy or repetition rate. Switch to “external” on the front panel of laser controller for using option 3.

After switching on the laser with `laser_on()`, the system must stabilize for some minutes. Do not apply abrupt changes of pulse energy or repetition rate.

Manufacturer homepage: https://www.crylas.de/products/pulsed_laser.html

hvl_ccb.dev.cube

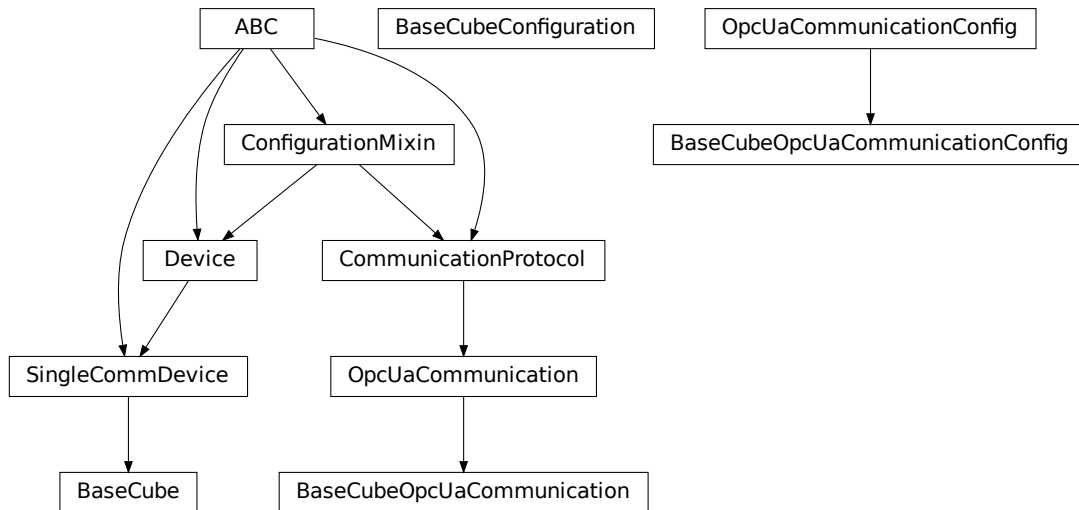
Submodules

hvl_ccb.dev.cube.alarms

Alarms

Alarms of the different “Cubes”.

hvl_ccb.dev.cube.base



Classes for the BaseCube device.

class `BaseCube`(*com*, *dev_config*=None)

Bases: `SingleCommDevice`

Base class for Cube variants.

OPC_MAX_YEAR = 2089

OPC_MIN_YEAR = 1990

active_alarms(*human_readable*: bool = True) → list[int | str]

Displays all active alarms / messages.

Parameters

human_readable – True for human readable message, False for corresponding integer

Returns

list with active alarms

property `breakdown_detection_active`: bool

Get the state of the breakdown detection functionality. Returns True if it is enabled, False otherwise.

Returns

state of the breakdown detection functionality

breakdown_detection_reset() → None

Reset the breakdown detection circuitry so that it is ready to detect breakdowns again.

property `breakdown_detection_triggered`: bool

See if breakdown detection unit has been triggered. Returns True if it is triggered, False otherwise.

Returns

trigger status of the breakdown detection unit

property cee16_socket

Read the on-state of the IEC CEE16 three-phase power socket.

Returns

the on-state of the CEE16 power socket

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

classmethod datetime_to_opc(time_dt: datetime) → list[int]

Converts python datetime format into opc format (list of 8 integers) as defined in the following link: <https://support.industry.siemens.com/cs/mdm/109798671?c=133950752267&lc=de-WW> Each byte corresponds to one list entry. [yy, MM, dd, hh, mm, ss, milliseconds, weekday] Milliseconds and Weekday are not used, as this precision / information is not needed. The conversion of the numbers is special. Each decimal number is treated as it would be a hex-number and then converted back to decimal. This is tested with the used PLC in the BaseCube. yy: 0 to 99 (0 -> 2000, 89 -> 2089, 90 -> 1990, 99 -> 1999) MM: 1 to 12 dd: 1 to 31 hh: 0 to 23 mm: 0 to 59 ss: 0 to 59

Parameters

time_dt – time to be converted

Returns

time in opc list format

static default_com_cls()

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

display_message_board() → None

Display 15 newest messages

display_status_board() → None

Display status board.

door_1_status

Get the status of a safety fence door. See constants.DoorStatus for possible returned door statuses.

door_2_status

Get the status of a safety fence door. See constants.DoorStatus for possible returned door statuses.

door_3_status

Get the status of a safety fence door. See constants.DoorStatus for possible returned door statuses.

earthing_rod_1_status

Get the status of a earthing rod. See constants.EarthingRodStatus for possible returned earthing rod statuses.

earthing_rod_2_status

Get the status of a earthing rod. See constants.EarthingRodStatus for possible returned earthing rod statuses.

earthing_rod_3_status

Get the status of a earthing rod. See constants.EarthingRodStatus for possible returned earthing rod statuses.

property operate: `bool` | *None*

Indicates if ‘operate’ is activated. ‘operate’ means locket safety circuit, red lamps, high voltage on and locked safety switches.

Returns

True if operate is activated (RED_OPERATE), *False* if ready is deactivated (RED_READY),
None otherwise

quit_error() → *None*

Quits errors that are active on the Cube.

read(node_id: str)

Local wrapper for the OPC UA communication protocol read method.

Parameters

node_id – the id of the node to read.

Returns

the value of the variable

property ready: `bool` | *None*

Indicates if ‘ready’ is activated. ‘ready’ means locket safety circuit, red lamps, but high voltage still off.

Returns

True if ready is activated (RED_READY), *False* if ready is deactivated (GREEN_READY),
None otherwise

set_message_board(msgs: list[str], display_board: bool = True) → None

Fills messages into message board that display that 15 newest messages with a timestamp.

Parameters

- **msgs** – list of strings
- **display_board** – display 15 newest messages if *True* (default)

Raises

ValueError – if there are too many messages or the positions indices are invalid.

set_status_board(msgs: list[str], pos: list[int] | None = None, clear_board: bool = True, display_board: bool = True) → None

Sets and displays a status board. The messages and the position of the message can be defined.

Parameters

- **msgs** – list of strings
- **pos** – list of integers [0...14]
- **clear_board** – clear unspecified lines if *True* (default), keep otherwise
- **display_board** – display new status board if *True* (default)

Raises

ValueError – if there are too many messages or the positions indices are invalid.

start() → *None*

Starts the device. Sets the root node for all OPC read and write commands to the Siemens PLC object node which holds all our relevant objects and variables.

property status: *SafetyStatus*

Get the safety circuit status of the Cube. This methods is for the user.

Returns

the safety status of the Cube's state machine.

stop() → *None*

Stop the Cube device. Deactivates the remote control and closes the communication protocol.

Raises

CubeStopError – when the cube is not in the correct status to stop the operation

t13_socket_1

Set and get the state of a SEV T13 power socket.

t13_socket_2

Set and get the state of a SEV T13 power socket.

t13_socket_3

Set and get the state of a SEV T13 power socket.

write(node_id, value) → *None*

Local wrapper for the OPC UA communication protocol write method.

Parameters

- **node_id** – the id of the node to write
- **value** – the value to write to the variable

```
class BaseCubeConfiguration(namespace_index: int = 3, polling_delay_sec: int | float = 5.0,  
                             polling_interval_sec: int | float = 1.0, timeout_status_change: int | float = 6,  
                             timeout_interval: int | float = 0.1, noise_level_measurement_channel_1: int |  
                             float = 100, noise_level_measurement_channel_2: int | float = 100,  
                             noise_level_measurement_channel_3: int | float = 100,  
                             noise_level_measurement_channel_4: int | float = 100)
```

Bases: object

Configuration dataclass for the BaseCube devices.

clean_values()

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

namespace_index: `int = 3`

Namespace of the OPC variables, typically this is 3 (coming from Siemens)

noise_level_measurement_channel_1: `int | float = 100`

noise_level_measurement_channel_2: `int | float = 100`

noise_level_measurement_channel_3: `int | float = 100`

noise_level_measurement_channel_4: `int | float = 100`

classmethod optional_defaults() `→ dict[str, object]`

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

polling_delay_sec: `int | float = 5.0`

polling_interval_sec: `int | float = 1.0`

classmethod required_keys() `→ Sequence[str]`

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

timeout_interval: `int | float = 0.1`

timeout_status_change: `int | float = 6`

class BaseCubeOpcUaCommunication(*config*)

Bases: *OpcUaCommunication*

Communication protocol specification for BaseCube devices.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class BaseCubeOpcUaCommunicationConfig(host: str | ~ipaddress.IPv4Address | ~ipaddress.IPv6Address,
endpoint_name: ~hvl_ccb.dev.cube.constants._CubeOpcEndpoint
= _CubeOpcEndpoint.BASE_CUBE, port: int = 4840,
sub_handler: ~hvl_ccb.comm.opc.OpcUaSubHandler =
<hvl_ccb.dev.cube.base._BaseCubeSubscriptionHandler object>,
update_parameter:
~asyncua.ua.uaprotoocol_auto.CreateSubscriptionParameters =
CreateSubscriptionParameters(RequestedPublishingInterval=1000,
RequestedLifetimeCount=300,
RequestedMaxKeepAliveCount=22,
MaxNotificationsPerPublish=10000, PublishingEnabled=True,
Priority=0), wait_timeout_retry_sec: int | float = 1,
max_timeout_retry_nr: int = 5)
```

Bases: *OpcUaCommunicationConfig*

Communication protocol configuration for OPC UA, specifications for the BaseCube devices.

endpoint_name: `_CubeOpcEndpoint = 'BaseCube'`

Endpoint of the OPC server, this is a path like 'OPCUA/SimulationServer'

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod **keys**() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod **optional_defaults**() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod **required_keys**() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

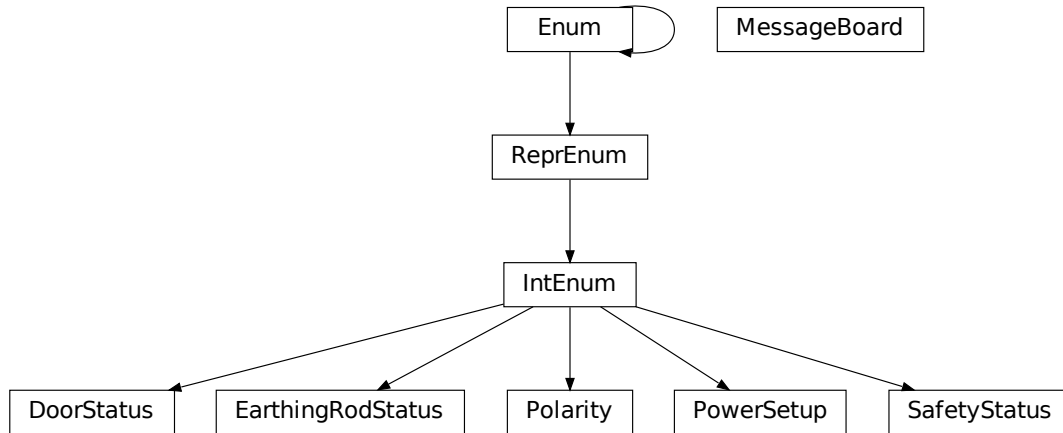
Returns

a list of strings containing all required keys.

sub_handler: *OpcUaSubHandler* = `<hvl_ccb.dev.cube.base._BaseCubeSubscriptionHandler object>`

Subscription handler for data change events

hvl_ccb.dev.cube.constants



Constants, variable names for the BaseCube OPC-connected devices.

```
class DoorStatus(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                  boundary=None)
```

Bases: IntEnum

Possible status values for doors.

CLOSED = 2

Door is closed, but not locked.

ERROR = 4

Door has an error or was opened in locked state (either with emergency stop or from the inside).

INACTIVE = 0

not enabled in BaseCube HMI setup, this door is not supervised.

LOCKED = 3

Door is closed and locked (safe state).

OPEN = 1

Door is open.

```
class EarthingRodStatus(value=<no_arg>, names=None, module=None, qualname=None, type=None,
                          start=1, boundary=None)
```

Bases: IntEnum

Possible status values for earthing rods.

EXPERIMENT_BLOCKED = 0

earthing rod is somewhere in the experiment and blocks the start of the experiment

EXPERIMENT_READY = 1

earthing rod is hanging next to the door, experiment is ready to operate

```
class MessageBoard(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,  
                  boundary=None)
```

Bases: `_LineEnumBase`

Variable NodeID strings for message board lines.

```
LINE_1 = "DB_OPC_Connection"."Is_status_Line_1"  
LINE_10 = "DB_OPC_Connection"."Is_status_Line_10"  
LINE_11 = "DB_OPC_Connection"."Is_status_Line_11"  
LINE_12 = "DB_OPC_Connection"."Is_status_Line_12"  
LINE_13 = "DB_OPC_Connection"."Is_status_Line_13"  
LINE_14 = "DB_OPC_Connection"."Is_status_Line_14"  
LINE_15 = "DB_OPC_Connection"."Is_status_Line_15"  
LINE_2 = "DB_OPC_Connection"."Is_status_Line_2"  
LINE_3 = "DB_OPC_Connection"."Is_status_Line_3"  
LINE_4 = "DB_OPC_Connection"."Is_status_Line_4"  
LINE_5 = "DB_OPC_Connection"."Is_status_Line_5"  
LINE_6 = "DB_OPC_Connection"."Is_status_Line_6"  
LINE_7 = "DB_OPC_Connection"."Is_status_Line_7"  
LINE_8 = "DB_OPC_Connection"."Is_status_Line_8"  
LINE_9 = "DB_OPC_Connection"."Is_status_Line_9"
```

```
class Polarity(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,  
              boundary=None)
```

Bases: `IntEnum`

An enumeration.

```
NEGATIVE = 0
```

```
POSITIVE = 1
```

```
class PowerSetup(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,  
                boundary=None)
```

Bases: `IntEnum`

Possible power setups corresponding to the value of variable `Power.setup`. The values for `slope_min` are experimentally defined, below these values the slope is more like a staircase

The name of the first argument needs to be 'value', otherwise the `IntEnum` is not working correctly.

```
AC_100KV = 3
```

```
AC_150KV = 4
```

```
AC_200KV = 5
```

AC_50KV = 2

DC_140KV = 7

DC_280KV = 8

EXTERNAL_SOURCE = 1

IMPULSE_140KV = 9

NO_SOURCE = 0

POWER_INVERTER_220V = 6

STOP_SAFETY_STATUSES: tuple[[SafetyStatus](#), ...] = (SafetyStatus.GREEN_NOT_READY, SafetyStatus.GREEN_READY)

BaseCube's safety statuses required to close the connection to the device.

class [SafetyStatus](#)(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: IntEnum

Safety status values that are possible states returned from [hvl_ccb.dev.cube.base.BaseCube.status\(\)](#). These values correspond to the states of the BaseCube's safety circuit statemachine.

ERROR = 6

GREEN_NOT_READY = 1

GREEN_READY = 2

INITIALIZING = 0

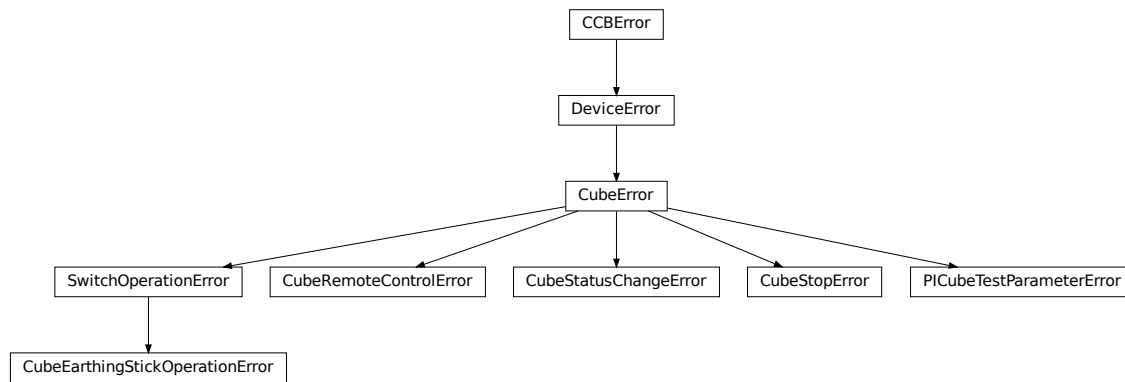
QUICK_STOP = 5

RED_OPERATE = 4

RED_READY = 3

[hvl_ccb.dev.cube.earthing_stick](#)

EarthingStick of the different "Cubes".

hvl_ccb.dev.cube.errors

Errors of the different “Cubes”.

exception CubeEarthingStickOperationError

Bases: *SwitchOperationError*

exception CubeError

Bases: *DeviceError*

exception CubeRemoteControlError

Bases: *CubeError*

exception CubeStatusChangeError

Bases: *CubeError*

exception CubeStopError

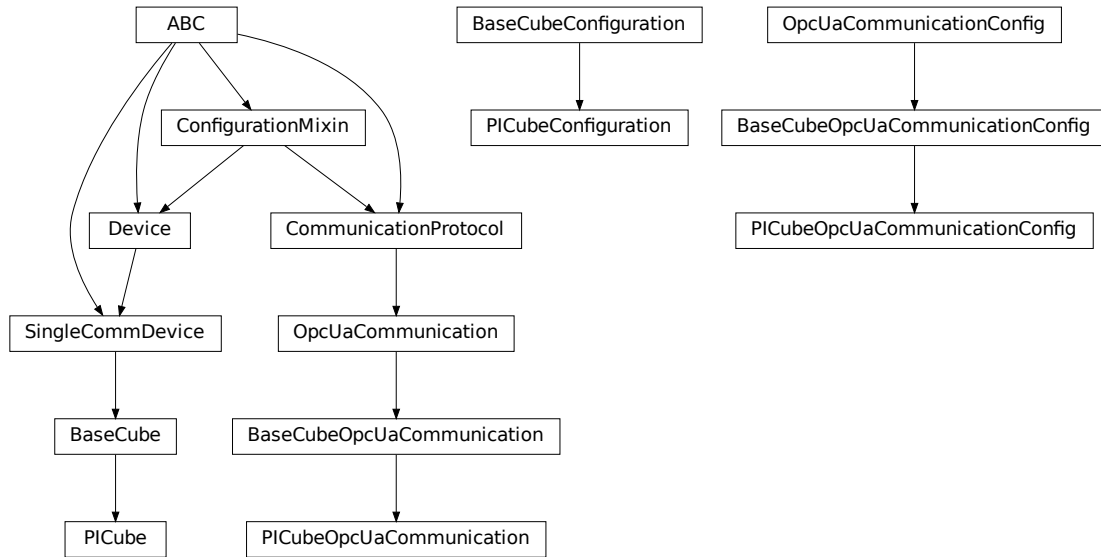
Bases: *CubeError*

exception PICubeTestParameterError

Bases: *CubeError*

exception SwitchOperationError

Bases: *CubeError*

hvl_ccb.dev.cube.picube

A PICube is a BaseCube with build in Power Inverter

class `PICube`(*com*, *dev_config=None*)

Bases: `BaseCube`

Variant of the BaseCube with build in Power Inverter

static `config_cls()`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

property `current_primary: float`

Read the current primary current at the output of the frequency converter (before transformer).

Returns

primary current in A

static `default_com_cls()`

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

property `frequency: float`

Read the electrical frequency of the current PICube setup.

Returns

the frequency in Hz

property `operate: bool | None`

Indicates if 'operate' is activated. 'operate' means locket safety circuit, red lamps, high voltage on and locked safety switches.

Returns

True if operate is activated (RED_OPERATE), *False* if ready is deactivated (RED_READY),
None otherwise

property polarity: *Polarity* | *None*

Polarity of a DC setup. :return: if a DC setup is programmed the polarity is returned, else None.

property power_setup: *PowerSetup*

Return the power setup selected in the PICube's settings.

Returns

the power setup

property voltage_actual: *float*

Reads the actual measured voltage and returns the value in V.

Returns

the actual voltage of the setup in V.

property voltage_max: *float*

Reads the maximum voltage of the setup and returns in V.

Returns

the maximum voltage of the setup in V.

property voltage_primary: *float*

Read the current primary voltage at the output of the frequency converter (before transformer).

Returns

primary voltage in V

```
class PICubeConfiguration(namespace_index: int = 3, polling_delay_sec: int | float = 5.0,  
                           polling_interval_sec: int | float = 1.0, timeout_status_change: int | float = 6,  
                           timeout_interval: int | float = 0.1, noise_level_measurement_channel_1: int | float  
                           = 100, noise_level_measurement_channel_2: int | float = 100,  
                           noise_level_measurement_channel_3: int | float = 100,  
                           noise_level_measurement_channel_4: int | float = 100, timeout_test_parameters:  
                           'Number' = 2.0)
```

Bases: *BaseCubeConfiguration*

clean_values()

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

timeout_test_parameters: int | float = 2.0

class PICubeOpcUaCommunication(config)

Bases: [BaseCubeOpcUaCommunication](#)

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

class PICubeOpcUaCommunicationConfig(host: Union[str, ipaddress.IPv4Address, ipaddress.IPv6Address], endpoint_name: '_CubeOpcEndpoint' = <_CubeOpcEndpoint.PI_CUBE: 'PICube'>, port: int = 4840, sub_handler: hvl_ccb.comm.opc.OpcUaSubHandler = <hvl_ccb.dev.cube.base._BaseCubeSubscriptionHandler object at 0x7ff8d710b8b0>, update_parameter: asyncua.ua.uaprotoocol_auto.CreateSubscriptionParameters = CreateSubscriptionParameters(RequestedPublishingInterval=1000, RequestedLifetimeCount=300, RequestedMaxKeepAliveCount=22, MaxNotificationsPerPublish=10000, PublishingEnabled=True, Priority=0), wait_timeout_retry_sec: Union[int, float] = 1, max_timeout_retry_nr: int = 5)

Bases: [BaseCubeOpcUaCommunicationConfig](#)

endpoint_name: _CubeOpcEndpoint = 'PICube'

Endpoint of the OPC server, this is a path like 'OPCUA/SimulationServer'

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod `optional_defaults()` → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod `required_keys()` → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

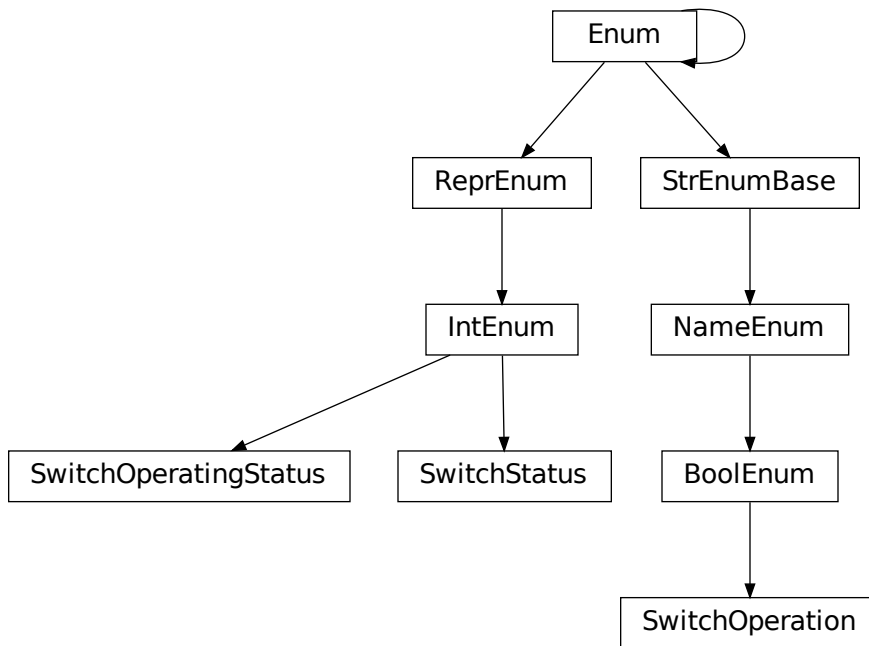
Returns

a list of strings containing all required keys.

`hvl_ccb.dev.cube.support`

Supports of the different “Cubes”.

`hvl_ccb.dev.cube.switches`



the different “Cubes”.

Switches of

class `SwitchOperatingStatus`(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: `IntEnum`

Operating Status of a switch. Switch can be in auto or manual mode.

AUTO = 0

MANUAL = 1

class SwitchOperation(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: *BoolEnum*

Operation of a switch in manual operating mode. Can be closed or opened.

CLOSE = True

OPEN = False

class SwitchStatus(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: *IntEnum*

Status of a switch. These are the possible values in the status integer e.g. in `_Switch.status`.

CLOSED = 1

ERROR = 3

INACTIVE = 0

OPEN = 2

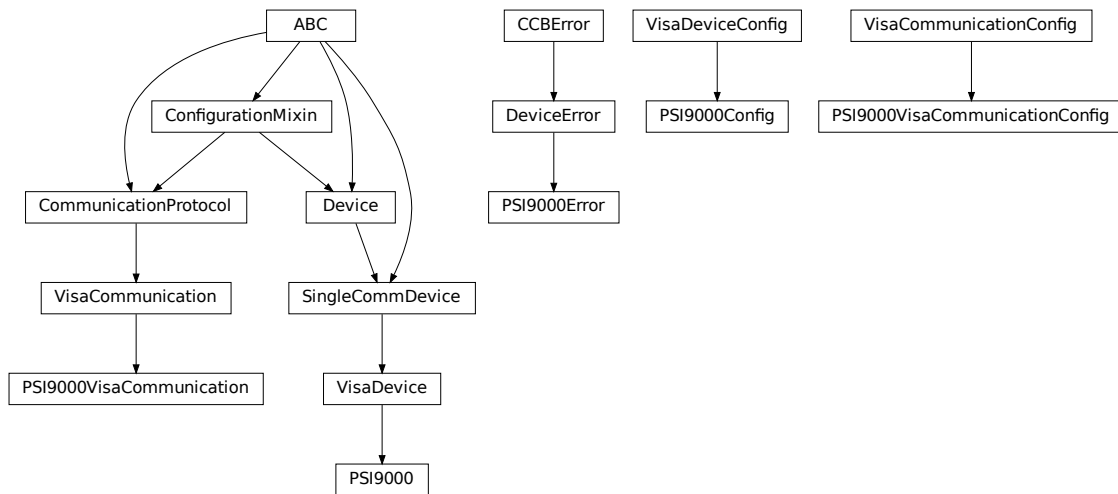
Module contents

Cube package with implementation for system versions from 2019 on (new concept with hard-PLC Siemens S7-1500 as CPU).

hvl_ccb.dev.ea_psi9000

Submodules

hvl_ccb.dev.ea_psi9000.ea_psi9000



Device class for controlling a Elektro Automatik PSI 9000 power supply over VISA.

It is necessary that a backend for pyvisa is installed. This can be NI-Visa oder pyvisa-py (up to now, all the testing was done with NI-Visa)

```
class PSI9000(com: PSI9000VisaCommunication | PSI9000VisaCommunicationConfig | dict, dev_config:
    PSI9000Config | dict | None = None)
```

Bases: [VisaDevice](#)

Elektro Automatik PSI 9000 power supply.

MS_NOMINAL_CURRENT = 2040

MS_NOMINAL_VOLTAGE = 80

SHUTDOWN_CURRENT_LIMIT = 0.1

SHUTDOWN_VOLTAGE_LIMIT = 0.1

check_master_slave_config() → *None*

Checks if the master / slave configuration and initializes if successful

Raises

[PSI9000Error](#) – if master-slave configuration failed

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

Return the default communication protocol for this device type, which is VisaCommunication.

Returns

the VisaCommunication class

get_output() → bool

Reads the current state of the DC output of the source. Returns True, if it is enabled, false otherwise.

Returns

the state of the DC output

get_system_lock() → bool

Get the current lock state of the system. The lock state is true, if the remote control is active and false, if not.

Returns

the current lock state of the device

get_ui_lower_limits() → tuple[float, float]

Get the lower voltage and current limits. A lower power limit does not exist.

Returns

Umin in V, Imin in A

get_uip_upper_limits() → tuple[float, float, float]

Get the upper voltage, current and power limits.

Returns

Umax in V, Imax in A, Pmax in W

get_voltage_current_setpoint() → tuple[float, float]

Get the voltage and current setpoint of the current source.

Returns

Uset in V, Iset in A

measure_voltage_current() → tuple[float, float]

Measure the DC output voltage and current

Returns

Umeas in V, Imeas in A

set_lower_limits(*voltage_limit: float | None = None, current_limit: float | None = None*) → *None*

Set the lower limits for voltage and current. After writing the values a check is performed if the values are set correctly.

Parameters

- **voltage_limit** – is the lower voltage limit in V
- **current_limit** – is the lower current limit in A

Raises

PSI9000Error – if the limits are out of range

set_output(*target_onstate: bool*) → *None*

Enables / disables the DC output.

Parameters

target_onstate – enable or disable the output power

Raises

PSI9000Error – if operation was not successful

set_system_lock(*lock: bool*) → *None*

Lock / unlock the device, after locking the control is limited to this class unlocking only possible when voltage and current are below the defined limits

Parameters

lock – True: locking, False: unlocking

set_upper_limits(*voltage_limit: float | None = None, current_limit: float | None = None, power_limit: float | None = None*) → *None*

Set the upper limits for voltage, current and power. After writing the values a check is performed if the values are set. If a parameter is left blank, the maximum configurable limit is set.

Parameters

- **voltage_limit** – is the voltage limit in V
- **current_limit** – is the current limit in A
- **power_limit** – is the power limit in W

Raises

PSI9000Error – if limits are out of range

set_voltage_current(*volt: float, current: float*) → *None*

Set voltage and current setpoints.

After setting voltage and current, a check is performed if writing was successful.

Parameters

- **volt** – is the setpoint voltage: 0..81.6 V (1.02 * 0-80 V) (absolute max, can be smaller if limits are set)
- **current** – is the setpoint current: 0..2080.8 A (1.02 * 0 - 2040 A) (absolute max, can be smaller if limits are set)

Raises

PSI9000Error – if the desired setpoint is out of limits

start() → *None*

Start this device.

stop() → *None*

Stop this device. Turns off output and lock, if enabled.

```
class PSI9000Config(spoll_interval: int | float = 0.5, spoll_start_delay: int | float = 2, power_limit: int | float = 43500, voltage_lower_limit: int | float = 0.0, voltage_upper_limit: int | float = 10.0, current_lower_limit: int | float = 0.0, current_upper_limit: int | float = 2040.0, wait_sec_system_lock: int | float = 0.5, wait_sec_settings_effect: int | float = 1, wait_sec_initialisation: int | float = 2)
```

Bases: *VisaDeviceConfig*

Elektro Automatik PSI 9000 power supply device class. The device is communicating over a VISA TCP socket.

Using this power supply, DC voltage and current can be supplied to a load with up to 2040 A and 80 V (using all four available units in parallel). The maximum power is limited by the grid, being at 43.5 kW available through the CEE63 power socket.

clean_values() → *None*

Cleans and enforces configuration values. Does nothing by default, but may be overridden to add custom configuration value checks.

current_lower_limit: `int | float = 0.0`

Lower current limit in A, depending on the experimental setup.

current_upper_limit: `int | float = 2040.0`

Upper current limit in A, depending on the experimental setup.

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

power_limit: `int | float = 43500`

Power limit in W depending on the experimental setup. With 3x63A, this is 43.5kW. Do not change this value, if you do not know what you are doing. There is no lower power limit.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

voltage_lower_limit: `int | float = 0.0`

Lower voltage limit in V, depending on the experimental setup.

voltage_upper_limit: `int | float = 10.0`

Upper voltage limit in V, depending on the experimental setup.

wait_sec_initialisation: `int | float = 2`

wait_sec_settings_effect: `int | float = 1`

wait_sec_system_lock: `int | float = 0.5`

exception PSI9000Error

Bases: *DeviceError*

Base error class regarding problems with the PSI 9000 supply.

class PSI9000VisaCommunication(configuration)

Bases: *VisaCommunication*

Communication protocol used with the PSI 9000 power supply.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class PSI9000VisaCommunicationConfig(host: str | IPv4Address | IPv6Address, interface_type: str |  
                                     InterfaceType = InterfaceType.TCPIP_SOCKET, board: int = 0,  
                                     port: int = 5025, timeout: int = 5000, chunk_size: int = 204800,  
                                     open_timeout: int = 1000, write_termination: str = '\n',  
                                     read_termination: str = '\n', visa_backend: str = "")
```

Bases: *VisaCommunicationConfig*

Visa communication protocol config dataclass with specification for the PSI 9000 power supply.

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

```
interface_type: str | InterfaceType = 1
```

Interface type of the VISA connection, being one of *InterfaceType*.

```
classmethod keys() → Sequence[str]
```

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

```
classmethod optional_defaults() → dict[str, object]
```

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

```
classmethod required_keys() → Sequence[str]
```

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

clear_display_message() → *None*

Page 59

Clears the displayed message on the Meter's display.

clear_error_queue() → *None*

Page 62

Sets all bits to zero in the Meter's status byte register and all event registers. Also clears the error queue

static config_cls() → type[*Fluke8845aConfig*]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

current_filter

dc_current_range

dc_voltage_range

static default_com_cls() → type[*Fluke8845aTelnetCommunication*]

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

property display_enable: bool

Page 59

get if the display is enabled or not fluke answer string "1" for ON and "0" for off bool(int("1")) = 1 and bool(int("0")) = 0

Returns

bool enabled = True, else False

property display_message: str

Page 59

Retrieves the text sent to the Meter's display.

fetch() → float

Page 36

Transfer stored readings to output buffer

four_wire_resistance_range

frequency_aperture

property identification: str

Page 60

Queries "*IDN?" and returns the identification string of the connected device.

Returns

the identification string of the connected device e.g. "FLUKE, 8845A, 2540017, 08/02/10-11:53"

initiate_trigger() → *None*

Set trigger system to wait-for-trigger

measure() → float

Page 42

Taking measurement

Once the Meter has been configured for a measurement, the INITiate command causes the Meter to take a measurement when the trigger condition have been met. To process readings from the Meter's internal memory to the output buffer, send the Meter a FETCh? command.

property measurement_function: *MeasurementFunction*

input_function getter, query what the input function is

Raises

Fluke8845aUnknownCommandError – if the input function is unknown

period_aperture

reset() → *None*

Page 60

resets the meter to its power-up configuration

start() → *None*

Start this device as recommended by the manual

stop() → *None*

Stop this device. Disables access and closes the communication protocol.

trigger() → *None*

Causes the meter to trigger a measurement when paused

property trigger_delay: int

input_trigger_delay getter, query what the input trigger delay is in second answer format from Fluke: string, '+1.00000000E+00', so convert to float and then to int

Returns

input trigger delay in second

property trigger_source: *TriggerSource*

input_trigger_source getter, query what the input trigger source is

Raises

Fluke8845aUnknownCommandError – if the input trigger source is unknown

two_wire_resistance_range

voltage_filter

class Fluke8845aConfig(name: str = 'Fluke I')

Bases: object

Config for Fluke8845a

name: the name of the device

clean_values()

Cleans and enforces configuration values. Does nothing by default, but may be overridden to add custom configuration value checks.

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

name: str = 'Fluke 1'

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

class Fluke8845aTelnetCommunication(*configuration*)

Bases: *TelnetCommunication*, *SyncCommunicationProtocol*

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

query(*command*: str, *n_attempts_max*: int | None = None, *attempt_interval_sec*: int | float | None = None)

→ str

Send a command to the interface and handle the status message. Eventually raises an error.

Parameters

- **command** – Command to send
- **n_attempts_max** – Amount of attempts how often a non-empty text is tried to be read as answer
- **attempt_interval_sec** – time between the reading attempts

Raises

Fluke8845aError – if the connection is broken

Returns

Answer from the interface

```
class Fluke8845aTelnetCommunicationConfig(terminator: bytes = b'\r', encoding: str = 'utf-8',
                                         encoding_error_handling: str = 'strict',
                                         wait_sec_read_text_nonempty: int | float = 0.5,
                                         default_n_attempts_read_text_nonempty: int = 10, host: str |
                                         ipaddress.IPv4Address | ipaddress.IPv6Address | NoneType =
                                         None, port: int = 3490, timeout: int | float = 0.2)
```

Bases: *TelnetCommunicationConfig*

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

port: int = 3490

Port at which Fluke 8845a is listening

classmethod required_keys() → Sequence[str]

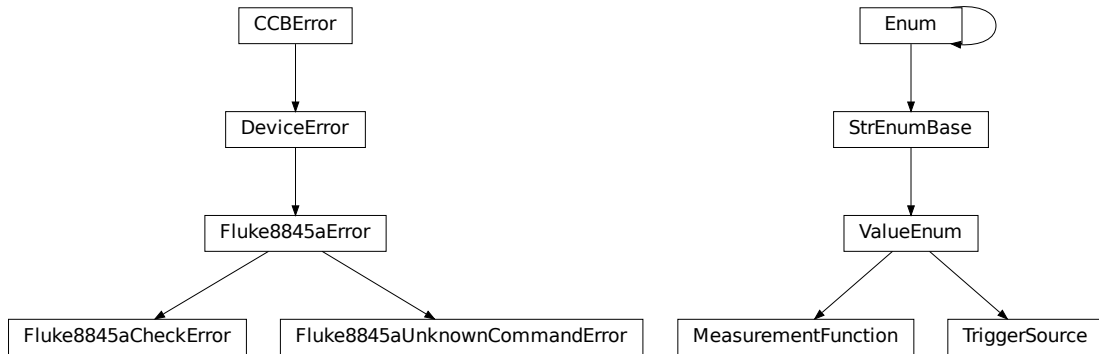
Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

terminator: bytes = b'\r'

The terminator is CR

hvl_ccb.dev.fluke884x.constants

Constants, ValueEnum: MeasurementFunction and TriggerSource Descriptors for range, filter and aperture

exception Fluke8845aCheckError

Bases: [Fluke8845aError](#)

exception Fluke8845aError

Bases: [DeviceError](#)

exception Fluke8845aUnknownCommandError

Bases: [Fluke8845aError](#)

class MeasurementFunction(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: [ValueEnum](#)

Page 40

Sets the Meter function. This command must be followed by the INIT and FETCh? commands to cause the meter to take a measurement.

CURRENT_AC = 'CURR:AC'

CURRENT_DC = 'CURR'

DIODE = 'DIOD'

FOUR_WIRE_RESISTANCE = 'FRES'

FREQUENCY = 'FREQ'

PERIOD = 'PER'

TWO_WIRE_RESISTANCE = 'RES'

VOLTAGE_AC = 'VOLT:AC'

VOLTAGE_DC = 'VOLT'

```
class TriggerSource(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                    boundary=None)
```

Bases: *ValueEnum*

Page 57

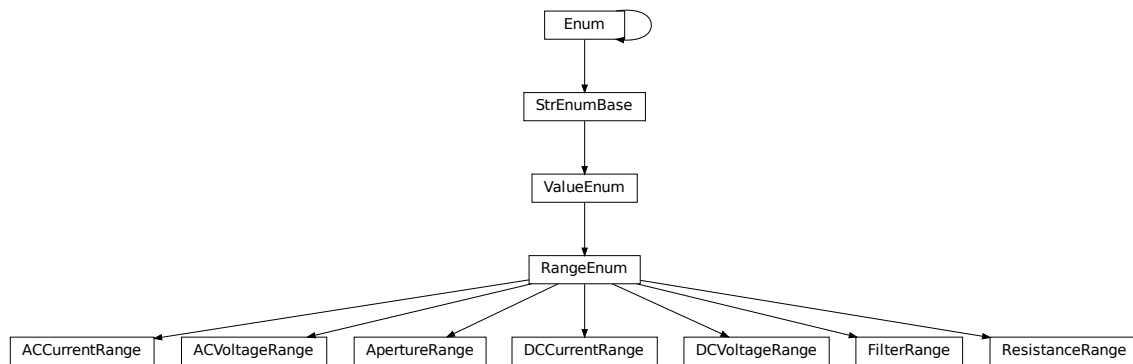
BUS: Sets the Meter to expect a trigger through the IEEE-488 bus or upon execution of a *TRG command
 IMM: Selects Meter's internal triggering system
 EXT: Sets the Meter to sense triggers through the trigger jack on the rear panel of the Meter

BUS = 'BUS'

EXTERNAL = 'EXT'

IMMEDIATE = 'IMM'

hvl_ccb.dev.fluke884x.ranges



Ranges, RangeEnum for Fluke8845a device

```
class ACCurrentRange(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                    boundary=None)
```

Bases: *RangeEnum*

possible measurement ranges for AC current with unit Ampere

FOUR_HUNDRED_MILLI_AMPERE = 0.4

ONE_AMPERE = 1.0

ONE_HUNDRED_MILLI_AMPERE = 0.1

TEN_AMPERE = 10.0

TEN_MILLI_AMPERE = 0.01

THREE_AMPERE = 3.0

```
class ACVoltageRange(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                    boundary=None)
```

Bases: [RangeEnum](#)

possible measurement ranges for AC voltage with unit volt

```
HUNDRED_VOLT = 100.0
```

```
ONE_HUNDRED_MILLI_VOLT = 0.1
```

```
ONE_VOLT = 1.0
```

```
SEVEN_HUNDRED_FIFTY_VOLT = 750.0
```

```
TEN_VOLT = 10.0
```

```
class ApertureRange(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                    boundary=None)
```

Bases: [RangeEnum](#)

Page 46

Sets the gate time for the frequency/period function to the value

10ms = 4 1/2 digits

100ms = 5 1/2 digits

1s = 6 1/2 digits

```
ONE_HUNDRED_MILLI_SECOND = 0.1
```

```
ONE_SECOND = 1.0
```

```
TEN_MILLI_SECOND = 0.01
```

```
class DCCurrentRange(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                    boundary=None)
```

Bases: [RangeEnum](#)

possible measurement ranges for DC current with unit Ampere

```
FOUR_HUNDRED_MILLI_AMPERE = 0.4
```

```
ONE_AMPERE = 1.0
```

```
ONE_HUNDRED_MICRO_AMPERE = 0.0001
```

```
ONE_HUNDRED_MILLI_AMPERE = 0.1
```

```
ONE_MILLI_AMPERE = 0.001
```

```
TEN_AMPERE = 10.0
```

```
TEN_MILLI_AMPERE = 0.01
```

```
THREE_AMPERE = 3.0
```

```
class DCVoltageRange(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                    boundary=None)
```

Bases: [RangeEnum](#)

possible measurement ranges for DC voltage with unit volt

```
HUNDRED_VOLT = 100.0
```

```
ONE_HUNDRED_MILLI_VOLT = 0.1
```

```
ONE_THOUSAND_VOLT = 1000.0
```

```
ONE_VOLT = 1.0
```

```
TEN_VOLT = 10.0
```

```
class FilterRange(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                  boundary=None)
```

Bases: [RangeEnum](#)

Page 47

```
Sets the appropriate filter for the frequency specified by <n>
High pass filter
For `VOLTAGE_AC`: <n> Hz to 300 kHz
For `CURRENT_AC`: <n> Hz to 10 kHz
parameters <n> = 3 slow filter
                  20 medium filter
                  200 fast filter
For `CURRENT_AC` and `VOLTAGE_AC`
```

```
FAST_FILTER = 200.0
```

```
MEDIUM_FILTER = 20.0
```

```
SLOW_FILTER = 3.0
```

```
class ResistanceRange(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                      boundary=None)
```

Bases: [RangeEnum](#)

possible measurement ranges for resistance with unit Ohm

```
ONE_HUNDRED_MILLION_OHM = 100000000.0
```

```
ONE_HUNDRED_OHM = 100.0
```

```
ONE_HUNDRED_THOUSAND_OHM = 100000.0
```

```
ONE_MILLION_OHM = 1000000.0
```

```
ONE_THOUSAND_OHM = 1000.0
```

```
TEN_MILLION_OHM = 10000000.0
```

```
TEN_THOUSAND_OHM = 10000.0
```


Returns**property di:** *FuGProbusVDIRegisters*

Returns the registers for the digital inputs

Returns

FuGProbusVDIRegisters

identify_device() → *None*

Identify the device nominal voltage and current based on its model number.

Raises*SerialCommunicationIOError* – when communication port is not opened**property max_current:** *int | float*

Returns the maximal current which could provided within the test setup

Returns**property max_current_hardware:** *int | float*

Returns the maximal current which could provided with the power supply

Returns**property max_voltage:** *int | float*

Returns the maximal voltage which could provided within the test setup

Returns**property max_voltage_hardware:** *int | float*

Returns the maximal voltage which could provided with the power supply

Returns**property on:** *FuGProbusVDORegisters*

Returns the registers for the output switch to turn the output on or off

Returns

FuGProbusVDORegisters

property outX0: *FuGProbusVDORegisters*

Returns the registers for the digital output X0

Returns

FuGProbusVDORegisters

property outX1: *FuGProbusVDORegisters*

Returns the registers for the digital output X1

Returns

FuGProbusVDORegisters

property outX2: *FuGProbusVDORegisters*

Returns the registers for the digital output X2

Returns

FuGProbusVDORegisters

property outXCMD: *FuGProbusVDORegisters*

Returns the registers for the digital outputX-CMD

Returns

FuGProbusVDORegisters

start(*max_voltage=0, max_current=0*) → *None*

Opens the communication protocol and configures the device.

Parameters

- **max_voltage** – Configure here the maximal permissible voltage which is allowed in the given experimental setup
- **max_current** – Configure here the maximal permissible current which is allowed in the given experimental setup

property voltage: *FuGProbusVSetRegisters*

Returns the registers for the voltage output

Returns

property voltage_monitor: *FuGProbusVMonitorRegisters*

Returns the registers for the voltage monitor.

A typically usage will be “self.voltage_monitor.value” to measure the output voltage

Returns

class FuGConfig(*wait_sec_stop_commands: int | float = 0.5*)

Bases: object

Device configuration dataclass for FuG power supplies.

clean_values()

force_value(*fieldname, value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

wait_sec_stop_commands: int | float = 0.5

Time to wait after subsequent commands during stop (in seconds)

class FuGDigitalVal(value)

Bases: IntEnum

An enumeration.

NO = 0

OFF = 0

ON = 1

YES = 1

exception FuGError(*args, **kwargs)

Bases: *DeviceError*

Error with the FuG voltage source.

errorcode: str

Errorcode from the Probus, see documentation of Probus V chapter 5. Errors with three-digit errorcodes are thrown by this python module.

class FuGErrorcodes(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: *NameEnum*

The power supply can return an errorcode. These errorcodes are handled by this class. The original errorcodes from the source are with one or two digits, see documentation of Probus V chapter 5. All three-digit errorcodes are from this python module.

E0 = ('no error', 'standard response on each command')

E1 = ('no data available', 'Customer tried to read from GPIB but there were no data prepared. (IBIG50 sent command ~T2 to ADDA)')

E10 = ('unknown SCPI command', 'This SCPI command is not implemented')

E100 = ('Command is not implemented', 'You tried to execute a command, which is not implemented or does not exist')

E106 = ('The rampstate is a read-only register', 'You tried to write data to the register, which can only give you the status of the ramping.')

E11 = ('not allowed Trigger-on-Talk', 'Not allowed attempt to Trigger-on-Talk (~T1) while ADDA was in addressable mode.')

E115 = ('The given index to select a digital value is out of range', 'Only integer values between 0 and 1 are allowed.')

E12 = ('invalid argument in ~Tn command', 'Only ~T1 and ~T2 is implemented.')

E125 = ('The given index to select a ramp mode is out of range', 'Only integer values between 0 and 4 are allowed.')

E13 = ('invalid N-value', 'Register > K8 contained an invalid value. Error code is output on an attempt to query data with ? or ~T1')

```
E135 = ('The given index to select the readback channel is out of range', 'Only
integer values between 0 and 6 are allowed.')

E14 = ('register is write only', 'Some registers can only be writte to (i.e.> H0)')

E145 = ('The given value for the AD-conversion is unknown', 'Valid values for the
ad-conversion are integer values from "0" to "7".')

E15 = ('string too long', 'i.e.serial number string too long during calibration')

E155 = ('The given value to select a polarity is out range.', 'The value should be 0
or 1.')

E16 = ('wrong checksum', 'checksum over command string was not correct, refer also
to 4.4 of the Probus V documentation')

E165 = ('The given index to select the terminator string is out of range', '')

E2 = ('unknown register type', "No valid register type after '>'")

E206 = ('This status register is read-only', 'You tried to write data to this
register, which can only give you the actual status of the corresponding digital
output.')

E306 = ('The monitor register is read-only', 'You tried to write data to a monitor,
which can only give you measured data.')

E4 = ('invalid argument', 'The argument of the command was rejected .i.e. malformed
number')

E5 = ('argument out of range', 'i.e. setvalue higher than type value')

E504 = ('Empty string as response', 'The connection is broken.')

E505 = ('The returned register is not the requested.', 'Maybe the connection is
overburden.')

E6 = ('register is read only', 'Some registers can only be read but not written to.
(i.e. monitor registers)')

E666 = ('You cannot overwrite the most recent error in the interface of the power
supply. But, well: You created an error anyway...', '')

E7 = ('Receive Overflow', 'Command string was longer than 50 characters.')

E8 = ('EEPROM is write protected', 'Write attempt to calibration data while the
write protection switch was set to write protected.')

E9 = ('address error', 'A non addressed command was sent to ADDA while it was in
addressable mode (and vice versa).')
```

```
raise_()
```

```
class FuGMonitorModes(value)
```

```
    Bases: IntEnum
```

```
    An enumeration.
```

T1MS = 1

15 bit + sign, 1 ms integration time

T200MS = 6

typ. 19 bit + sign, 200 ms integration time

T20MS = 3

17 bit + sign, 20 ms integration time

T256US = 0

14 bit + sign, 256 us integration time

T40MS = 4

17 bit + sign, 40 ms integration time

T4MS = 2

15 bit + sign, 4 ms integration time

T800MS = 7

typ. 20 bit + sign, 800 ms integration time

T80MS = 5

typ. 18 bit + sign, 80 ms integration time

class FuGPolarities(value)

Bases: `IntEnum`

An enumeration.

NEGATIVE = 1

POSITIVE = 0

class FuGProbusIV(com, dev_config=None)

Bases: `SingleCommDevice`, `ABC`

FuG Probus IV device class

Sends basic SCPI commands and reads the answer. Only the special commands and PROBUS IV instruction set is implemented.

command(*command*: `FuGProbusIVCommands`, *value*=None) → str

Parameters

- **command** – one of the commands given within `FuGProbusIVCommands`
- **value** – an optional value, depending on the command

Returns

a String if a query was performed

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

output_off() → *None*

Switch DC voltage output off.

reset() → *None*

Reset of the interface: All setvalues are set to zero

abstract start()

Open the associated communication protocol.

stop() → *None*

Close the associated communication protocol.

class FuGProbusIVCommands(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: *NameEnum*

An enumeration.

ADMODE = ('S', (<enum 'FuGMonitorModes'>, <class 'int'>))

CURRENT = ('I', (<class 'int'>, <class 'float'>))

EXECUTE = ('X', None)

EXECUTEONX = ('G', (<enum 'FuGDigitalVal'>, <class 'int'>))

Wait for “X” to execute pending commands

ID = ('*IDN?', None)

OUTPUT = ('F', (<enum 'FuGDigitalVal'>, <class 'int'>))

POLARITY = ('P', (<enum 'FuGPolarities'>, <class 'int'>))

QUERY = ('?', None)

READBACKCHANNEL = ('N', (<enum 'FuGReadbackChannels'>, <class 'int'>))

RESET = ('=', None)

TERMINATOR = ('Y', (<enum 'FuGTerminators'>, <class 'int'>))

VOLTAGE = ('U', (<class 'int'>, <class 'float'>))

XOUTPUTS = ('R', <class 'int'>)

TODO: the possible values are limited to 0..13

class FuGProbusV(com, dev_config=None)

Bases: *FuGProbusIV*

FuG Probus V class which uses register based commands to control the power supplies

get_register(*register: str*) → str

get the value from a register

Parameters

register – the register from which the value is requested

Returns

the value of the register as a String

set_register(*register: str, value: int | float | str*) → *None*

generic method to set value to register

Parameters

- **register** – the name of the register to set the value
- **value** – which should be written to the register

class **FuGProbusVConfigRegisters**(*fug, super_register: FuGProbusVRegisterGroups*)

Bases: object

Configuration and Status values, acc. 4.2.5

property **execute_on_x:** *FuGDigitalVal*

status of Execute-on-X

Returns

FuGDigitalVal of the status

property **most_recent_error:** *FuErrorcodes*

Reads the Error-Code of the most recent command

Return **FuGError**

Raises

FuGError – if code is not “E0”

property **readback_data:** *FuGReadbackChannels*

Preselection of readout data for Trigger-on-Talk

Returns

index for the readback channel

property **srq_mask:** **int**

SRQ-Mask, Service-Request Enable status bits for SRQ 0: no SRQ Bit 2: SRQ on change of status to CC
Bit 1: SRQ on change to CV

Returns

representative integer value

property **srq_status:** **str**

SRQ-Statusbyte output as a decimal number: Bit 2: PS is in CC mode Bit 1: PS is in CV mode

Returns

representative string

property **status:** **str**

Statusbyte as a string of 0/1. Combined status (compatibel to Probus IV), MSB first: Bit 7: I-REG Bit 6:
V-REG Bit 5: ON-Status Bit 4: 3-Reg Bit 3: X-Stat (polarity) Bit 2: Cal-Mode Bit 1: unused Bit 0: SEL-D

Returns

string of 0/1

property terminator: *FuGTerminators*

Terminator character for answer strings from ADDA

Returns

FuGTerminators

class FuGProbusVDIRegisters(*fug, super_register: FuGProbusVRegisterGroups*)

Bases: object

Digital Inputs acc. 4.2.4

property analog_control: *FuGDigitalVal*

Returns

shows 1 if power supply is controlled by the analog interface

property calibration_mode: *FuGDigitalVal*

Returns

shows 1 if power supply is in calibration mode

property cc_mode: *FuGDigitalVal*

Returns

shows 1 if power supply is in CC mode

property cv_mode: *FuGDigitalVal*

Returns

shows 1 if power supply is in CV mode

property digital_control: *FuGDigitalVal*

Returns

shows 1 if power supply is digitally controlled

property on: *FuGDigitalVal*

Returns

shows 1 if power supply ON

property reg_3: *FuGDigitalVal*

For special applications.

Returns

input from bit 3-REG

property x_stat: *FuGPolarities*

Returns

polarity of HVPS with polarity reversal

class FuGProbusVDORegisters(*fug, super_register: FuGProbusVRegisterGroups*)

Bases: object

Digital outputs acc. 4.2.2

property out: *int* | *FuGDigitalVal*

Status of the output according to the last setting. This can differ from the actual state if output should only pulse.

Returns

FuGDigitalVal

property status: *FuGDigitalVal*

Returns the actual value of output. This can differ from the set value if pulse function is used.

Returns

FuGDigitalVal

class FuGProbusVMonitorRegisters(*fug, super_register: FuGProbusVRegisterGroups*)

Bases: object

Analog monitors acc. 4.2.3

property adc_mode: *FuGMonitorModes*

The programmed resolution and integration time of the AD converter

Returns

FuGMonitorModes

property value: float

Value from the monitor.

Returns

a float value in V or A

property value_raw: float

uncalibrated raw value from AD converter

Returns

float value from ADC

class FuGProbusVRegisterGroups(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: *NameEnum*

An enumeration.

CONFIG = 'K'

INPUT = 'D'

MONITOR_I = 'M1'

MONITOR_V = 'M0'

OUTPUTONCMD = 'BON'

OUTPUTX0 = 'B0'

OUTPUTX1 = 'B1'

OUTPUTX2 = 'B2'

OUTPUTXCMD = 'BX'

SETCURRENT = 'S1'

SETVOLTAGE = 'S0'

class FuGProbusVSetRegisters(*fug, super_register: FuGProbusVRegisterGroups*)

Bases: object

Setvalue control acc. 4.2.1 for the voltage and the current output

property actualsetvalue: float

The actual valid set value, which depends on the ramp function.

Returns

actual valid set value

property high_resolution: *FuGDigitalVal*

Status of the high resolution mode of the output.

Return 0

normal operation

Return 1

High Res. Mode

property rampmode: *FuGRampModes*

The set ramp mode to control the setvalue.

Returns

the mode of the ramp as instance of *FuGRampModes*

property ramprate: float

The set ramp rate in V/s.

Returns

ramp rate in V/s

property rampstate: *FuGDigitalVal*

Status of ramp function.

Return 0

if final setvalue is reached

Return 1

if still ramping up

property setvalue: float

For the voltage or current output this setvalue was programmed.

Returns

the programmed setvalue

class *FuGRampModes*(value)

Bases: *IntEnum*

An enumeration.

FOLLOWRAMP = 1

Follow the ramp up- and downwards

IMMEDIATELY = 0

Standard mode: no ramp

ONLYUPWARDSOFFTOZERO = 4

Follow the ramp up- and downwards, if output is OFF set value is zero

RAMPUPWARDS = 2

Follow the ramp only upwards, downwards immediately

SPECIALRAMPUPWARDS = 3

Follow a special ramp function only upwards

```
class FuGReadbackChannels(value)
```

Bases: `IntEnum`

An enumeration.

CURRENT = 1

FIRMWARE = 5

RATEDCURRENT = 4

RATEDVOLTAGE = 3

SN = 6

STATUSBYTE = 2

VOLTAGE = 0

```
class FuGSerialCommunication(configuration)
```

Bases: `SerialCommunication`

Specific communication protocol implementation for FuG power supplies. Already predefines device-specific protocol parameters in config.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

query(*command: str*) → str

Send a command to the interface and handle the status message. Raises an error, if the answer starts with “E”.

Parameters

command – Command to send

Raises

`FuGError` – if the connection is broken or the error from the power source itself

Returns

Answer from the interface or empty string

```
class FuGSerialCommunicationConfig(terminator: bytes = b'\n', encoding: str = 'utf-8',
                                   encoding_error_handling: str = 'strict', wait_sec_read_text_nonempty:
                                   Union[int, float] = 0.5, default_n_attempts_read_text_nonempty: int =
                                   10, port: Optional[str] = None, baudrate: int = 9600, parity:
                                   Union[str, hvl_ccb.comm.serial.SerialCommunicationParity] =
                                   <SerialCommunicationParity.NONE: 'N'>, stopbits: Union[int,
                                   hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                   <SerialCommunicationStopbits.ONE: 1>, bytesize: Union[int,
                                   hvl_ccb.comm.serial.SerialCommunicationBytesize] =
                                   <SerialCommunicationBytesize.EIGHTBITS: 8>, timeout: Union[int,
                                   float] = 3)
```

Bases: `SerialCommunicationConfig`

baudrate: int = 9600

Baudrate for FuG power supplies is 9600 baud

bytesize: `int` | `SerialCommunicationBytesize` = 8

One byte is eight bits long

default_n_attempts_read_text_nonempty: `int` = 10

default number of attempts to read a non-empty text

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod **keys**() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod **optional_defaults**() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

parity: `str` | `SerialCommunicationParity` = 'N'

FuG does not use parity

classmethod **required_keys**() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

stopbits: `int` | `SerialCommunicationStopbits` = 1

FuG uses one stop bit

terminator: `bytes` = `b'\n'`

The terminator is LF

timeout: `int` | `float` = 3

use 3 seconds timeout as default

wait_sec_read_text_nonempty: `int` | `float` = 0.5

default time to wait between attempts of reading a non-empty text

class **FuGTerminators**(*value*)

Bases: IntEnum

An enumeration.

CR = 3

CRLF = 0

LF = 2

LFCR = 1

Module contents

Device classes for “Probus V - ADDAT30” Interfaces which are used to control power supplies from FuG Elektronik GmbH

This interface is used for many FuG power units. Manufacturer homepage: <https://www.fug-elektronik.de>

The Professional Series of Power Supplies from FuG is a series of low, medium and high voltage direct current power supplies as well as capacitor chargers. The class FuG is tested with a HCK 800-20 000 in Standard Mode. The addressable mode is not implemented. Check the code carefully before using it with other devices. Manufacturer homepage: <https://www.fug-elektronik.de/netzgeraete/professional-series/>

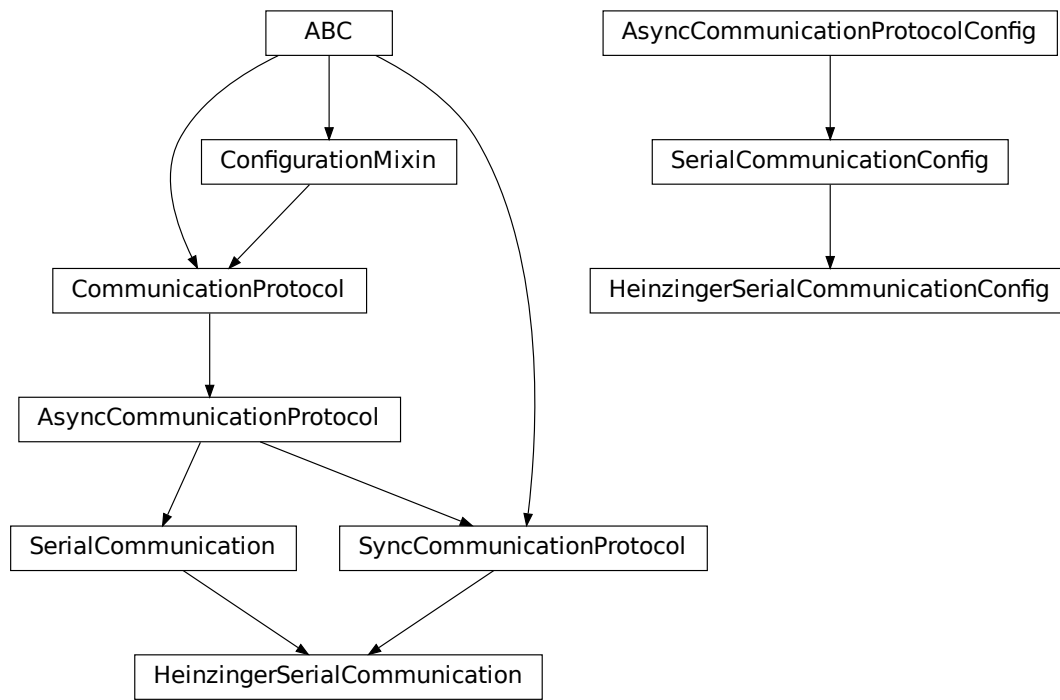
The documentation of the interface from the manufacturer can be found here: https://www.fug-elektronik.de/wp-content/uploads/download/de/SOFTWARE/Probus_V.zip

The provided classes support the basic and some advanced commands. The commands for calibrating the power supplies are not implemented, as they are only for very special porpoises and should not be used by “normal” customers.

`hvl_ccb.dev.heinzinger`

Submodules

hvl_ccb.dev.heinzinger.base



Base classes for Heinzinger Digital Interface I/II and Heinzinger PNC power supply.

The Heinzinger Digital Interface I/II is used for many Heinzinger power units. Interface Manual: https://www.heinzinger.com/assets/uploads/downloads/Handbuch_DigitalInterface_2021-12-14-V1.6.pdf

The Heinzinger PNC series is a series of high voltage direct current power supplies. The class HeinzingerPNC is tested with two PNChp 60000-1neg and a PNChp 1500-1neg. Check the code carefully before using it with other PNC devices, especially PNC3p or PNCcap. Manufacturer homepage: <https://www.heinzinger.com/en/products/pnc-serie>

class HeinzingerSerialCommunication(*configuration*)

Bases: *SerialCommunication*, *SyncCommunicationProtocol*

Specific communication protocol implementation for Heinzinger power supplies. Already predefines device-specific protocol parameters in config.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class HeinzingerSerialCommunicationConfig(terminator: bytes = b'\n', encoding: str = 'utf-8',
                                         encoding_error_handling: str = 'strict',
                                         wait_sec_read_text_nonempty: Union[int, float] = 0.5,
                                         default_n_attempts_read_text_nonempty: int = 40, port:
                                         Optional[str] = None, baudrate: int = 9600, parity:
                                         Union[str, hvl_ccb.comm.serial.SerialCommunicationParity]
                                         = <SerialCommunicationParity.NONE: 'N'>, stopbits:
                                         Union[int,
                                         hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                         <SerialCommunicationStopbits.ONE: 1>, bytesize:
                                         Union[int,
                                         hvl_ccb.comm.serial.SerialCommunicationBytesize] =
                                         <SerialCommunicationBytesize.EIGHTBITS: 8>, timeout:
                                         Union[int, float] = 3)
```

Bases: `SerialCommunicationConfig`

baudrate: `int = 9600`

Baudrate for Heinzinger power supplies is 9600 baud

bytesize: `int | SerialCommunicationBytesize = 8`

One byte is eight bits long

default_n_attempts_read_text_nonempty: `int = 40`

increased to 40 default number of attempts to read a non-empty text

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

parity: `str | SerialCommunicationParity = 'N'`

Heinzinger does not use parity

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

stopbits: `int` | `SerialCommunicationStopbits` = 1

Heinzinger uses one stop bit

terminator: `bytes` = `b'\n'`

The terminator is LF

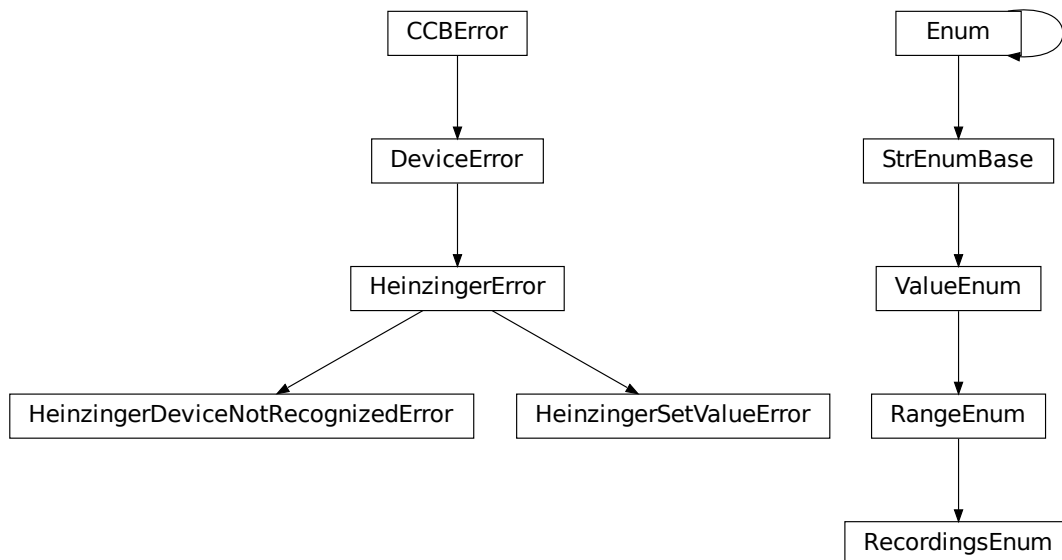
timeout: `int` | `float` = 3

use 3 seconds timeout as default

wait_sec_read_text_nonempty: `int` | `float` = 0.5

default time to wait between attempts of reading a non-empty text

`hvl_ccb.dev.heinzinger.constants`



Constants, Heinzinger Digital Interface I/II and Heinzinger PNC power supply. Descriptors for errors

exception `HeinzingerDeviceNotRecognizedError`

Bases: `HeinzingerError`

Error indicating that the serial number of the device is not recognized.

exception `HeinzingerError`

Bases: `DeviceError`

General error with the Heinzinger PNC voltage source.

exception `HeinzingerSetValueError`

Bases: `HeinzingerError`

Error indicating that the value (current, voltage, ...) is not set correctly


```
class RecordingsEnum(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                     boundary=None)
```

Bases: *RangeEnum*

An enumeration.

EIGHT = 8.0

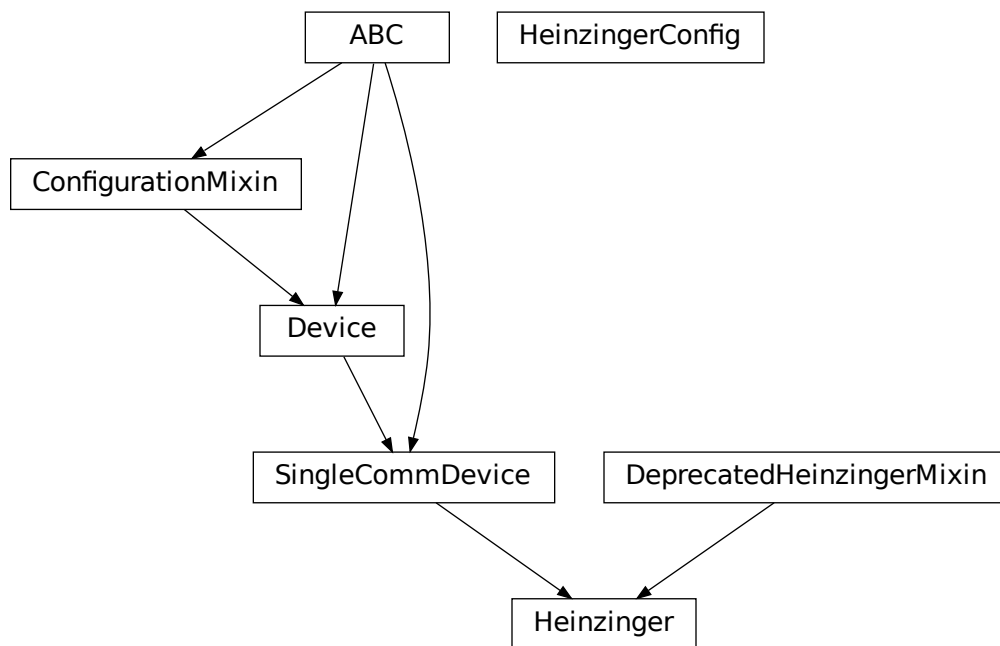
FOUR = 4.0

ONE = 1.0

SIXTEEN = 16.0

TWO = 2.0

hvl_ccb.dev.heinzinger.device



Device classes for Heinzinger Digital Interface I/II and Heinzinger PNC power supply.

The Heinzinger Digital Interface I/II is used for many Heinzinger power units. Interface Manual: https://www.heinzinger.com/assets/uploads/downloads/Handbuch_DigitalInterface_2021-12-14-V1.6.pdf

The Heinzinger PNC series is a series of high voltage direct current power supplies. The class `Heinzinger` is tested with different PNChp-types. Check the code carefully before using it with other PNC devices, especially PNC3p or PNCcap. Manufacturer homepage: <https://www.heinzinger.com/en/products/pnc-serie>

class `Heinzinger`(*com*, *dev_config=None*)

Bases: `SingleCommDevice`, `DeprecatedHeinzingerMixin`

Heinzinger power supply device class. The power supply is controlled over a Heinzinger Digital Interface I/II

Sends basic SCPI commands and reads the answer. Only the standard instruction set from the manual is implemented.

static `config_cls()` → type[`HeinzingerConfig`]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

property `current`: int | float

Ask the Device to measure its output current and return the measurement result in A.

Returns

measured current as float

Raises

`SerialCommunicationIOError` – when communication port is not opened

static `default_com_cls()` → type[`HeinzingerSerialCommunication`]

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

get_interface_version() → str

Queries the version number of the digital interface.

Raises

`SerialCommunicationIOError` – when communication port is not opened

get_serial_number() → str

Ask the device for its serial number and returns the answer as a string.

Returns

string containing the device serial number

Raises

`SerialCommunicationIOError` – when communication port is not opened

identify_device() → *None*

Identify the device nominal voltage and current based on its serial number.

Raises

`SerialCommunicationIOError` – when communication port is not opened

property `max_current`: int | float

Maximal settable output current in A

property `max_current_hardware`: int | float

Maximal output current the hardware can provide in A

property `max_voltage`: int | float

Maximal settable output voltage in V

property `max_voltage_hardware`: int | float

Maximal output voltage the hardware can provide in V

property number_of_recordings: int

Queries the number of recordings the device is using for average value calculation.

Returns

int number of recordings

Raises

SerialCommunicationIOError – when communication port is not opened

property output: bool | None

Switch DC voltage output on and updates the output status.

Raises

SerialCommunicationIOError – when communication port is not opened

reset_interface() → None

Reset of the digital interface; only Digital Interface I: Power supply is switched to the Local-Mode (Manual operation)

Raises

SerialCommunicationIOError – when communication port is not opened

property set_current: int | float

Queries the set current of the Heinzinger PNC (not the measured current!) in A.

Raises

SerialCommunicationIOError – when communication port is not opened

property set_voltage: int | float

Queries the set voltage of the Heinzinger PNC (not the measured voltage!) in V.

Raises

SerialCommunicationIOError – when communication port is not opened

start() → None

Opens the communication protocol and configures the device.

Raises

SerialCommunicationIOError – when communication port cannot be opened.

stop() → None

Stop the device. Closes also the communication protocol.

property voltage: int | float

Ask the Device to measure its output voltage and return the measurement result in V.

Returns

measured voltage as float in V

Raises

SerialCommunicationIOError – when communication port is not opened

class HeinzingerConfig(default_number_of_recordings: int | *RecordingsEnum* = 1, number_of_decimals: int = 6, wait_sec_stop_commands: int | float = 0.5)

Bases: object

Device configuration dataclass for Heinzinger power supplies.

clean_values()

default_number_of_recordings: int | *RecordingsEnum* = 1

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

number_of_decimals: int = 6

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

wait_sec_stop_commands: int | float = 0.5

Time to wait after subsequent commands during stop (in seconds)

[hvl_ccb.dev.heinzinger.mixin](#)

DeprecatedHeinzingerMixin

Mixin class for Heinzinger's deprecated methods.Raise

DeprecationWarning, will be removed in the next release

class DeprecatedHeinzingerMixin

Bases: object

static get_number_of_recordings() → None

static measure_current() → None

```

static measure_voltage() → None

static output_off() → None

static output_on() → None

static set_number_of_recordings() → None

```

Module contents

Device classes for Heinzinger Digital Interface I/II and Heinzinger PNC power supply.

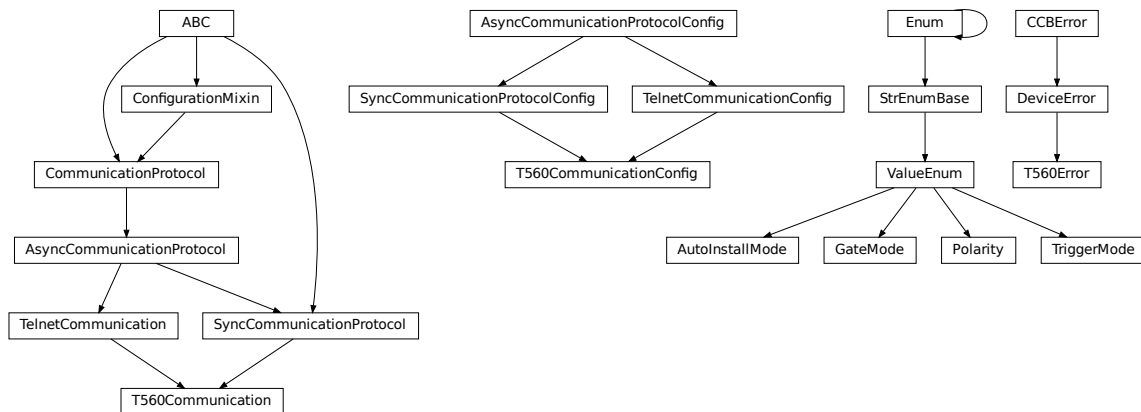
The Heinzinger Digital Interface I/II is used for many Heinzinger power units. Interface Manual: https://www.heinzinger.com/assets/uploads/downloads/Handbuch_DigitalInterface_2021-12-14-V1.6.pdf

The Heinzinger PNC series is a series of high voltage direct current power supplies. The class HeinzingerPNC is tested with two PNChp 60000-1neg and a PNChp 1500-1neg. Check the code carefully before using it with other PNC devices, especially PNC3p or PNCcap. Manufacturer homepage: <https://www.heinzinger.com/en/products/pnc-serie>

hvl_ccb.dev.highland_t560

Submodules

hvl_ccb.dev.highland_t560.base



Module containing base device and communication classes and enums.

Communication with device is performed via its ethernet port and a Telnet connection.

```

class AutoInstallMode(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                      boundary=None)

```

Bases: *ValueEnum*

Modes for installing configuration settings to the device.

INSTALL = 1

OFF = 0

QUEUE = 2

class GateMode(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: [ValueEnum](#)

Available T560 gate modes

INPUT = 'INP'

OFF = 'OFF'

OUTPUT = 'OUT'

class Polarity(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: [ValueEnum](#)

Possible channel polarity states

ACTIVE_HIGH = 'POS'

ACTIVE_LOW = 'NEG'

class T560Communication(configuration)

Bases: [SyncCommunicationProtocol](#), [TelnetCommunication](#)

Communication class for T560. It uses a TelnetCommunication with the SyncCommunicationProtocol

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

query(command: str, n_attempts_max: int | None = None, attempt_interval_sec: int | float | None = None) → str

Send a command to the device and handle the response.

For device setting queries, response will be 'OK' if successful, or '??' if setting cannot be carried out, raising an error.

Parameters

- **command** – Command string to be sent
- **n_attempts_max** – Amount of attempts how often a non-empty text is tried to be read as answer
- **attempt_interval_sec** – time between the reading attempts

Raises

[T560Error](#) – if no response is received, or if the device responds with an error message.

Returns

Response from the device.

```
class T560CommunicationConfig(terminator: bytes = b'\r', encoding: str = 'utf-8', encoding_error_handling:
                               str = 'strict', wait_sec_read_text_nonempty: int | float = 0.5,
                               default_n_attempts_read_text_nonempty: int = 10, host: str |
                               ipaddress.IPv4Address | ipaddress.IPv6Address | NoneType = None, port: int
                               = 2000, timeout: int | float = 0.2)
```

Bases: [SyncCommunicationProtocolConfig](#), [TelnetCommunicationConfig](#)

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod **keys**() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod **optional_defaults**() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

port: **int** = **2000**

Port at which the host is listening

classmethod **required_keys**() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

terminator: **bytes** = **b'\r'**

The terminator character. Typically this is b'\r\n' or b'\n', but can also be b'\r' or other combinations. This defines the end of a single line.

exception **T560Error**

Bases: [DeviceError](#)

T560 related errors.

```
class TriggerMode(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                  boundary=None)
```

Bases: [ValueEnum](#)

Available T560 trigger modes

COMMAND = **'REM'**

EXT_FALLING_EDGE = **'NEG'**

```
EXT_RISING_EDGE = 'POS'
```

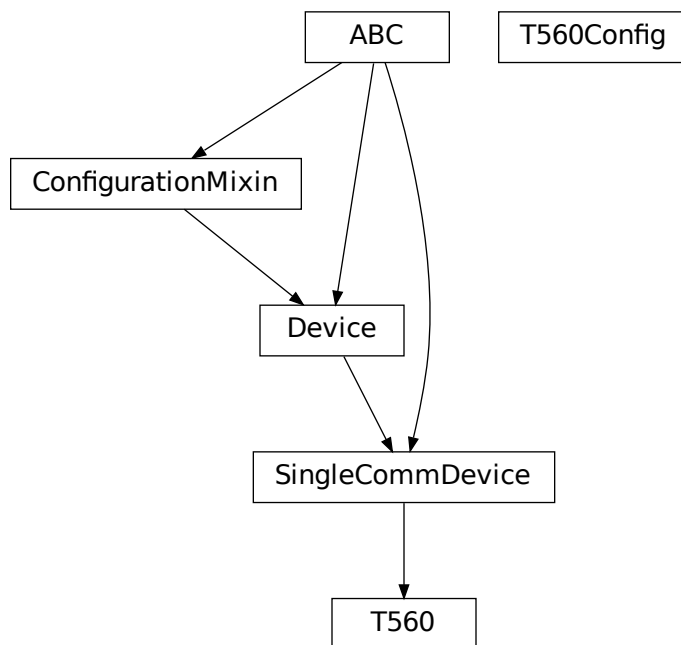
```
INT_SYNTHESIZER = 'SYN'
```

```
OFF = 'OFF'
```

`hvl_ccb.dev.highland_t560.channel`

Module for controlling pulse output channels A, B, C and D.

`hvl_ccb.dev.highland_t560.device`



Module for controlling device,

including TRIG, CLOCK and GATE I/Os.

```
class T560(com, dev_config=None)
```

Bases: `SingleCommDevice`

```
activate_clock_output()
```

Outputs 10 MHz clock signal

```
property auto_install_mode: AutoInstallMode
```

Check the autoinstall settings of the T560. The autoinstall mode sets how changes to device settings are applied. See manual section 4.7.2 for more information about these modes.

```
property ch_a: _Channel
```

Channel A of T560

property ch_b: _Channel

Channel B of T560

property ch_c: _Channel

Channel C of T560

property ch_d: _Channel

Channel D of T560

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

disarm_trigger()

Disarm DDG by disabling all trigger sources.

fire_trigger()

Fire a software trigger.

property frequency: float

The frequency of the timing cycle in Hz.

property gate_mode: *GateMode*

Check the mode setting of the GATE I/O port.

property gate_polarity: *Polarity*

Check the polarity setting of the GATE I/O port.

load_device_configuration()

Load the settings saved in nonvolatile memory.

property period: float

The period of the timing cycle (time between triggers) in seconds.

save_device_configuration()

Save the current settings to nonvolatile memory.

property trigger_level

Get external trigger level.

property trigger_mode

Get device trigger source.

use_external_clock()

Finds and accepts an external clock signal to the CLOCK input

class T560Config

Bases: object

auto_install_mode = 1

clean_values()

Cleans and enforces configuration values. Does nothing by default, but may be overridden to add custom configuration value checks.

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True**classmethod keys()** → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

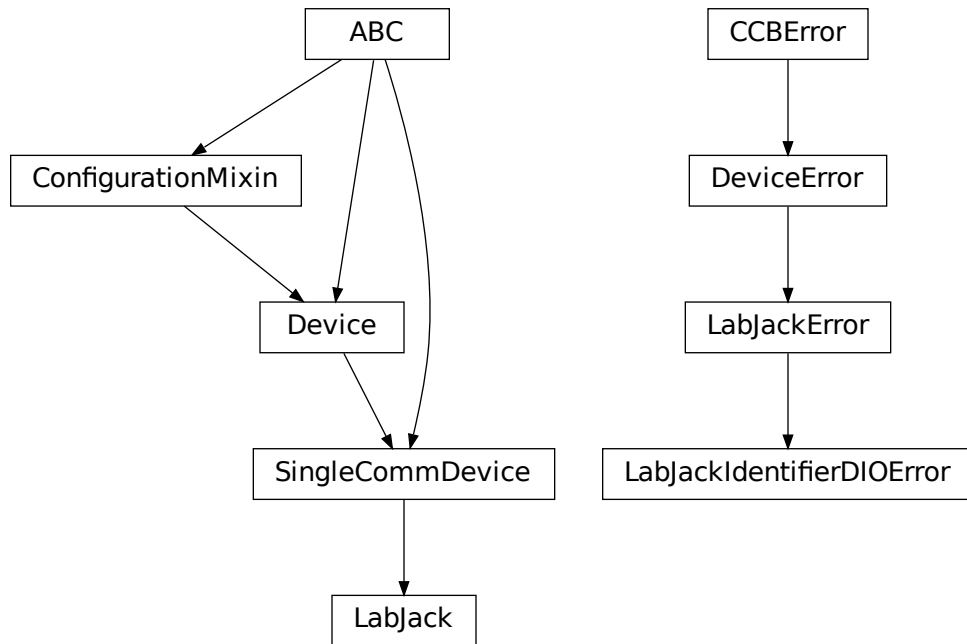
Module contents

This module establishes methods for interfacing with the Highland Technology T560-2 via its ethernet adapter with a telnet communication protocol.

The T560 is a small digital delay & pulse generator. It outputs up to four individually timed pulses with 10-ps precision, given an internal or external trigger.

This module introduces methods for configuring channels, gating, and triggering. Further documentation and a more extensive command list may be obtained from:

<https://www.highlandtechnology.com/DSS/T560DS.shtml>

hvl_ccb.dev.labjack**Submodules****hvl_ccb.dev.labjack.labjack**

LabJack T-series devices wrapper around the LabJack's LJM Library; see <https://labjack.com/ljm> . The wrapper was originally developed and tested for a LabJack T7-PRO device. A

Extra installation

To use this LabJack T-series devices wrapper:

1. install the hvl_ccb package with a labjack extra feature:

```
$ pip install "hvl_ccb[labjack]"
```

this will install the Python bindings for the library.

2. install the library - follow instruction in <https://labjack.com/support/software/installers/ljm> .

class LabJack(com, dev_config=None)

Bases: *SingleCommDevice*

LabJack Device.

This class is tested with a LabJack T7-Pro and should also work with T4 and T7 devices communicating through the LJM Library. Other or older hardware versions and variants of LabJack devices are not supported.

```
class AInRange(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
               boundary=None)
```

Bases: [*StrEnumBase*](#)

An enumeration.

ONE = 1.0

ONE_HUNDREDTH = 0.01

ONE_TENTH = 0.1

TEN = 10.0

property value: float

```
class BitLimit(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
               boundary=None)
```

Bases: [*IntEnum*](#)

Maximum integer values for clock settings

THIRTY_TWO_BIT = 4294967295

```
class CalMicroAmpere(value=<no_arg>, names=None, module=None, qualname=None, type=None,
                      start=1, boundary=None)
```

Bases: [*Enum*](#)

Pre-defined microampere (uA) values for calibration current source query.

TEN = '10uA'

TWO_HUNDRED = '200uA'

```
class CjcType(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
               boundary=None)
```

Bases: [*NameEnum*](#)

CJC slope and offset

internal = (1, 0)

lm34 = (55.56, 255.37)

```
class ClockFrequency(value=<no_arg>, names=None, module=None, qualname=None, type=None,
                      start=1, boundary=None)
```

Bases: [*IntEnum*](#)

Available clock frequencies, in Hz

FIVE_MHZ = 5000000

FORTY_MHZ = 40000000

MAXIMUM = 80000000

MINIMUM = 312500

```
TEN_MHZ = 10000000
```

```
TWELVE_HUNDRED_FIFTY_KHZ = 1250000
```

```
TWENTY_FIVE_HUNDRED_KHZ = 2500000
```

```
TWENTY_MHZ = 20000000
```

DIOChannel

alias of TSeriesDIOChannel

```
class DIOStatus(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                boundary=None)
```

Bases: `IntEnum`

State of a digital I/O channel.

```
HIGH = 1
```

```
LOW = 0
```

```
class DeviceType(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                 boundary=None)
```

Bases: `AutoNumberNameEnum`

LabJack device types.

Can be also looked up by ambiguous Product ID (*p_id*) or by instance name: ``python LabJackDeviceType(4) is LabJackDeviceType('T4')``

```
ANY = 1
```

```
T4 = 2
```

```
T7 = 3
```

```
T7_PRO = 4
```

```
classmethod get_by_p_id(p_id: int) → DeviceType | list[DeviceType]
```

Get LabJack device type instance via LabJack product ID.

Note: Product ID is not unambiguous for LabJack devices.

Parameters

p_id – Product ID of a LabJack device

Returns

Instance or list of instances of *LabJackDeviceType*

Raises

ValueError – when Product ID is unknown

```
class TemperatureUnit(value=<no_arg>, names=None, module=None, qualname=None, type=None,
                      start=1, boundary=None)
```

Bases: `NameEnum`

Temperature unit (to be returned)

```
C = 1
```

```
F = 2
```

```
K = 0
```

```
class ThermocoupleType(value=<no_arg>, names=None, module=None, qualname=None, type=None,
                        start=1, boundary=None)
```

Bases: *NameEnum*

Thermocouple type; NONE means disable thermocouple mode.

C = 30

E = 20

J = 21

K = 22

NONE = 0

PT100 = 40

PT1000 = 42

PT500 = 41

R = 23

S = 25

T = 24

```
config_high_pulse(address: str | TSeriesDIOChannel, t_start: int | float, t_width: int | float, n_pulses: int
                  = 1) → None
```

Configures one FIO channel to send a timed HIGH pulse. Configure multiple channels to send pulses with relative timing accuracy. Times have a maximum resolution of 1e-7 seconds @ 10 MHz. :param address: FIO channel: [T7] FIO0;2;3;4;5. [T4] FIO6;7. :raises LabJackError if address is not supported. :param t_start: pulse start time in seconds. :raises ValueError: if t_start is negative or would exceed the clock period. :param t_width: duration of high pulse, in seconds. :raises ValueError: if t_width is negative or would exceed the clock period. :param n_pulses: number of pulses to be sent; single pulse default. :raises TypeError if n_pulses is not of type int. :raises Value Error if n_pulses is negative or exceeds the 32bit limit.

```
static default_com_cls()
```

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

```
disable_pulses(*addresses: str | TSeriesDIOChannel | None) → None
```

Disable previously configured pulse channels. :param addresses: tuple of FIO addresses. All channels disabled if no argument is passed.

```
enable_clock(clock_enabled: bool) → None
```

Enable/disable LabJack clock to configure or send pulses. :param clock_enabled: True -> enable, False -> disable. :raises TypeError: if clock_enabled is not of type bool

```
get_ain(*channels: int) → float | Sequence[float]
```

Read currently measured value (voltage, resistance, ...) from one or more of analog inputs.

Parameters

channels – AIN number or numbers (0..254)

Returns

the read value (voltage, resistance, ...) as *float* or *tuple* of them in case multiple channels given

get_cal_current_source(*name: str | CalMicroAmpere*) → float

This function will return the calibration of the chosen current source, this is not a measurement!

The value was stored during fabrication.

Parameters

name – ‘200uA’ or ‘10uA’ current source

Returns

calibration of the chosen current source in ampere

get_clock() → dict[str, int | float]

Return clock settings read from LabJack.

get_digital_input(*address: str | TSeriesDIOChannel*) → *DIOStatus*

Get the value of a digital input.

allowed names for T7 (Pro): FIO0 - FIO7, EIO0 - EIO 7, CIO0- CIO3, MIO0 - MIO2 :param address: name of the output -> ‘FIO0’ :return: HIGH when *address* DIO is high, and LOW when *address* DIO is low

get_product_id() → int

This function returns the product ID reported by the connected device.

Attention: returns 7 for both T7 and T7-Pro devices!

Returns

integer product ID of the device

get_product_name(*force_query_id=False*) → str

This function will return the product name based on product ID reported by the device.

Attention: returns “T7” for both T7 and T7-Pro devices!

Parameters

force_query_id – boolean flag to force *get_product_id* query to device instead of using cached device type from previous queries.

Returns

device name string, compatible with *LabJack.DeviceType*

get_product_type(*force_query_id: bool = False*) → *DeviceType*

This function will return the device type based on reported device type and in case of unambiguity based on configuration of device’s communication protocol (e.g. for “T7” and “T7_PRO” devices), or, if not available first matching.

Parameters

force_query_id – boolean flag to force *get_product_id* query to device instead of using cached device type from previous queries.

Returns

DeviceType instance

Raises

LabJackIdentifierDIOError – when read Product ID is unknown

get_sbus_rh(*number: int*) → float

Read the relative humidity value from a serial SBUS sensor.

Parameters

number – port number (0..22)

Returns

relative humidity in %RH

get_sbus_temp(*number: int*) → float

Read the temperature value from a serial SBUS sensor.

Parameters

number – port number (0..22)

Returns

temperature in Kelvin

get_serial_number() → int

Returns the serial number of the connected LabJack.

Returns

Serial number.

read_resistance(*channel: int*) → float

Read resistance from specified channel.

Parameters

channel – channel with resistor

Returns

resistance value with 2 decimal places

read_thermocouple(*pos_channel: int*) → float

Read the temperature of a connected thermocouple.

Parameters

pos_channel – is the AIN number of the positive pin

Returns

temperature in specified unit

send_pulses(**addresses: str | TSeriesDIOChannel*) → *None*

Sends pre-configured pulses for specified addresses. :param addresses: tuple of FIO addresses :raises LabJackError if an address has not been configured.

set_ain_differential(*pos_channel: int, differential: bool*) → *None*

Sets an analog input to differential mode or not. T7-specific: For base differential channels, positive must be even channel from 0-12 and negative must be positive+1. For extended channels 16-127, see Mux80 datasheet.

Parameters

- **pos_channel** – is the AIN number (0..12)
- **differential** – True or False

Raises

LabJackError – if parameters are unsupported

set_ain_range(*channel: int, vrangle: Real | AInRange*) → *None*

Set the range of an analog input port.

Parameters

- **channel** – is the AIN number (0..254)
- **vrangle** – is the voltage range to be set

set_ain_resistance(*channel: int, vrangle: Real | AInRange, resolution: int*) → *None*

Set the specified channel to resistance mode. It utilized the 200uA current source of the LabJack.

Parameters

- **channel** – channel that should measure the resistance
- **vrangle** – voltage range of the channel
- **resolution** – resolution index of the channel T4: 0-5, T7: 0-8, T7-Pro 0-12

set_ain_resolution(*channel: int, resolution: int*) → *None*

Set the resolution index of an analog input port.

Parameters

- **channel** – is the AIN number (0..254)
- **resolution** – is the resolution index within 0...`get_product_type().ain_max_resolution` range; 0 will set the resolution index to default value.

set_ain_thermocouple(*pos_channel: int, thermocouple: None | str | ThermocoupleType, cjc_address: int = 60050, cjc_type: str | CjcType = CjcType.internal, vrangle: Real | AInRange = AInRange.ONE_HUNDREDTH, resolution: int = 10, unit: str | TemperatureUnit = TemperatureUnit.K*) → *None*

Set the analog input channel to thermocouple mode.

Parameters

- **pos_channel** – is the analog input channel of the positive part of the differential pair
- **thermocouple** – None to disable thermocouple mode, or string specifying the thermocouple type
- **cjc_address** – modbus register address to read the CJC temperature
- **cjc_type** – determines cjc slope and offset, 'internal' or 'lm34'
- **vrangle** – measurement voltage range
- **resolution** – resolution index (T7-Pro: 0-12)
- **unit** – is the temperature unit to be returned ('K', 'C' or 'F')

Raises

LabJackError – if parameters are unsupported

set_analog_output(*channel: int, value: int | float*) → *None*

Set the voltage of a analog output port

Parameters

- **channel** – DAC channel number 1/0
- **value** – The output voltage value 0-5 Volts int/float

set_clock(*clock_frequency: Number | ClockFrequency = 10000000*, *clock_period: Number = 1*) → *None*

Configure LabJack clock for pulse out feature. :param clock_frequency: clock frequency in Hz; default 10 MHz for base 10. :raises ValueError: if clock_frequency is not allowed (see ClockFrequency). :param clock_period: clock roll time in seconds; default 1s, 0 for max. :raises ValueError: if clock_period exceeds the 32bit tick limit. Clock period determines pulse spacing when using multi-pulse settings. Ensure period exceeds maximum intended pulse end time.

set_digital_output(*address: str*, *state: int | DIOStatus*) → *None*

Set the value of a digital output.

Parameters

- **address** – name of the output -> 'FIO0'
- **state** – state of the output -> *DIOStatus* instance or corresponding *int* value

start() → *None*

Start the Device.

stop() → *None*

Stop the Device.

exception LabJackError

Bases: *DeviceError*

General Error for the LabJack device.

exception LabJackIdentifierDIOError

Bases: *LabJackError*

Error indicating a wrong DIO identifier

Module contents

A LabJack T-series devices wrapper around the LabJack's LJM Library; see <https://labjack.com/ljm> . The wrapper was originally developed and tested for a LabJack T7-PRO device.

Extra installation

To use this LabJack T-series devices wrapper:

1. install the hv1_ccb package with a labjack extra feature:

```
$ pip install "hv1_ccb[labjack]"
```

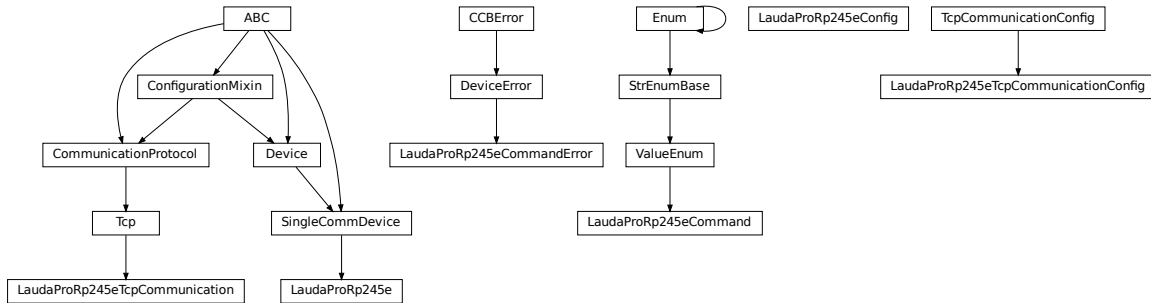
this will install the Python bindings for the library.

2. install the library - follow instruction in <https://labjack.com/support/software/installers/ljm> .

hvl_ccb.dev.lauda

Submodules

hvl_ccb.dev.lauda.lauda



Device class for controlling a Lauda PRO RP245E, circulation chiller over TCP.

class `LaudaProRp245e`(*com*, *dev_config=None*)

Bases: `SingleCommDevice`

Lauda RP245E circulation chiller class.

static `config_cls()` → type[`LaudaProRp245eConfig`]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

continue_ramp() → str

Continue current ramp program.

Returns

reply of the device to the last call of “query”

static `default_com_cls()` → type[`LaudaProRp245eTcpCommunication`]

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

get_bath_temp() → float

:return : float value of measured lauda bath temp in °C

get_device_type() → str

:return : Connected Lauda device type (for connection/com test)

pause() → str

Stop temperature control and pump.

Returns

reply of the device to the last call of “query”

pause_ramp() → str

Pause current ramp program.

Returns

reply of the device to the last call of “query”

reset_ramp() → str

Delete all segments from current ramp program.

Returns

reply of the device to the last call of “query”

run() → str

Start temperature control & pump.

Returns

reply of the device to the last call of “query”

set_control_mode(*mod: int* | [ExtControlModeEnum](#) = *ExtControlModeEnum.INTERNAL*) → str

Define control mode. 0 = INTERNAL (control bath temp), 1 = EXPT100 (pt100 attached to chiller), 2 = ANALOG, 3 = SERIAL, 4 = USB, 5 = ETH (to be used when passing the ext. temp. via ethernet) (temperature then needs to be passed every second, when not using options 3, 4, or 5)

Parameters

mod – temp control mode (control internal temp or external temp).

Returns

reply of the device to the last call of “query” (“OK”, if command was recognized)

set_external_temp(*external_temp: float* = 20.0) → str

Pass value of external controlled temperature. Should be done every second, when control of external temperature is active. Has to be done right before control of external temperature is activated.

Parameters

external_temp – current value of external temperature to be controlled.

Returns

reply of the device to the last call of “query”

set_pump_level(*pump_level: int* = 6) → str

Set pump level Raises ValueError, if pump level is invalid.

Parameters

pump_level – pump level.

Returns

reply of the device to the last call of “query”

set_ramp_iterations(*num: int* = 1) → str

Define number of ramp program cycles.

Parameters

num – number of program cycles to be performed.

Returns

reply of the device to the last call of “query”

set_ramp_program(*program: int* = 1) → str

Define ramp program for following ramp commands. Raises ValueError if maximum number of ramp programs (5) is exceeded.

Parameters

program – Number of ramp program to be activated for following commands.

Returns

reply of the device to the last call of “query”

set_ramp_segment(*temp: float = 20.0, dur: int = 0, tol: float = 0.0, pump: int = 6*) → str

Define segment of current ramp program - will be attached to current program. Raises ValueError, if pump level is invalid.

Parameters

- **temp** – target temperature of current ramp segment
- **dur** – duration in minutes, in which target temperature should be reached
- **tol** – tolerance at which target temperature should be reached (for 0.00, next segment is started after dur has passed).
- **pump** – pump level to be used for this program segment.

Returns

reply of the device to the last call of “query”

set_temp_set_point(*temp_set_point: float = 20.0*) → str

Define temperature set point

Parameters

temp_set_point – temperature set point.

Returns

reply of the device to the last call of “query”

start() → *None*

Start this device.

start_ramp() → str

Start current ramp program.

Returns

reply of the device to the last call of “query”

stop() → *None*

Stop this device. Disables access and closes the communication protocol.

stop_ramp() → str

Stop current ramp program.

Returns

reply of the device to the last call of “query”

validate_pump_level(*level: int*)

Validates pump level. Raises ValueError, if pump level is incorrect. :param level: pump level, integer

class LaudaProRp245eCommand(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: *ValueEnum*

Commands for Lauda PRO RP245E Chiller Command strings most often need to be complimented with a parameter (attached as a string) before being sent to the device. Commands implemented as defined in “Lauda Betriebsanleitung fuer PRO Badthermostate und Umwaelzthermostate” pages 42 - 49

BATH_TEMP = 'IN_PV_00'

Request internal bath temperature

COM_TIME_OUT = 'OUT_SP_08_'

Define communication time out

CONT_MODE = 'OUT_MODE_01_'

Set control mode 1=internal, 2=ext. analog, 3=ext. serial, 4=USB, 5=ethernet

DEVICE_TYPE = 'TYPE'

Request device type

EXTERNAL_TEMP = 'OUT_PV_05_'

Pass on external controlled temperature

LOWER_TEMP = 'OUT_SP_05_'

Define lower temp limit

OPERATION_MODE = 'OUT_SP_02_'

Define operation mode

PUMP_LEVEL = 'OUT_SP_01_'

Define pump level 1-8

RAMP_CONTINUE = 'RMP_CONT'

Continue a paused ramp program

RAMP_DELETE = 'RMP_RESET'

Reset a selected ramp program

RAMP_ITERATIONS = 'RMP_OUT_02_'

Define how often a ramp program should be iterated

RAMP_PAUSE = 'RMP_PAUSE'

Pause a selected ramp program

RAMP_SELECT = 'RMP_SELECT_'

Select a ramp program (target for all further ramp commands)

RAMP_SET = 'RMP_OUT_00_'

Define parameters of a selected ramp program

RAMP_START = 'RMP_START'

Start a selected ramp program

RAMP_STOP = 'RMP_STOP'

Stop a running ramp program

START = 'START'

Start temp control (pump and heating/cooling)

STOP = 'STOP'

Stop temp control (pump and heating/cooling)

TEMP_SET_POINT = 'OUT_SP_00_'

Define temperature set point

```
UPPER_TEMP = 'OUT_SP_04_'
```

Define upper temp limit

```
build_str(param: str = "", terminator: str = '\r\n')
```

Build a command string for sending to the device

Parameters

- **param** – Command's parameter given as string
- **terminator** – Command's terminator

Returns

Command's string with a parameter and terminator

```
exception LaudaProRp245eCommandError
```

Bases: [DeviceError](#)

Error raised when an error is returned upon a command.

```
class LaudaProRp245eConfig(temp_set_point_init: int | float = 20.0, pump_init: int = 6, upper_temp: int | float
                           = 80.0, lower_temp: int | float = -55.0, com_time_out: int | float = 0,
                           max_pump_level: int = 8, max_pr_number: int = 5, operation_mode: int |
                           OperationModeEnum = OperationModeEnum.AUTO, control_mode: int |
                           ExtControlModeEnum = ExtControlModeEnum.INTERNAL)
```

Bases: object

Configuration for the Lauda RP245E circulation chiller.

```
class ExtControlModeEnum(value)
```

Bases: IntEnum

Source for definition of external, controlled temperature (option 2, 3 and 4 are not available with current configuration of the Lauda RP245E, add-on hardware would required)

```
ANALOG = 2
```

```
ETH = 5
```

```
EXPT100 = 1
```

```
INTERNAL = 0
```

```
SERIAL = 3
```

```
USB = 4
```

```
class OperationModeEnum(value)
```

Bases: IntEnum

Operation Mode (Cooling OFF/Cooling On/AUTO - set to AUTO)

```
AUTO = 2
```

Automatically select heating/cooling

```
COOLOFF = 0
```

```
COOLON = 1
```

```
clean_values() → None
```

com_time_out: int | float = 0

Communication time out (0 = OFF)

control_mode: int | *ExtControlModeEnum* = 0

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

lower_temp: int | float = -55.0

Lower temperature limit (safe for Galden HT135 cooling liquid)

max_pr_number: int = 5

Maximum number of ramp programs that can be stored in the memory of the chiller

max_pump_level: int = 8

Highest pump level of the chiller

operation_mode: int | *OperationModeEnum* = 2

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

pump_init: int = 6

Default pump Level

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

temp_set_point_init: int | float = 20.0

Default temperature set point

upper_temp: int | float = 80.0

Upper temperature limit (safe for Galden HT135 cooling liquid)

class `LaudaProRp245eTcpCommunication`(*configuration*)

Bases: `Tcp`

Implements the Communication Protocol for Lauda PRO RP245E TCP connection.

close() → *None*

Close the Lauda PRO RP245E TCP connection.

static config_cls() → type[`LaudaProRp245eTcpCommunicationConfig`]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

open() → *None*

Open the Lauda PRO RP245E TCP connection.

Raises

`LaudaProRp245eCommandError` – if the connection fails.

query_command(*command*: `LaudaProRp245eCommand`, *param*: *str* = "") → *str*

Send and receive function. E.g. to be used when setting/changing device setting. :param *command*: first part of command string, defined in `LaudaProRp245eCommand` :param *param*: second part of command string, parameter (by default '') :return: *None*

read() → *str*

Receive value function. :return: reply from device as a string, the terminator, as well as the 'OK' stripped from the reply to make it directly useful as a value (e.g. in case the internal bath temperature is requested)

write_command(*command*: `LaudaProRp245eCommand`, *param*: *str* = "") → *None*

Send command function. :param *command*: first part of command string, defined in `LaudaProRp245eCommand` :param *param*: second part of command string, parameter (by default '') :return: *None*

class `LaudaProRp245eTcpCommunicationConfig`(*host*: *str* | `IPv4Address` | `IPv6Address`, *port*: *int* = 54321, *bufsize*: *int* = 1024, *wait_sec_pre_read_or_write*: *int* | *float* = 0.005, *terminator*: *str* = '\r\n')

Bases: `TcpCommunicationConfig`

Configuration dataclass for `LaudaProRp245eTcpCommunication`.

clean_values() → *None*

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define `post_force_value` method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[*str*]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod `optional_defaults()` → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod `required_keys()` → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

terminator: str = '\r\n'

The terminator character

wait_sec_pre_read_or_write: int | float = 0.005

Delay time between commands in seconds

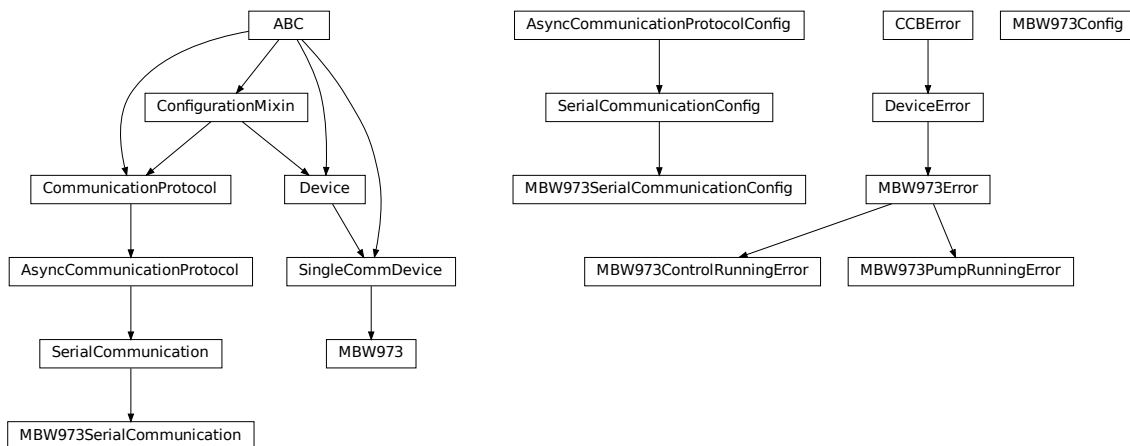
Module contents

Device class for controlling a Lauda PRO RP245E, circulation chiller over TCP.

hvl_ccb.dev.mbw973

Submodules

hvl_ccb.dev.mbw973.mbw973



Device class for controlling a MBW 973 SF6 Analyzer over a serial connection.

The MBW 973 is a gas analyzer designed for gas insulated switchgear and measures humidity, SF6 purity and SO2 contamination in one go. Manufacturer homepage: <https://www.mbw.ch/products/sf6-gas-analysis/973-sf6-analyzer/>

class MBW973(*com*, *dev_config=None*)

Bases: *SingleCommDevice*

MBW 973 dew point mirror device class.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

is_done() → bool

Poll status of the dew point mirror and return True, if all measurements are done.

Returns

True, if all measurements are done; False otherwise.

Raises

SerialCommunicationIOError – when communication port is not opened

read(*cast_type: type = <class 'str'>*)

Read value from *self.com* and cast to *cast_type*. Raises *ValueError* if read text (*str*) is not convertible to *cast_type*, e.g. to *float* or to *int*.

Returns

Read value of *cast_type* type.

read_float() → float

Convenience wrapper for *self.read()*, with typing hint for return value.

Returns

Read *float* value.

read_int() → int

Convenience wrapper for *self.read()*, with typing hint for return value.

Returns

Read *int* value.

read_measurements() → dict[str, float]

Read out measurement values and return them as a dictionary.

Returns

Dictionary with values.

Raises

SerialCommunicationIOError – when communication port is not opened

set_measuring_options(*humidity: bool = True*, *sf6_purity: bool = False*) → *None*

Send measuring options to the dew point mirror.

Parameters

- **humidity** – Perform humidity test or not?
- **sf6_purity** – Perform SF6 purity test or not?

Raises

SerialCommunicationIOError – when communication port is not opened

start() → *None*

Start this device. Opens the communication protocol and retrieves the set measurement options from the device.

Raises

SerialCommunicationIOError – when communication port cannot be opened.

start_control() → *None*

Start dew point control to acquire a new value set.

Raises

SerialCommunicationIOError – when communication port is not opened

stop() → *None*

Stop the device. Closes also the communication protocol.

write(value) → *None*

Send *value* to *self.com*.

Parameters

value – Value to send, converted to *str*.

Raises

SerialCommunicationIOError – when communication port is not opened

class MBW973Config(*polling_interval: int | float = 2*)

Bases: object

Device configuration dataclass for MBW973.

clean_values()

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

polling_interval: `int | float = 2`

Polling period for *is_done* status queries [in seconds].

classmethod required_keys() `→ Sequence[str]`

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

exception MBW973ControlRunningError

Bases: *MBW973Error*

Error indicating there is still a measurement running, and a new one cannot be started.

exception MBW973Error

Bases: *DeviceError*

General error with the MBW973 dew point mirror device.

exception MBW973PumpRunningError

Bases: *MBW973Error*

Error indicating the pump of the dew point mirror is still recovering gas, unable to start a new measurement.

class MBW973SerialCommunication(*configuration*)

Bases: *SerialCommunication*

Specific communication protocol implementation for the MBW973 dew point mirror. Already predefines device-specific protocol parameters in config.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class MBW973SerialCommunicationConfig(terminator: bytes = b'\r', encoding: str = 'utf-8',
                                     encoding_error_handling: str = 'strict',
                                     wait_sec_read_text_nonempty: Union[int, float] = 0.5,
                                     default_n_attempts_read_text_nonempty: int = 10, port:
                                     Optional[str] = None, baudrate: int = 9600, parity: Union[str,
                                     hvl_ccb.comm.serial.SerialCommunicationParity] =
                                     <SerialCommunicationParity.NONE: 'N'>, stopbits: Union[int,
                                     hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                     <SerialCommunicationStopbits.ONE: 1>, bytesize: Union[int,
                                     hvl_ccb.comm.serial.SerialCommunicationBytesize] =
                                     <SerialCommunicationBytesize.EIGHTBITS: 8>, timeout:
                                     Union[int, float] = 3)
```

Bases: *SerialCommunicationConfig*

baudrate: `int = 9600`

Baudrate for MBW973 is 9600 baud

bytesize: `int | SerialCommunicationBytesize = 8`

One byte is eight bits long

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

parity: str | *SerialCommunicationParity* = 'N'

MBW973 does not use parity

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

stopbits: int | *SerialCommunicationStopbits* = 1

MBW973 does use one stop bit

terminator: bytes = b'\r'

The terminator is only CR

timeout: int | float = 3

use 3 seconds timeout as default

Module contents

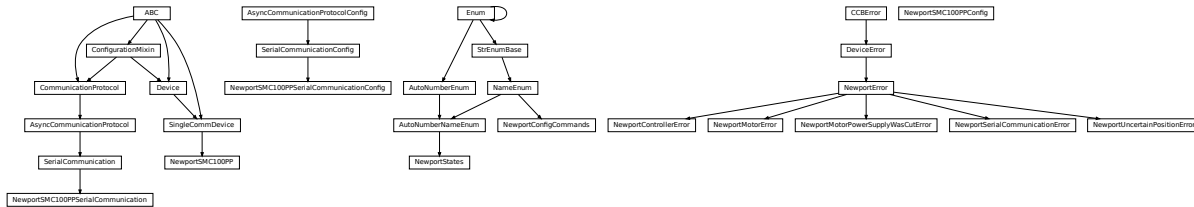
Device class for controlling a MBW 973 SF6 Analyzer over a serial connection.

The MBW 973 is a gas analyzer designed for gas insulated switchgear and measures humidity, SF6 purity and SO2 contamination in one go. Manufacturer homepage: <https://www.mbw.ch/products/sf6-gas-analysis/973-sf6-analyzer/>

hvl_ccb.dev.newport

Submodules

hvl_ccb.dev.newport.newport



Device class for Newport SMC100PP stepper motor controller with serial communication.

The SMC100PP is a single axis motion controller/driver for stepper motors up to 48 VDC at 1.5 A rms. Up to 31 controllers can be networked through the internal RS-485 communication link.

Manufacturer homepage: <https://www.newport.com/f/smc100-single-axis-dc-or-stepper-motion-controller>

class NewportConfigCommands(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: *NameEnum*

Commands predefined by the communication protocol of the SMC100PP

AC = 'acceleration'

BA = 'backlash_compensation'

BH = 'hysteresis_compensation'

FRM = 'micro_step_per_full_step_factor'

FRS = 'motion_distance_per_full_step'

HT = 'home_search_type'

JR = 'jerk_time'

OH = 'home_search_velocity'

OT = 'home_search_timeout'

QIL = 'peak_output_current_limit'

SA = 'rs485_address'

SL = 'negative_software_limit'

SR = 'positive_software_limit'

VA = 'velocity'

VB = 'base_velocity'

ZX = 'stage_configuration'

exception NewportControllerErrorBases: *NewportError*

Error with the Newport controller.

exception NewportErrorBases: *DeviceError*

General Error for Newport Device

exception NewportMotorErrorBases: *NewportError*

Error with the Newport motor.

exception NewportMotorPowerSupplyWasCutErrorBases: *NewportError*

Error with the Newport motor after the power supply was cut and then restored, without interrupting the communication with the controller.

class NewportSMC100PP(*com, dev_config=None*)Bases: *SingleCommDevice*

Device class of the Newport motor controller SMC100PP

class MotorErrors(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: Enum

Possible motor errors reported by the motor during get_state().

DC_VOLTAGE_TOO_LOW = 3**FOLLOWING_ERROR** = 6**HOMING_TIMEOUT** = 5**NED_END_OF_TURN** = 11**OUTPUT_POWER_EXCEEDED** = 2**PEAK_CURRENT_LIMIT** = 9**POS_END_OF_TURN** = 10**RMS_CURRENT_LIMIT** = 8**SHORT_CIRCUIT** = 7**WRONG_ESP_STAGE** = 4**class StateMessages**(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: Enum

Possible messages returned by the controller on get_state() query.

CONFIG = '14'**DISABLE_FROM_JOGGING** = '3E'


```

DISABLE_FROM_MOVING = '3D'
DISABLE_FROM_READY = '3C'
HOMING_FROM_RS232 = '1E'
HOMING_FROM_SMC = '1F'
JOGGING_FROM_DISABLE = '47'
JOGGING_FROM_READY = '46'
MOVING = '28'
NO_REF_ESP_STAGE_ERROR = '10'
NO_REF_FROM_CONFIG = '0C'
NO_REF_FROM_DISABLED = '0D'
NO_REF_FROM_HOMING = '0B'
NO_REF_FROM_JOGGING = '11'
NO_REF_FROM_MOVING = '0F'
NO_REF_FROM_READY = '0E'
NO_REF_FROM_RESET = '0A'
READY_FROM_DISABLE = '34'
READY_FROM_HOMING = '32'
READY_FROM_JOGGING = '35'
READY_FROM_MOVING = '33'

```

States

alias of *NewportStates*

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

exit_configuration(add: int | None = None) → None

Exit the CONFIGURATION state and go back to the NOT REFERENCED state. All configuration parameters are saved to the device's memory.

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

get_acceleration(*add*: int | None = None) → int | float

Leave the configuration state. The configuration parameters are saved to the device's memory.

Parameters

add – controller address (1 to 31)

Returns

acceleration (preset units/s²), value between 1e-6 and 1e12

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

get_controller_information(*add*: int | None = None) → str

Get information on the controller name and driver version

Parameters

add – controller address (1 to 31)

Returns

controller information

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

get_motor_configuration(*add*: int | None = None) → dict[str, float]

Query the motor configuration and returns it in a dictionary.

Parameters

add – controller address (1 to 31)

Returns

dictionary containing the motor's configuration

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

get_move_duration(*dist*: int | float, *add*: int | None = None) → float

Estimate the time necessary to move the motor of the specified distance.

Parameters

- **dist** – distance to travel
- **add** – controller address (1 to 31), defaults to self.address

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

get_negative_software_limit(*add*: int | None = None) → int | float

Get the negative software limit (the maximum position that the motor is allowed to travel to towards the left).

Parameters

add – controller address (1 to 31)

Returns

negative software limit (preset units), value between -1e12 and 0

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

get_position(*add*: int | None = None) → float

Returns the value of the current position.

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error
- *NewportUncertainPositionError* – if the position is ambiguous

get_positive_software_limit(*add*: int | None = None) → int | float

Get the positive software limit (the maximum position that the motor is allowed to travel to towards the right).

Parameters

add – controller address (1 to 31)

Returns

positive software limit (preset units), value between 0 and 1e12

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

get_state(*add*: int | None = None) → *StateMessages*

Check on the motor errors and the controller state

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error
- *NewportMotorError* – if the motor reports an error

Returns

state message from the device (member of StateMessages)

go_home(*add*: int | None = None) → None

Move the motor to its home position.

Parameters

add – controller address (1 to 31), defaults to self.address

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

go_to_configuration(*add*: int | None = None) → None

This method is executed during start(). It can also be executed after a reset(). The controller is put in CONFIG state, where configuration parameters can be changed.

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

initialize(*add*: int | None = None) → None

Puts the controller from the NOT_REF state to the READY state. Sends the motor to its “home” position.

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

move_to_absolute_position(*pos*: int | float, *add*: int | None = None) → None

Move the motor to the specified position.

Parameters

- **pos** – target absolute position (affected by the configured offset)
- **add** – controller address (1 to 31), defaults to self.address

Raises

- *SerialCommunicationIOError* – if the com is closed

- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

move_to_relative_position(*pos*: int | float, *add*: int | None = None) → None

Move the motor of the specified distance.

Parameters

- **pos** – distance to travel (the sign gives the direction)
- **add** – controller address (1 to 31), defaults to self.address

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

reset(*add*: int | None = None) → None

Resets the controller, equivalent to a power-up. This puts the controller back to NOT REFERENCED state, which is necessary for configuring the controller.

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

set_acceleration(*acc*: int | float, *add*: int | None = None) → None

Leave the configuration state. The configuration parameters are saved to the device's memory.

Parameters

- **acc** – acceleration (preset units/s²), value between 1e-6 and 1e12
- **add** – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

set_motor_configuration(*add*: int | None = None, *config*: dict | None = None) → None

Set the motor configuration. The motor must be in CONFIG state.

Parameters

- **add** – controller address (1 to 31)
- **config** – dictionary containing the motor's configuration

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained

- **NewportControllerError** – if the controller reports an error

set_negative_software_limit(lim: int | float, add: int | None = None) → None

Set the negative software limit (the maximum position that the motor is allowed to travel to towards the left).

Parameters

- **lim** – negative software limit (preset units), value between -1e12 and 0
- **add** – controller address (1 to 31)

Raises

- **SerialCommunicationIOError** – if the com is closed
- **NewportSerialCommunicationError** – if an unexpected answer is obtained
- **NewportControllerError** – if the controller reports an error

set_positive_software_limit(lim: int | float, add: int | None = None) → None

Set the positive software limit (the maximum position that the motor is allowed to travel to towards the right).

Parameters

- **lim** – positive software limit (preset units), value between 0 and 1e12
- **add** – controller address (1 to 31)

Raises

- **SerialCommunicationIOError** – if the com is closed
- **NewportSerialCommunicationError** – if an unexpected answer is obtained
- **NewportControllerError** – if the controller reports an error

start()

Opens the communication protocol and applies the config.

Raises

- **SerialCommunicationIOError** – when communication port cannot be opened

stop() → None

Stop the device. Close the communication protocol.

stop_motion(add: int | None = None) → None

Stop a move in progress by decelerating the positioner immediately with the configured acceleration until it stops. If a controller address is provided, stops a move in progress on this controller, else stops the moves on all controllers.

Parameters

- **add** – controller address (1 to 31)

Raises

- **SerialCommunicationIOError** – if the com is closed
- **NewportSerialCommunicationError** – if an unexpected answer is obtained
- **NewportControllerError** – if the controller reports an error

wait_until_motor_initialized(*add*: int | None = None) → None

Wait until the motor leaves the HOMING state (at which point it should have arrived to the home position).

Parameters

add – controller address (1 to 31)

Raises

- **SerialCommunicationIOError** – if the com is closed
- **NewportSerialCommunicationError** – if an unexpected answer is obtained
- **NewportControllerError** – if the controller reports an error

```
class NewportSMC100PPConfig(address: int = 1, user_position_offset: int | float = 23.987, screw_scaling: int | float = 1, exit_configuration_wait_sec: int | float = 5, move_wait_sec: int | float = 1, acceleration: int | float = 10, backlash_compensation: int | float = 0, hysteresis_compensation: int | float = 0.015, micro_step_per_full_step_factor: int = 100, motion_distance_per_full_step: int | float = 0.01, home_search_type: int | HomeSearch = HomeSearch.HomeSwitch, jerk_time: int | float = 0.04, home_search_velocity: int | float = 4, home_search_timeout: int | float = 27.5, home_search_polling_interval: int | float = 1, peak_output_current_limit: int | float = 0.4, rs485_address: int = 2, negative_software_limit: int | float = -23.5, positive_software_limit: int | float = 25, velocity: int | float = 4, base_velocity: int | float = 0, stage_configuration: int | EspStageConfig = EspStageConfig.EnableEspStageCheck)
```

Bases: object

Configuration dataclass for the Newport motor controller SMC100PP.

```
class EspStageConfig(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)
```

Bases: IntEnum

Different configurations to check or not the motor configuration upon power-up.

DisableEspStageCheck = 1

EnableEspStageCheck = 3

UpdateEspStageInfo = 2

```
class HomeSearch(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)
```

Bases: IntEnum

Different methods for the motor to search its home position during initialization.

CurrentPosition = 1

EndOfRunSwitch = 4

EndOfRunSwitch_and_Index = 3

HomeSwitch = 2

HomeSwitch_and_Index = 0

acceleration: int | float = 10

address: int = 1

backlash_compensation: int | float = 0

base_velocity: int | float = 0

clean_values()

exit_configuration_wait_sec: int | float = 5

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

home_search_polling_interval: int | float = 1

home_search_timeout: int | float = 27.5

home_search_type: int | *HomeSearch* = 2

home_search_velocity: int | float = 4

hysteresis_compensation: int | float = 0.015

is_configdataclass = True

jerk_time: int | float = 0.04

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

micro_step_per_full_step_factor: int = 100

motion_distance_per_full_step: int | float = 0.01

property motor_config: dict[str, float]

Gather the configuration parameters of the motor into a dictionary.

Returns

dict containing the configuration parameters of the motor

move_wait_sec: int | float = 1

negative_software_limit: int | float = -23.5

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

peak_output_current_limit: int | float = 0.4

positive_software_limit: int | float = 25

post_force_value(*fieldname, value*)

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

rs485_address: int = 2

screw_scaling: int | float = 1

stage_configuration: int | *EspStageConfig* = 3

user_position_offset: int | float = 23.987

velocity: int | float = 4

class NewportSMC100PPSerialCommunication(*configuration*)

Bases: *SerialCommunication*

Specific communication protocol implementation for NewportSMC100 controller. Already predefines device-specific protocol parameters in config.

class ControllerErrors(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: Enum

Possible controller errors with values as returned by the device in response to sent commands.

ADDR_INCORRECT = 'B'

CMD_EXEC_ERROR = 'V'

CMD_NOT_ALLOWED = 'D'

CMD_NOT_ALLOWED_CC = 'X'

CMD_NOT_ALLOWED_CONFIGURATION = 'I'

CMD_NOT_ALLOWED_DISABLE = 'J'

CMD_NOT_ALLOWED_HOMING = 'L'

CMD_NOT_ALLOWED_MOVING = 'M'

CMD_NOT_ALLOWED_NOT_REFERENCED = 'H'

CMD_NOT_ALLOWED_PP = 'W'

CMD_NOT_ALLOWED_READY = 'K'

CODE_OR_ADDR_INVALID = 'A'

COM_TIMEOUT = 'S'

DISPLACEMENT_OUT_OF_LIMIT = 'G'

EEPROM_ACCESS_ERROR = 'U'

ESP_STAGE_NAME_INVALID = 'F'

HOME_STARTED = 'E'

NO_ERROR = '@'

PARAM_MISSING_OR_INVALID = 'C'

POSITION_OUT_OF_LIMIT = 'N'

check_for_error(*add: int*) → *None*

Ask the Newport controller for the last error it recorded.

This method is called after every command or query.

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

query(*add: int, cmd: str, param: int | float | str | None = None*) → *str*

Send a query to the controller, read the answer, and check for errors. The prefix add+cmd is removed from the answer.

Parameters

- **add** – the controller address (1 to 31)
- **cmd** – the command to be sent
- **param** – optional parameter (int/float/str) appended to the command

Returns

the answer from the device without the prefix

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

query_multiple(*add: int, cmd: str, prefixes: list[str]*) → *list[str]*

Send a query to the controller, read the answers, and check for errors. The prefixes are removed from the answers.

Parameters

- **add** – the controller address (1 to 31)
- **cmd** – the command to be sent
- **prefixes** – prefixes of each line expected in the answer

Returns

list of answers from the device without prefix

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

read_text() → str

Read one line of text from the serial port, and check for presence of a null char which indicates that the motor power supply was cut and then restored. The input buffer may hold additional data afterwards, since only one line is read.

This method uses *self.access_lock* to ensure thread-safety.

Returns

String read from the serial port; '' if there was nothing to read.

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *NewportMotorPowerSupplyWasCutError* – if a null char is read

send_command(add: int, cmd: str, param: int | float | str | None = None) → None

Send a command to the controller, and check for errors.

Parameters

- **add** – the controller address (1 to 31)
- **cmd** – the command to be sent
- **param** – optional parameter (int/float/str) appended to the command

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

send_stop(add: int) → None

Send the general stop ST command to the controller, and check for errors.

Parameters

add – the controller address (1 to 31)

Returns

ControllerErrors reported by Newport Controller

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained

```
class NewportSMC100PPSerialCommunicationConfig(terminator: bytes = b'\n\n', encoding: str = 'ascii',
                                                encoding_error_handling: str = 'replace',
                                                wait_sec_read_text_nonempty: Union[int, float] = 0.5,
                                                default_n_attempts_read_text_nonempty: int = 10,
                                                port: Optional[str] = None, baudrate: int = 57600,
                                                parity: Union[str,
                                                                hvl_ccb.comm.serial.SerialCommunicationParity] =
                                                                <SerialCommunicationParity.NONE: 'N'>, stopbits:
                                                                Union[int,
                                                                hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                                                <SerialCommunicationStopbits.ONE: 1>, bytesize:
                                                                Union[int,
                                                                hvl_ccb.comm.serial.SerialCommunicationBytesize] =
                                                                <SerialCommunicationBytesize.EIGHTBITS: 8>,
                                                timeout: Union[int, float] = 10)
```

Bases: [SerialCommunicationConfig](#)

baudrate: `int = 57600`

Baudrate for NewportSMC100 controller is 57600 baud

bytesize: `int | SerialCommunicationBytesize = 8`

NewportSMC100 controller uses 8 bits for one data byte

encoding: `str = 'ascii'`

use ASCII as de-/encoding, cf. the manual

encoding_error_handling: `str = 'replace'`

replace bytes with instead of raising utf-8 exception when decoding fails

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod **keys**() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod **optional_defaults**() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

parity: `str | SerialCommunicationParity = 'N'`

NewportSMC100 controller does not use parity

classmethod `required_keys()` → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

stopbits: int | *SerialCommunicationStopbits* = 1

NewportSMC100 controller uses one stop bit

terminator: bytes = b'\r\n'

The terminator is CR/LF

timeout: int | float = 10

use 10 seconds timeout as default

exception `NewportSerialCommunicationError`

Bases: *NewportError*

Communication error with the Newport controller.

class `NewportStates`(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: *AutoNumberNameEnum*

States of the Newport controller. Certain commands are allowed only in certain states.

CONFIG = 3

DISABLE = 6

HOMING = 2

JOGGING = 7

MOVING = 5

NO_REF = 1

READY = 4

exception `NewportUncertainPositionError`

Bases: *NewportError*

Error with the position of the Newport motor.

Module contents

Device class for Newport SMC100PP stepper motor controller with serial communication.

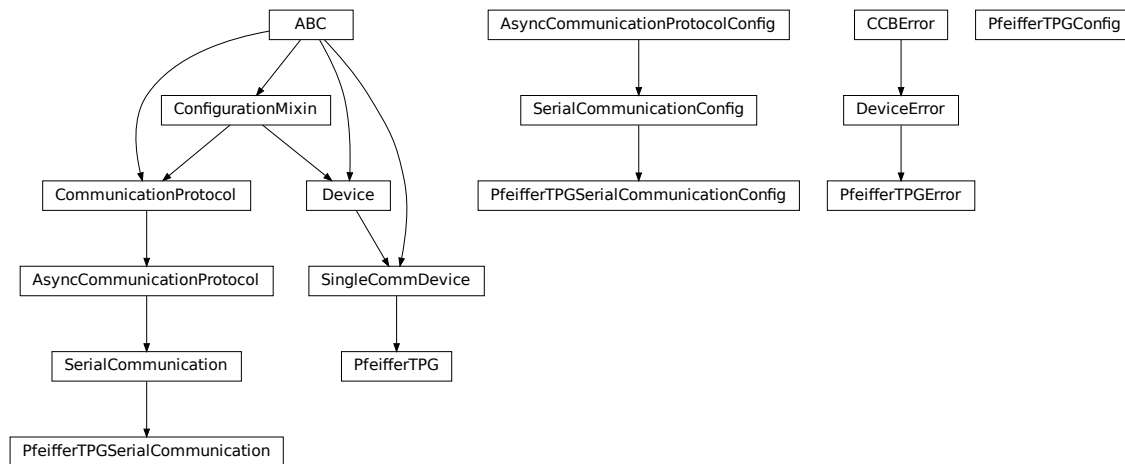
The SMC100PP is a single axis motion controller/driver for stepper motors up to 48 VDC at 1.5 A rms. Up to 31 controllers can be networked through the internal RS-485 communication link.

Manufacturer homepage: <https://www.newport.com/f/smc100-single-axis-dc-or-stepper-motion-controller>

hvl_ccb.dev.pfeiffer_tpg

Submodules

hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg



Device class for Pfeiffer TPG controllers.

The Pfeiffer TPG control units are used to control Pfeiffer Compact Gauges. Models: TPG 251 A, TPG 252 A, TPG 256A, TPG 261, TPG 262, TPG 361, TPG 362 and TPG 366.

Manufacturer homepage: <https://www.pfeiffer-vacuum.com/en/products/measurement-analysis/measurement/activeline/controllers/>

class PfeifferTPG(*com*, *dev_config=None*)

Bases: *SingleCommDevice*

Pfeiffer TPG control unit device class

class SensorStatus(*value*)

Bases: *IntEnum*

An enumeration.

Identification_error = 6

No_sensor = 5

Ok = 0

Overrange = 2

Sensor_error = 3

Sensor_off = 4

Underrange = 1

```
class SensorTypes(value)
```

Bases: Enum

An enumeration.

CMR = 4

IKR = 2

IKR11 = 2

IKR9 = 2

IMR = 5

None = 7

PBR = 6

PKR = 3

TPR = 1

noSENSOR = 7

noSen = 7

```
static config_cls()
```

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
static default_com_cls()
```

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

```
get_full_scale_mbar() → list[int | float]
```

Get the full scale range of the attached sensors

Returns

full scale range values in mbar, like *[0.01, 1, 0.1, 1000, 50000, 10]*

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *PfeifferTPGError* – if command fails

```
get_full_scale_unitless() → list[int]
```

Get the full scale range of the attached sensors. See lookup table between command and corresponding pressure in the device user manual.

Returns

list of full scale range values, like *[0, 1, 3, 3, 2, 0]*

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *PfeifferTPGError* – if command fails

identify_sensors() → *None*

Send identification request TID to sensors on all channels.

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *PfeifferTPGError* – if command fails

measure(channel: int) → tuple[str, float]

Get the status and measurement of one sensor

Parameters

channel – int channel on which the sensor is connected, with $1 \leq \text{channel} \leq \text{number_of_sensors}$

Returns

measured value as float if measurement successful, sensor status as string if not

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *PfeifferTPGError* – if command fails

measure_all() → list[tuple[str, float]]

Get the status and measurement of all sensors (this command is not available on all models)

Returns

list of measured values as float if measurements successful, and or sensor status as strings if not

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *PfeifferTPGError* – if command fails

property number_of_sensors

set_full_scale_mbar(fsr: list[int | float]) → *None*

Set the full scale range of the attached sensors (in unit mbar)

Parameters

fsr – full scale range values in mbar, for example *[0.01, 1000]*

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *PfeifferTPGError* – if command fails

set_full_scale_unitless(fsr: list[int]) → *None*

Set the full scale range of the attached sensors. See lookup table between command and corresponding pressure in the device user manual.

Parameters

fsr – list of full scale range values, like *[0, 1, 3, 3, 2, 0]*

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *PfeifferTPGError* – if command fails

start() → *None*

Start this device. Opens the communication protocol, and identify the sensors.

Raises

SerialCommunicationIOError – when communication port cannot be opened

stop() → *None*

Stop the device. Closes also the communication protocol.

property unit

The pressure unit of readings is always mbar, regardless of the display unit.

class PfeifferTPGConfig(*model: str* | *Model* = *Model.TPG25xA*)

Bases: *object*

Device configuration dataclass for Pfeiffer TPG controllers.

class Model(*value=<no_arg>*, *names=None*, *module=None*, *qualname=None*, *type=None*, *start=1*, *boundary=None*)

Bases: *NameEnum*

An enumeration.

TPG25xA = {**0.1**: 8, **1**: 0, **10**: 1, **100**: 2, **1000**: 3, **2000**: 4, **5000**: 5, **10000**: 6, **50000**: 7}

TPGx6x = {**0.01**: 0, **0.1**: 1, **1**: 2, **10**: 3, **100**: 4, **1000**: 5, **2000**: 6, **5000**: 7, **10000**: 8, **50000**: 9}

is_valid_scale_range_reversed_str(*v: str*) → *bool*

Check if given string represents a valid reversed scale range of a model.

Parameters

v – Reversed scale range string.

Returns

True if valid, *False* otherwise.

clean_values()

force_value(*fieldname, value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = *True*

classmethod keys() → *Sequence[str]*

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

model: str | *Model* = {**0.1**: 8, **1**: 0, **10**: 1, **100**: 2, **1000**: 3, **2000**: 4, **5000**: 5, **10000**: 6, **50000**: 7}

classmethod `optional_defaults()` → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod `required_keys()` → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

exception `PfeifferTPGError`

Bases: `DeviceError`

Error with the Pfeiffer TPG Controller.

class `PfeifferTPGSerialCommunication(configuration)`

Bases: `SerialCommunication`

Specific communication protocol implementation for Pfeiffer TPG controllers. Already predefines device-specific protocol parameters in config.

static `config_cls()`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

query(*cmd: str*) → str

Send a query, then read and returns the first line from the com port.

Parameters

cmd – query message to send to the device

Returns

first line read on the com

Raises

- `SerialCommunicationIOError` – when communication port is not opened
- `PfeifferTPGError` – if the device does not acknowledge the command or if the answer from the device is empty

send_command(*cmd: str*) → *None*

Send a command to the device and check for acknowledgement.

Parameters

cmd – command to send to the device

Raises

- `SerialCommunicationIOError` – when communication port is not opened
- `PfeifferTPGError` – if the answer from the device differs from the expected acknowledgement character 'chr(6)'.

```
class PfeifferTPGSerialCommunicationConfig(terminator: bytes = b'\r\n', encoding: str = 'utf-8',
                                           encoding_error_handling: str = 'strict',
                                           wait_sec_read_text_nonempty: Union[int, float] = 0.5,
                                           default_n_attempts_read_text_nonempty: int = 10, port:
                                           Optional[str] = None, baudrate: int = 9600, parity:
                                           Union[str,
                                           hvl_ccb.comm.serial.SerialCommunicationParity] =
                                           <SerialCommunicationParity.NONE: 'N'>, stopbits:
                                           Union[int,
                                           hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                           <SerialCommunicationStopbits.ONE: 1>, bytesize:
                                           Union[int,
                                           hvl_ccb.comm.serial.SerialCommunicationBytesize] =
                                           <SerialCommunicationBytesize.EIGHTBITS: 8>, timeout:
                                           Union[int, float] = 3)
```

Bases: `SerialCommunicationConfig`

baudrate: `int = 9600`

Baudrate for Pfeiffer TPG controllers is 9600 baud

bytesize: `int | SerialCommunicationBytesize = 8`

One byte is eight bits long

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

parity: `str | SerialCommunicationParity = 'N'`

Pfeiffer TPG controllers do not use parity

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

stopbits: `int` | `SerialCommunicationStopbits` = 1

Pfeiffer TPG controllers use one stop bit

terminator: `bytes` = `b'\r\n'`

The terminator is <CR><LF>

timeout: `int` | `float` = 3

use 3 seconds timeout as default

Module contents

Device class for Pfeiffer TPG controllers.

The Pfeiffer TPG control units are used to control Pfeiffer Compact Gauges. Models: TPG 251 A, TPG 252 A, TPG 256A, TPG 261, TPG 262, TPG 361, TPG 362 and TPG 366.

Manufacturer homepage: <https://www.pfeiffer-vacuum.com/en/products/measurement-analysis/> measurement/activeline/controllers/

`hvl_ccb.dev.picotech_pt104`

NOTE: `PicoSDK Python wrappers` already on import attempt to load the `PicoSDK library`; thus, the API docs can only be generated in a system with the latter installed and are by default disabled.

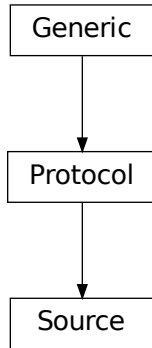
To build the API docs for this submodule locally edit the `docs/hvl_ccb.dev.picotech_pt104.rst` file to remove the `.. code-block::` directive preceding the following directives:

```
.. inheritance-diagram:: hvl_ccb.dev.picotech_pt104
   :parts: 1

.. automodule:: hvl_ccb.dev.picotech_pt104
   :members:
   :undoc-members:
   :show-inheritance:
```

`hvl_ccb.dev.protocols`

Submodules

hvl_ccb.dev.protocols.sources

class `Source(*args, **kwargs)`

Bases: `Protocol`

Protocol for a voltage/current source

(Future) Implementations:

- *ea_psi9000.PSI9000*
- *fug.Fug*
- *heinzinger.HeinzingerPNC*
- *technix.Technix*

property `current: int | float`

Return the measured output current in A

property `max_current: int | float`

Maximal output current of the hardware in A, but user can reset to a lower value

property `max_voltage: int | float`

Maximal output voltage of the hardware in V, but user can reset to a lower value

property `output: bool | None`

State of the high voltage output

property `set_current: int | float`

Return the set current (may differ from actual value) in A

property `set_voltage: int | float`

Return the set voltage (may differ from actual value) in V

property `voltage: int | float`

Return the measured output voltage in V

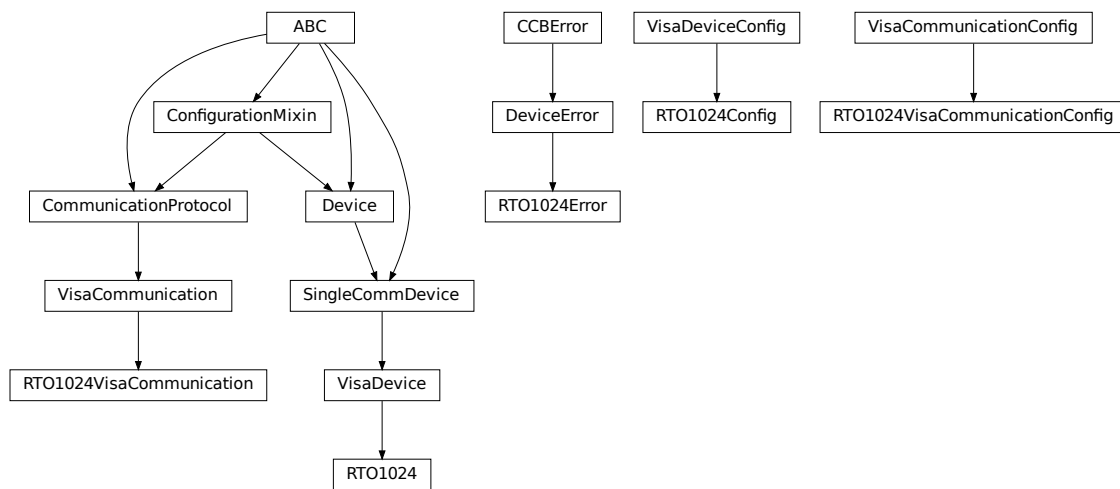
Module contents

This module has some common protocols to interface similar device with the same methods. The benefit is to be able to switch between different devices with less effort of change the code and also to keep the same “look-and-feel”.

hvl_ccb.dev.rs_rto1024

Submodules

hvl_ccb.dev.rs_rto1024.rs_rto1024



Python module for the Rhode & Schwarz RTO 1024 oscilloscope. The communication to the device is through VISA, type TCPIP / INSTR.

class **RTO1024**(*com*: [RTO1024VisaCommunication](#) | [RTO1024VisaCommunicationConfig](#) | *dict*, *dev_config*: [RTO1024Config](#) | *dict*)

Bases: [VisaDevice](#)

Device class for the Rhode & Schwarz RTO 1024 oscilloscope.

class **TriggerModes**(*value*=<no_arg>, *names*=None, *module*=None, *qualname*=None, *type*=None, *start*=1, *boundary*=None)

Bases: [AutoNumberNameEnum](#)

Enumeration for the three available trigger modes.

AUTO = 1

FREERUN = 3

NORMAL = 2

classmethod **names**()

Returns a list of the available trigger modes. :return: list of strings

activate_measurements(*meas_n: int, source: str, measurements: list[str], category: str = 'AMPTIME'*)

Activate the list of 'measurements' of the waveform 'source' in the measurement box number 'meas_n'. The list 'measurements' starts with the main measurement and continues with additional measurements of the same 'category'.

Parameters

- **meas_n** – measurement number 1..8
- **source** – measurement source, for example C1W1
- **measurements** – list of measurements, the first one will be the main measurement.
- **category** – the category of measurements, by default AMPTIME

backup_waveform(*filename: str*) → *None*

Backup a waveform file from the standard directory specified in the device configuration to the standard backup destination specified in the device configuration. The filename has to be specified without .bin or path.

Parameters

filename – The waveform filename without extension and path

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

Return the default communication protocol for this device type, which is VisaCommunication.

Returns

the VisaCommunication class

file_copy(*source: str, destination: str*) → *None*

Copy a file from one destination to another on the oscilloscope drive. If the destination file already exists, it is overwritten without notice.

Parameters

- **source** – absolute path to the source file on the DSO filesystem
- **destination** – absolute path to the destination file on the DSO filesystem

Raises

RT01024Error – if the operation did not complete

get_acquire_length() → float

Gets the time of one acquisition, that is the time across the 10 divisions of the diagram.

- Range: 250E-12 ... 500 [s]
- Increment: 1E-12 [s]

Returns

the time for one acquisition. Range: 250e-12 ... 500 [s]

get_channel_offset(*channel: int*) → float

Gets the voltage offset of the indicated channel.

Parameters

channel – is the channel number (1..4)

Returns

channel offset voltage in V (value between -1 and 1)

get_channel_position(*channel: int*) → float

Gets the vertical position of the indicated channel.

Parameters

channel – is the channel number (1..4)

Returns

channel position in div (value between -5 and 5)

get_channel_range(*channel: int*) → float

Queries the channel range in V.

Parameters

channel – is the input channel (1..4)

Returns

channel range in V

get_channel_scale(*channel: int*) → float

Queries the channel scale in V/div.

Parameters

channel – is the input channel (1..4)

Returns

channel scale in V/div

get_channel_state(*channel: int*) → bool

Queries if the channel is active or not.

Parameters

channel – is the input channel (1..4)

Returns

True if active, else False

get_reference_point() → int

Gets the reference point of the time scale in % of the display. If the “Trigger offset” is zero, the trigger point matches the reference point. ReferencePoint = zero pint of the time scale

- Range: 0 ... 100 [%]
- Increment: 1 [%]

Returns

the reference in %

get_repetitions() → int

Get the number of acquired waveforms with RUN Nx SINGLE. Also defines the number of waveforms used to calculate the average waveform.

- Range: 1 ... 16777215
- Increment: 10
- *RST = 1

Returns

the number of waveforms to acquire

get_timestamps() → list[float]

Gets the timestamps of all recorded frames in the history and returns them as a list of floats.

Returns

list of timestamps in [s]

Raises

RTO1024Error – if the timestamps are invalid

list_directory(path: str) → list[tuple[str, str, int]]

List the contents of a given directory on the oscilloscope filesystem.

Parameters

path – is the path to a folder

Returns

a list of filenames in the given folder

load_configuration(filename: str) → *None*

Load current settings from a configuration file. The filename has to be specified without base directory and '.dfl' extension.

Information from the manual *ReCall* calls up the instrument settings from an intermediate memory identified by the specified number. The instrument settings can be stored to this memory using the command *SAV with the associated number. It also activates the instrument settings which are stored in a file and loaded using *MMEMory:LOAD:STATe* .

Parameters

filename – is the name of the settings file without path and extension

local_display(state: bool) → *None*

Enable or disable local display of the scope.

Parameters

state – is the desired local display state

prepare_ultra_segmentation() → *None*

Make ready for a new acquisition in ultra segmentation mode. This function does one acquisition without ultra segmentation to clear the history and prepare for a new measurement.

read_measurement(meas_n: int, name: str) → float

Parameters

- **meas_n** – measurement number 1..8
- **name** – measurement name, for example "MAX"

Returns

measured value

run_continuous_acquisition() → *None*

Start acquiring continuously.

run_single_acquisition() → *None*

Start a single or Nx acquisition.

save_configuration(*filename: str*) → *None*

Save the current oscilloscope settings to a file. The filename has to be specified without path and '.dff' extension, the file will be saved to the configured settings directory.

Information from the manual *SAVe* stores the current instrument settings under the specified number in an intermediate memory. The settings can be recalled using the command **RCL* with the associated number. To transfer the stored instrument settings to a file, use *MMEMory:STORe:STATe* .

Parameters

filename – is the name of the settings file without path and extension

save_waveform_history(*filename: str, channel: int, waveform: int = 1*) → *None*

Save the history of one channel and one waveform to a .bin file. This function is used after an acquisition using sequence trigger mode (with or without ultra segmentation) was performed.

Parameters

- **filename** – is the name (without extension) of the file
- **channel** – is the channel number
- **waveform** – is the waveform number (typically 1)

Raises

RT01024Error – if storing waveform times out

set_acquire_length(*timerange: float*) → *None*

Defines the time of one acquisition, that is the time across the 10 divisions of the diagram.

- Range: 250E-12 ... 500 [s]
- Increment: 1E-12 [s]
- *RST = 0.5 [s]

Parameters

timerange – is the time for one acquisition. Range: 250e-12 ... 500 [s]

set_channel_offset(*channel: int, offset: float*) → *None*

Sets the voltage offset of the indicated channel.

- Range: Dependent on the channel scale and coupling [V]
- Increment: Minimum 0.001 [V], may be higher depending on the channel scale and coupling
- *RST = 0

Parameters

- **channel** – is the channel number (1..4)
- **offset** – Offset voltage. Positive values move the waveform down, negative values move it up.

set_channel_position(*channel: int, position: float*) → *None*

Sets the vertical position of the indicated channel as a graphical value.

- Range: -5.0 ... 5.0 [div]
- Increment: 0.02
- *RST = 0

Parameters

- **channel** – is the channel number (1..4)
- **position** – is the position. Positive values move the waveform up, negative values move it down.

set_channel_range(*channel: int, v_range: float*) → *None*

Sets the voltage range across the 10 vertical divisions of the diagram. Use the command alternatively instead of set_channel_scale.

- Range for range: Depends on attenuation factors and coupling. With 1:1 probe and external attenuations and 50 input coupling, the range is 10 mV to 10 V. For 1 M input coupling, it is 10 mV to 100 V. If the probe and/or external attenuation is changed, multiply the range values by the attenuation factors.
- Increment: 0.01
- *RST = 0.5

Parameters

- **channel** – is the channel number (1..4)
- **v_range** – is the vertical range [V]

set_channel_scale(*channel: int, scale: float*) → *None*

Sets the vertical scale for the indicated channel. The scale value is given in volts per division.

- Range for scale: depends on attenuation factor and coupling. With 1:1 probe and external attenuations and 50 input coupling, the vertical scale (input sensitivity) is 1 mV/div to 1 V/div. For 1 M input coupling, it is 1 mV/div to 10 V/div. If the probe and/or external attenuation is changed, multiply the values by the attenuation factors to get the actual scale range.
- Increment: 1e-3
- *RST = 0.05

See also: set_channel_range

Parameters

- **channel** – is the channel number (1..4)
- **scale** – is the vertical scaling [V/div]

set_channel_state(*channel: int, state: bool*) → *None*

Switches the channel signal on or off.

Parameters

- **channel** – is the input channel (1..4)
- **state** – is True for on, False for off

set_reference_point(*percentage: int*) → *None*

Sets the reference point of the time scale in % of the display. If the “Trigger offset” is zero, the trigger point matches the reference point. ReferencePoint = zero pint of the time scale

- Range: 0 ... 100 [%]
- Increment: 1 [%]
- *RST = 50 [%]

Parameters

percentage – is the reference in %

set_repetitions(*number: int*) → *None*

Set the number of acquired waveforms with RUN Nx SINGLE. Also defines the number of waveforms used to calculate the average waveform.

- Range: 1 ... 16777215
- Increment: 10
- *RST = 1

Parameters

number – is the number of waveforms to acquire

set_trigger_level(*channel: int, level: float, event_type: int = 1*) → *None*

Sets the trigger level for the specified event and source.

- Range: -10 to 10 V
- Increment: 1e-3 V
- *RST = 0 V

Parameters

- **channel** – indicates the trigger source.
 - 1..4 = channel 1 to 4, available for all event types 1..3
 - 5 = external trigger input on the rear panel for analog signals, available for A-event type = 1
 - 6..9 = not available
- **level** – is the voltage for the trigger level in [V].
- **event_type** – is the event type. 1: A-Event, 2: B-Event, 3: R-Event

set_trigger_mode(*mode: str | TriggerModes*) → *None*

Sets the trigger mode which determines the behavior of the instrument if no trigger occurs.

Parameters

mode – is either auto, normal, or freerun.

Raises

RT01024Error – if an invalid triggermode is selected

set_trigger_source(*channel: int, event_type: int = 1*) → *None*

Set the trigger (Event A) source channel.

Parameters

- **channel** – is the channel number (1..4)
- **event_type** – is the event type. 1: A-Event, 2: B-Event, 3: R-Event

start() → *None*

Start the RTO1024 oscilloscope and bring it into a defined state and remote mode.

stop() → *None*

Stop the RTO1024 oscilloscope, reset events and close communication. Brings back the device to a state where local operation is possible.

stop_acquisition() → *None*

Stop any acquisition.

```
class RT01024Config(waveforms_path: str, settings_path: str, backup_path: str,
                    poll_interval: int | float = 0.5,
                    poll_start_delay: int | float = 2, command_timeout_seconds: int | float = 60,
                    wait_sec_short_pause: int | float = 0.1, wait_sec_enable_history: int | float = 1,
                    wait_sec_post_acquisition_start: int | float = 2)
```

Bases: *VisaDeviceConfig*, *RT01024ConfigDefaultsBase*, *RT01024ConfigBase*

Configdataclass for the RTO1024 device.

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

exception RT01024Error

Bases: *DeviceError*

class RT01024VisaCommunication(configuration)

Bases: *VisaCommunication*

Specialization of VisaCommunication for the RTO1024 oscilloscope

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class RT01024VisaCommunicationConfig(host: str | IPv4Address | IPv6Address, interface_type: str |
                                     InterfaceType = InterfaceType.TCPIP_INSTR, board: int = 0, port:
                                     int = 5025, timeout: int = 5000, chunk_size: int = 204800,
                                     open_timeout: int = 1000, write_termination: str = '\n',
                                     read_termination: str = '\n', visa_backend: str = "")
```

Bases: [VisaCommunicationConfig](#)

Configuration dataclass for VisaCommunication with specifications for the RTO1024 device class.

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

interface_type: str | [InterfaceType](#) = 2

Interface type of the VISA connection, being one of [InterfaceType](#).

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

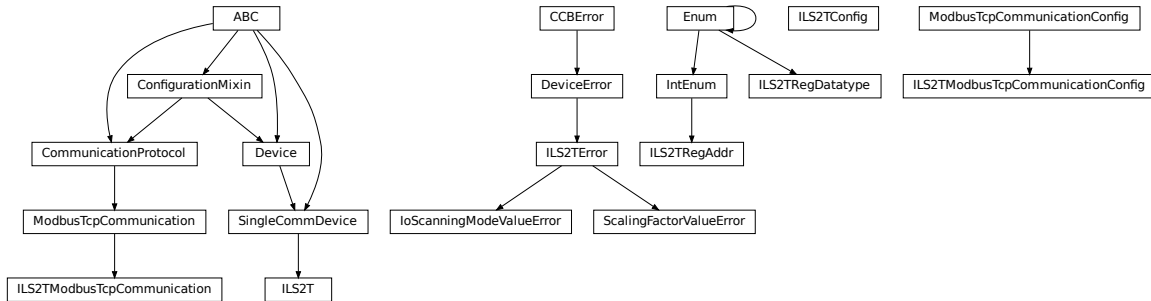
Module contents

Python module for the Rhode & Schwarz RTO 1024 oscilloscope. The communication to the device is through VISA, type TCPIP / INSTR.

hvl_ccb.dev.se_ils2t

Submodules

hvl_ccb.dev.se_ils2t.se_ils2t



Device class for controlling a Schneider Electric ILS2T stepper drive over modbus TCP.

```
class ILS2T(com, dev_config=None)
```

Bases: [SingleCommDevice](#)

Schneider Electric ILS2T stepper drive class.

```
ACTION_JOG_VALUE = 0
```

The single action value for *ILS2T.Mode.JOG*

```
class ActionsPtp(value)
```

Bases: [IntEnum](#)

Allowed actions in the point to point mode (*ILS2T.Mode.PTP*).

```
ABSOLUTE_POSITION = 0
```

```
RELATIVE_POSITION_MOTOR = 2
```

```
RELATIVE_POSITION_TARGET = 1
```

```
DEFAULT_IO_SCANNING_CONTROL_VALUES = {'action': 2, 'continue_after_stop_cu': 0,
    'disable_driver_di': 0, 'enable_driver_en': 0, 'execute_stop_sh': 0,
    'fault_reset_fr': 0, 'mode': 3, 'quick_stop_qs': 0, 'ref_16': 1500, 'ref_32':
    0, 'reset_stop_ch': 0}
```

Default IO Scanning control mode values

```
class Mode(value)
```

Bases: [IntEnum](#)

ILS2T device modes

```
JOG = 1
```

```
PTP = 3
```

class `Ref16Jog(value)`

Bases: `Flag`

Allowed values for ILS2T ref_16 register (the shown values are the integer representation of the bits), all in Jog mode = 1

FAST = 4

NEG = 2

NEG_FAST = 6

NONE = 0

POS = 1

POS_FAST = 5

RegAddr

Modbus Register Adresses

alias of *ILS2TRegAddr*

RegDatatype

Modbus Register Datatypes

alias of *ILS2TRegDatatype*

class `State(value)`

Bases: `IntEnum`

State machine status values

ON = 6

QUICKSTOP = 7

READY = 4

static `config_cls()`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static `default_com_cls()`

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

disable(*log_warn*: `bool = True`, *wait_sec_max*: `int | None = None`) → `bool`

Disable the driver of the stepper motor and enable the brake.

Note: the driver cannot be disabled if the motor is still running.

Parameters

- **log_warn** – if log a warning in case the motor cannot be disabled.
- **wait_sec_max** – maximal wait time for the motor to stop running and to disable it; by default, with *None*, use a config value

Returns

True if disable request could and was sent, *False* otherwise.

do_ioscanning_write(**kwargs: int) → *None*

Perform a write operation using IO Scanning mode.

Parameters

kwargs – Keyword-argument list with options to send, remaining are taken from the defaults.

enable() → *None*

Enable the driver of the stepper motor and disable the brake.

execute_absolute_position(position: int) → bool

Execute a absolute position change, i.e. enable motor, perform absolute position change, wait until done and disable motor afterwards.

Check position at the end if wrong do not raise error; instead just log and return check result.

Parameters

position – absolute position of motor in user defined steps.

Returns

True if actual position is as expected, *False* otherwise.

execute_relative_step(steps: int) → bool

Execute a relative step, i.e. enable motor, perform relative steps, wait until done and disable motor afterwards.

Check position at the end if wrong do not raise error; instead just log and return check result.

Parameters

steps – Number of steps.

Returns

True if actual position is as expected, *False* otherwise.

get_dc_volt() → float

Read the DC supply voltage of the motor.

Returns

DC input voltage.

get_error_code() → dict[int, dict[str, Any]]

Read all messages in fault memory. Will read the full error message and return the decoded values. At the end the fault memory of the motor will be deleted. In addition, `reset_error` is called to re-enable the motor for operation.

Returns

Dictionary with all information

get_position() → int

Read the position of the drive and store into status.

Returns

Position step value

get_status() → dict[str, int]

Perform an IO Scanning read and return the status of the motor.

Returns

dict with status information.

get_temperature() → int

Read the temperature of the motor.

Returns

Temperature in degrees Celsius.

jog_run(*direction: bool = True, fast: bool = False*) → *None*

Slowly turn the motor in positive direction.

jog_stop() → *None*

Stop turning the motor in Jog mode.

quickstop() → *None*

Stops the motor with high deceleration rate and falls into error state. Reset with *reset_error* to recover into normal state.

reset_error() → *None*

Resets the motor into normal state after quick stop or another error occurred.

set_jog_speed(*slow: int = 60, fast: int = 180*) → *None*

Set the speed for jog mode. Default values correspond to startup values of the motor.

Parameters

- **slow** – RPM for slow jog mode.
- **fast** – RPM for fast jog mode.

set_max_acceleration(*rpm_minute: int*) → *None*

Set the maximum acceleration of the motor.

Parameters

rpm_minute – revolution per minute per minute

set_max_deceleration(*rpm_minute: int*) → *None*

Set the maximum deceleration of the motor.

Parameters

rpm_minute – revolution per minute per minute

set_max_rpm(*rpm: int*) → *None*

Set the maximum RPM.

Parameters

rpm – revolution per minute (0 < rpm <= RPM_MAX)

Raises

ILS2TError – if RPM is out of range

set_ramp_type(*ramp_type: int = -1*) → *None*

Set the ramp type. There are two options available:

0: linear ramp -1: motor optimized ramp

Parameters

ramp_type – 0: linear ramp | -1: motor optimized ramp

start() → *None*

Start this device.

stop() → *None*

Stop this device. Disables the motor (applies brake), disables access and closes the communication protocol.

user_steps(*steps: int = 16384, revolutions: int = 1*) → *None*

Define steps per revolution. Default is 16384 steps per revolution. Maximum precision is 32768 steps per revolution.

Parameters

- **steps** – number of steps in *revolutions*.
- **revolutions** – number of revolutions corresponding to *steps*.

write_absolute_position(*position: int*) → *None*

Write instruction to turn the motor until it reaches the absolute position. This function does not enable or disable the motor automatically.

Parameters

position – absolute position of motor in user defined steps.

write_relative_step(*steps: int*) → *None*

Write instruction to turn the motor the relative amount of steps. This function does not enable or disable the motor automatically.

Parameters

steps – Number of steps to turn the motor.

```
class ILS2TConfig(rpm_max_init: Integral = 1500, wait_sec_post_enable: int | float = 1,  
                 wait_sec_max_disable: int | float = 10, wait_sec_post_cannot_disable: int | float = 1,  
                 wait_sec_post_relative_step: int | float = 2, wait_sec_post_absolute_position: int | float = 2)
```

Bases: object

Configuration for the ILS2T stepper motor device.

clean_values()

force_value(*fieldname, value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = **True**

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod **required_keys()** → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

rpm_max_init: **Integral** = **1500**

initial maximum RPM for the motor, can be set up to 3000 RPM. The user is allowed to set a new max RPM at runtime using *ILS2T.set_max_rpm()*, but the value must never exceed this configuration setting.

wait_sec_max_disable: **int** | **float** = **10**

wait_sec_post_absolute_position: **int** | **float** = **2**

wait_sec_post_cannot_disable: **int** | **float** = **1**

wait_sec_post_enable: **int** | **float** = **1**

wait_sec_post_relative_step: **int** | **float** = **2**

exception **ILS2TError**

Bases: *DeviceError*

Error to indicate problems with the SE ILS2T stepper motor.

class **ILS2TModbusTcpCommunication**(*configuration*)

Bases: *ModbusTcpCommunication*

Specific implementation of Modbus/TCP for the Schneider Electric ILS2T stepper motor.

static **config_cls()**

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

class **ILS2TModbusTcpCommunicationConfig**(*host: str | IPv4Address | IPv6Address, unit: int = 255, port: int = 502*)

Bases: *ModbusTcpCommunicationConfig*

Configuration dataclass for Modbus/TCP communication specific for the Schneider Electric ILS2T stepper motor.

force_value(*fieldname, value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod **keys()** → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod **optional_defaults()** → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod **required_keys()** → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

unit: int = 255

The unit has to be 255 such that IO scanning mode works.

class **ILS2TRegAddr**(*value*)

Bases: IntEnum

Modbus Register Adresses for for Schneider Electric ILS2T stepper drive.

ACCESS_ENABLE = 282

FLT_INFO = 15362

FLT_MEM_DEL = 15112

FLT_MEM_RESET = 15114

IO_SCANNING = 6922

JOGN_FAST = 10506

JOGN_SLOW = 10504

POSITION = 7706

RAMP_ACC = 1556

RAMP_DECEL = 1558

RAMP_N_MAX = 1554

RAMP_TYPE = 1574

SCALE = 1550

TEMP = 7200

VOLT = 7198

```
class ILS2TRegDatatype(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,  
                      boundary=None)
```

Bases: Enum

Modbus Register Datatypes for Schneider Electric ILS2T stepper drive.

From the manual of the drive:

datatype	byte	min	max
INT8	1 Byte	-128	127
UINT8	1 Byte	0	255
INT16	2 Byte	-32_768	32_767
UINT16	2 Byte	0	65_535
INT32	4 Byte	-2_147_483_648	2_147_483_647
UINT32	4 Byte	0	4_294_967_295
BITS	just 32bits	N/A	N/A

INT32 = (-2147483648, 2147483647)

is_in_range(*value: int*) → bool

exception IoScanningModeValueError

Bases: [ILS2TError](#)

Error to indicate that the selected IO scanning mode is invalid.

exception ScalingFactorValueError

Bases: [ILS2TError](#)

Error to indicate that a scaling factor value is invalid.

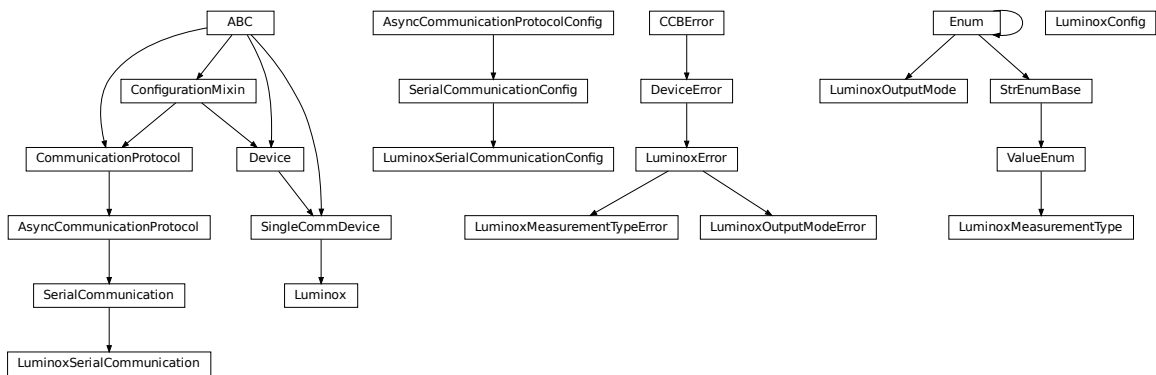
Module contents

Device class for controlling a Schneider Electric ILS2T stepper drive over modbus TCP.

[hvl_ccb.dev.sst_luminos](#)

Submodules

hvl_ccb.dev.sst_luminox.sst_luminox



Device class for a SST Luminox Oxygen sensor. This device can measure the oxygen concentration between 0 % and 25 %.

Furthermore, it measures the barometric pressure and internal temperature. The device supports two operating modes: in streaming mode the device measures all parameters every second, in polling mode the device measures only after a query.

Technical specification and documentation for the device can be found at the manufacturer's page: <https://www.sstsensing.com/product/luminox-optical-oxygen-sensors-2/>

class Luminox(*com*, *dev_config=None*)

Bases: *SingleCommDevice*

Luminox oxygen sensor device class.

activate_output(*mode: LuminoxOutputMode*) → *None*

activate the selected output mode of the Luminox Sensor. :param mode: polling or streaming

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

query_polling(*measurement: str | LuminoxMeasurementType*) → dict[str | *LuminoxMeasurementType*, float | int | str] | float | int | str

Query a value or values of Luminox measurements in the polling mode, according to a given measurement type.

Parameters

measurement – type of measurement

Returns

value of requested measurement

Raises

- **ValueError** – when a wrong key for `LuminoxMeasurementType` is provided
- **`LuminoxOutputModeError`** – when polling mode is not activated
- **`LuminoxMeasurementTypeError`** – when expected measurement value is not read

read_streaming() → dict[str | `LuminoxMeasurementType`, float | int | str]

Read values of Luminox in the streaming mode. Convert the single string into separate values.

Returns

dictionary with `LuminoxMeasurementType.all_measurements_types()` keys and accordingly type-parsed values.

Raises

- **`LuminoxOutputModeError`** – when streaming mode is not activated
- **`LuminoxMeasurementTypeError`** – when any of expected measurement values is not read

start() → *None*

Start this device. Opens the communication protocol.

stop() → *None*

Stop the device. Closes also the communication protocol.

class LuminoxConfig(*wait_sec_post_activate: int | float = 0.5, wait_sec_trials_activate: int | float = 0.1, nr_trials_activate: int = 5*)

Bases: object

Configuration for the SST Luminox oxygen sensor.

clean_values()

force_value(*fieldname, value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

nr_trials_activate: int = 5

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod `required_keys()` → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

`wait_sec_post_activate: int | float = 0.5`

`wait_sec_trials_activate: int | float = 0.1`

exception `LuminoxError`

Bases: `DeviceError`

General Error for Luminox Device.

class `LuminoxMeasurementType`(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)

Bases: `ValueEnum`

Measurement types for `LuminoxOutputMode.polling`.

The `all_measurements` type will read values for the actual measurement types as given in `LuminoxOutputMode.all_measurements_types()`; it parses multiple single values using regexp's for other measurement types, therefore, no regexp is defined for this measurement type.

`all_measurements = 'A'`

classmethod `all_measurements_types()` → tuple[`LuminoxMeasurementType`, ...]

A tuple of `LuminoxMeasurementType` enum instances which are actual measurements, i.e. not date of manufacture or software revision.

`barometric_pressure = 'P'`

property `command: str`

`date_of_manufacture = '# 0'`

`parse_read_measurement_value(read_txt: str) → dict[str | LuminoxMeasurementType, float | int | str] | float | int | str`

`partial_pressure_o2 = 'O'`

`percent_o2 = '%'`

`sensor_status = 'e'`

`serial_number = '# 1'`

`software_revision = '# 2'`

`temperature_sensor = 'T'`

LuminoxMeasurementTypeDict

A typing hint for a dictionary holding `LuminoxMeasurementType` values. Keys are allowed as strings because `LuminoxMeasurementType` is of a `StrEnumBase` type.

exception `LuminoxMeasurementTypeError`

Bases: `LuminoxError`

Wrong measurement type for requested data

LuminoxMeasurementTypeValue

A typing hint for all possible LuminoxMeasurementType values as read in either streaming mode or in a polling mode with *LuminoxMeasurementType.all_measurements*.

Beware: has to be manually kept in sync with *LuminoxMeasurementType* instances *cast_type* attribute values.

alias of Union[float, int, str]

class LuminoxOutputMode(value)

Bases: Enum

output mode.

polling = 1

streaming = 0

exception LuminoxOutputModeError

Bases: *LuminoxError*

Wrong output mode for requested data

class LuminoxSerialCommunication(configuration)

Bases: *SerialCommunication*

Specific communication protocol implementation for the SST Luminox oxygen sensor. Already predefines device-specific protocol parameters in config.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class LuminoxSerialCommunicationConfig(terminator: bytes = b'\n', encoding: str = 'utf-8',
                                         encoding_error_handling: str = 'strict',
                                         wait_sec_read_text_nonempty: Union[int, float] = 0.5,
                                         default_n_attempts_read_text_nonempty: int = 10, port:
                                         Optional[str] = None, baudrate: int = 9600, parity: Union[str,
                                         hvl_ccb.comm.serial.SerialCommunicationParity] =
                                         <SerialCommunicationParity.NONE: 'N'>, stopbits: Union[int,
                                         hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                         <SerialCommunicationStopbits.ONE: 1>, bytesize: Union[int,
                                         hvl_ccb.comm.serial.SerialCommunicationBytesize] =
                                         <SerialCommunicationBytesize.EIGHTBITS: 8>, timeout:
                                         Union[int, float] = 3)
```

Bases: *SerialCommunicationConfig*

baudrate: int = 9600

Baudrate for SST Luminox is 9600 baud

bytesize: int | SerialCommunicationBytesize = 8

One byte is eight bits long

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod **keys()** → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod **optional_defaults()** → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

parity: str | *SerialCommunicationParity* = 'N'

SST Luminos does not use parity

classmethod **required_keys()** → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

stopbits: int | *SerialCommunicationStopbits* = 1

SST Luminos does use one stop bit

terminator: bytes = b'\r\n'

The terminator is CR LF

timeout: int | float = 3

use 3 seconds timeout as default

Module contents

Device class for a SST Luminos Oxygen sensor. This device can measure the oxygen concentration between 0 % and 25 %.

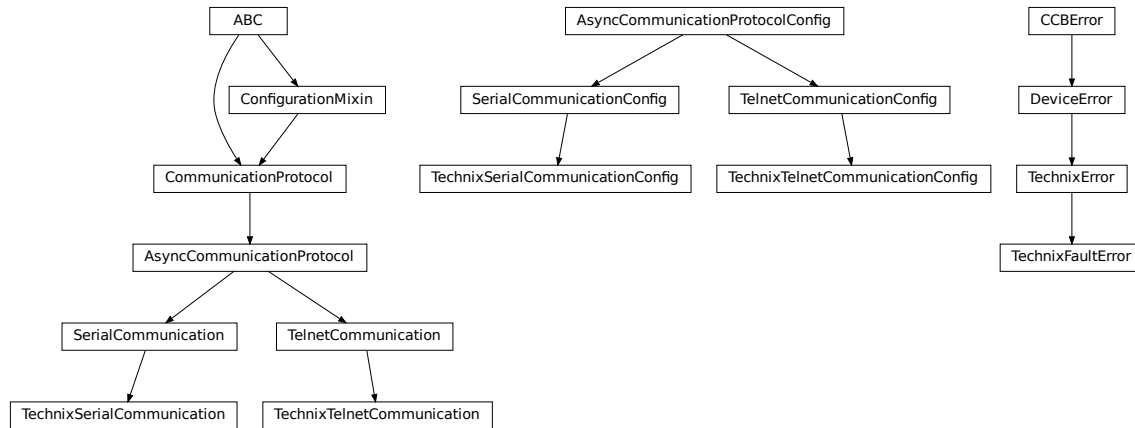
Furthermore, it measures the barometric pressure and internal temperature. The device supports two operating modes: in streaming mode the device measures all parameters every second, in polling mode the device measures only after a query.

Technical specification and documentation for the device can be found at the manufacturer's page: <https://www.sstsensing.com/product/luminos-optical-oxygen-sensors-2/>

`hvl_ccb.dev.technix`

Submodules

`hvl_ccb.dev.technix.base`



Communication and auxiliary classes for Technix

exception `TechnixError`

Bases: `DeviceError`

Technix related errors.

exception `TechnixFaultError`

Bases: `TechnixError`

Raised when the fault flag was detected while the interlock is closed

class `TechnixSerialCommunication(configuration)`

Bases: `_TechnixCommunication`, `SerialCommunication`

Serial communication for Technix

static `config_cls()`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class TechnixSerialCommunicationConfig(terminator: bytes = b'\r', encoding: str = 'utf-8',
                                       encoding_error_handling: str = 'strict',
                                       wait_sec_read_text_nonempty: int | float = 0.5,
                                       default_n_attempts_read_text_nonempty: int = 10, port: str |
                                       None = None, baudrate: int = 9600, parity: str |
                                       SerialCommunicationParity =
                                       SerialCommunicationParity.NONE, stopbits: int | float |
                                       SerialCommunicationStopbits =
                                       SerialCommunicationStopbits.ONE, bytesize: int |
                                       SerialCommunicationBytesize =
                                       SerialCommunicationBytesize.EIGHTBITS, timeout: int | float =
                                       2)
```

Bases: `_TechnixCommunicationConfig`, `SerialCommunicationConfig`

Configuration for the serial communication for Technix

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

```
class TechnixTelnetCommunication(configuration)
```

Bases: `TelnetCommunication`, `_TechnixCommunication`

Telnet communication for Technix

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class TechnixTelnetCommunicationConfig(terminator: bytes = b'\r', encoding: str = 'utf-8',
                                       encoding_error_handling: str = 'strict',
                                       wait_sec_read_text_nonempty: int | float = 0.5,
                                       default_n_attempts_read_text_nonempty: int = 10, host: str |
                                       IPv4Address | IPv6Address | None = None, port: int = 4660,
                                       timeout: int | float = 0.2)
```

Bases: `_TechnixCommunicationConfig`, `TelnetCommunicationConfig`

Configuration for the telnet communication for Technix

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define `post_force_value` method with same signature as this method to do extra processing after `value` has been forced on `fieldname`.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

port: `int = 4660`

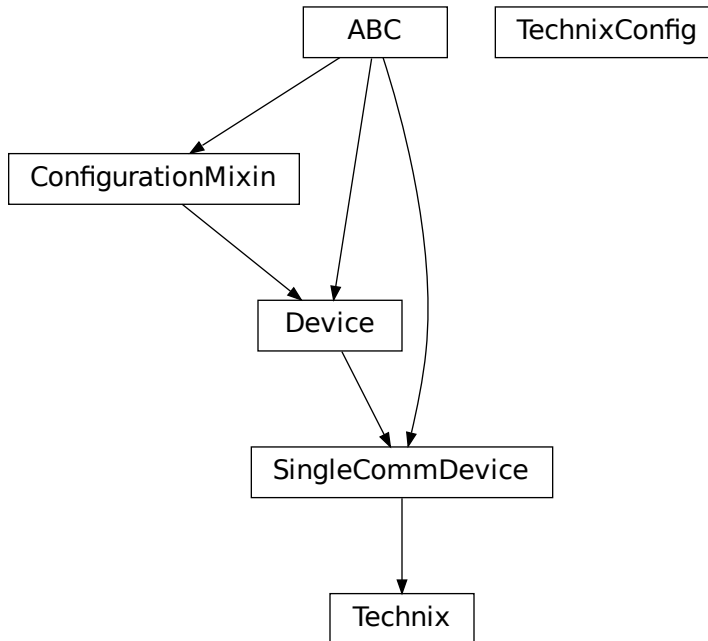
Port at which Technix is listening

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

hvl_ccb.dev.technix.device

its corresponding configuration class

The device class *Technix* and

```
class Technix(com, dev_config)
```

Bases: *SingleCommDevice*

Device class to control capacitor chargers from Technix

```
static config_cls()
```

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
property current: int | float
```

Actual current of the output in A

```
default_com_cls() → type[TechnixSerialCommunication] | type[TechnixTelnetCommunication]
```

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

```
property inhibit: bool | None
```

Is the output of the voltage inhibited? The output stage can still be active.

```
property is_started: bool
```

Is the device started?

property max_current: int | float

Maximal output current of the hardware in A

property max_voltage: int | float

Maximal output voltage of the hardware in V

property open_interlock: bool | *None*

Is the interlock open? (in safe mode)

property output: bool | *None*

State of the high voltage output

query_status(*, *_retry: bool = False*)

Query the status of the device.

Returns

This function returns nothing

property remote: bool | *None*

Is the device in remote control mode?

property set_current: int | float

Return the set current (may differ from actual value) in A

property set_voltage: int | float

Return the set voltage (may differ from actual value) in V

start()

Start the device and set it into the remote controllable mode. The high voltage is turn off, and the status poller is started.

property status: *_Status* | *None*

The status of the device with the different states as sub-fields

stop()

Stop the device. The status poller is stopped and the high voltage output is turn off.

property voltage: int | float

Actual voltage at the output in V

property voltage_regulation: bool | *None*

Status if the output is in voltage regulation mode (or current regulation)

class TechnixConfig(*communication_channel: type[hvl_ccb.dev.technix.base.TechnixSerialCommunication] | type[hvl_ccb.dev.technix.base.TechnixTelnetCommunication], max_voltage: int | float, max_current: int | float, polling_interval_sec: int | float = 4, post_stop_pause_sec: int | float = 1, register_pulse_time: int | float = 0.1, read_output_while_polling: bool = False*)

Bases: object

clean_values()

Cleans and enforces configuration values. Does nothing by default, but may be overridden to add custom configuration value checks.

communication_channel: type[*TechnixSerialCommunication*] | type[*TechnixTelnetCommunication*]

communication channel between computer and Technix

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = **True**

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

max_current: int | float

Maximal Output current

max_voltage: int | float

Maximal Output voltage

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

polling_interval_sec: int | float = 4

Polling interval in s to maintain to watchdog of the device

post_stop_pause_sec: int | float = 1

Time to wait after stopping the device

read_output_while_polling: bool = False

Read output voltage and current within the polling event

register_pulse_time: int | float = 0.1

Time for pulsing a register

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

Module contents

Device classes for “RS 232” and “Ethernet” interfaces, which are used to control power supplies from Technix. Manufacturer homepage: <https://www.technix-hv.com>

The regulated power supplies series and capacitor chargers series from Technix are series of low and high voltage direct current power supplies as well as capacitor chargers. The class *Technix* is tested with a CCR10KV-7,5KJ via an ethernet connection as well as a CCR15-P-2500-OP via a serial connection. Check the code carefully before using it with other devices or device series

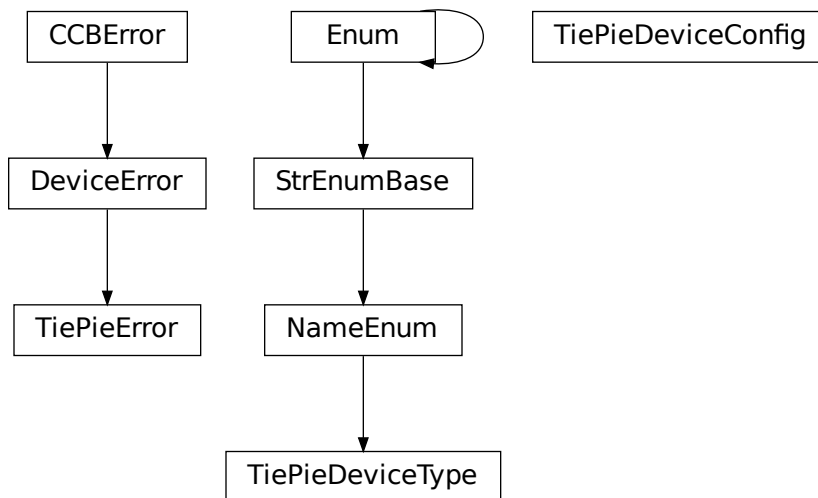
This Python package may support the following interfaces from Technix:

- Remote Interface RS232
- Ethernet Remote Interface
- Optic Fiber Remote Interface

hvl_ccb.dev.tiepie

Submodules

hvl_ccb.dev.tiepie.base



```
class TiePieDeviceConfig(serial_number: int, require_block_measurement_support: bool = True,
                          n_max_try_get_device: int = 10, wait_sec_retry_get_device: int | float = 1.0,
                          is_data_ready_polling_interval_sec: int | float = 0.01)
```

Bases: object

Configuration dataclass for TiePie

clean_values()

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True

is_data_ready_polling_interval_sec: int | float = 0.01

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

n_max_try_get_device: int = 10

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

require_block_measurement_support: bool = True

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

serial_number: int

wait_sec_retry_get_device: int | float = 1.0

class TiePieDeviceType(*value=<no_arg>*, *names=None*, *module=None*, *qualname=None*, *type=None*, *start=1*, *boundary=None*)

Bases: [NameEnum](#)

TiePie device type.

GENERATOR = 2

OSCILLOSCOPE = 1

exception TiePieError

Bases: [DeviceError](#)

Error of the class TiePie

get_device_by_serial_number(*serial_number: int, device_type: str | tuple[int, _LtpDeviceReturnType], n_max_try_get_device: int = 10, wait_sec_retry_get_device: float = 1.0*) → *_LtpDeviceReturnType*

Open and return handle of TiePie device with a given serial number

Parameters

- **serial_number** – int serial number of the device
- **device_type** – a *TiePieDeviceType* instance containing device identifier (int number) and its corresponding class, both from *libtiepie*, or a string name of such instance
- **n_max_try_get_device** – maximal number of device list updates (int number)
- **wait_sec_retry_get_device** – waiting time in seconds between retries (int number)

Returns

Instance of a *libtiepie* device class according to the specified *device_type*

Raises

- **TiePieError** – when there is no device with given serial number
- **ValueError** – when *device_type* is not an instance of *TiePieDeviceType*

wrap_libtiepie_exception(*func: Callable*) → *Callable*

Decorator wrapper for *libtiepie* methods that use *libtiepie.library.check_last_status_raise_on_error()* calls.

Parameters

func – Function or method to be wrapped

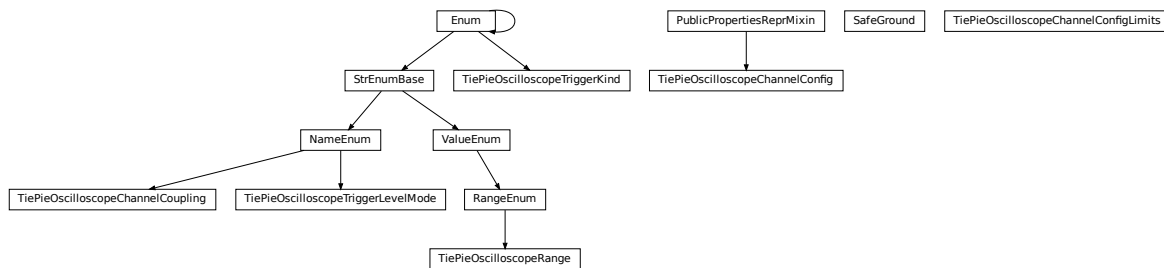
Raises

TiePieError – instead of *LibTiePieException* or one of its subtypes.

Returns

whatever *func* returns

hvl_ccb.dev.tiepie.channel



class SafeGround

Bases: object

Class that dynamically adds the `safeground_enabled` attribute getter/setter if the bound oscilloscope has the safe-ground option.

```
class TiePieOscilloscopeChannelConfig(ch_number: int, channel: OscilloscopeChannel)
```

Bases: *PublicPropertiesReprMixin*

Oscilloscope's channel configuration, with cleaning of values in properties setters as well as setting and reading them on and from the device's channel.

```
static clean_coupling(coupling: str | TiePieOscilloscopeChannelCoupling) →  
TiePieOscilloscopeChannelCoupling
```

```
static clean_enabled(enabled: bool) → bool
```

```
clean_input_range(input_range: float | TiePieOscilloscopeRange) → TiePieOscilloscopeRange
```

```
clean_probe_offset(probe_offset: float) → float
```

```
static clean_trigger_enabled(trigger_enabled)
```

```
clean_trigger_hysteresis(trigger_hysteresis: float) → float
```

```
static clean_trigger_kind(trigger_kind: str | TiePieOscilloscopeTriggerKind) →  
TiePieOscilloscopeTriggerKind
```

```
clean_trigger_level(trigger_level: int | float) → float
```

```
static clean_trigger_level_mode(level_mode: str | TiePieOscilloscopeTriggerLevelMode) →  
TiePieOscilloscopeTriggerLevelMode
```

```
property coupling: TiePieOscilloscopeChannelCoupling
```

```
property enabled: bool
```

```
property has_safeground: bool
```

Check whether bound oscilloscope device has "safeground" option

Returns

bool: 1=safeground available

```
property input_range: TiePieOscilloscopeRange
```

```
property probe_offset: float
```

```
property trigger_enabled: bool
```

```
property trigger_hysteresis: float
```

```
property trigger_kind: TiePieOscilloscopeTriggerKind
```

```
property trigger_level: float
```

```
property trigger_level_mode: TiePieOscilloscopeTriggerLevelMode
```

```
class TiePieOscilloscopeChannelConfigLimits(osc_channel: OscilloscopeChannel)
```

Bases: object

Default limits for oscilloscope channel parameters.

```
class TiePieOscilloscopeChannelCoupling(value=<no_arg>, names=None, module=None,  
qualname=None, type=None, start=1, boundary=None)
```

Bases: *NameEnum*

An enumeration.

ACA = 8

ACV = 2

DCA = 4

DCV = 1

class TiePieOscilloscopeRange(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: [*RangeEnum*](#)

An enumeration.

EIGHTY_VOLT = 80.0

EIGHT_HUNDRED_MILLI_VOLT = 0.8

EIGHT_VOLT = 8.0

FORTY_VOLT = 40.0

FOUR_HUNDRED_MILLI_VOLT = 0.4

FOUR_VOLT = 4.0

TWENTY_VOLT = 20.0

TWO_HUNDRED_MILLI_VOLT = 0.2

TWO_VOLT = 2.0

class TiePieOscilloscopeTriggerKind(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: Enum

An enumeration.

ANY = 16

FALLING = 2

RISING = 1

class TiePieOscilloscopeTriggerLevelMode(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: [*NameEnum*](#)

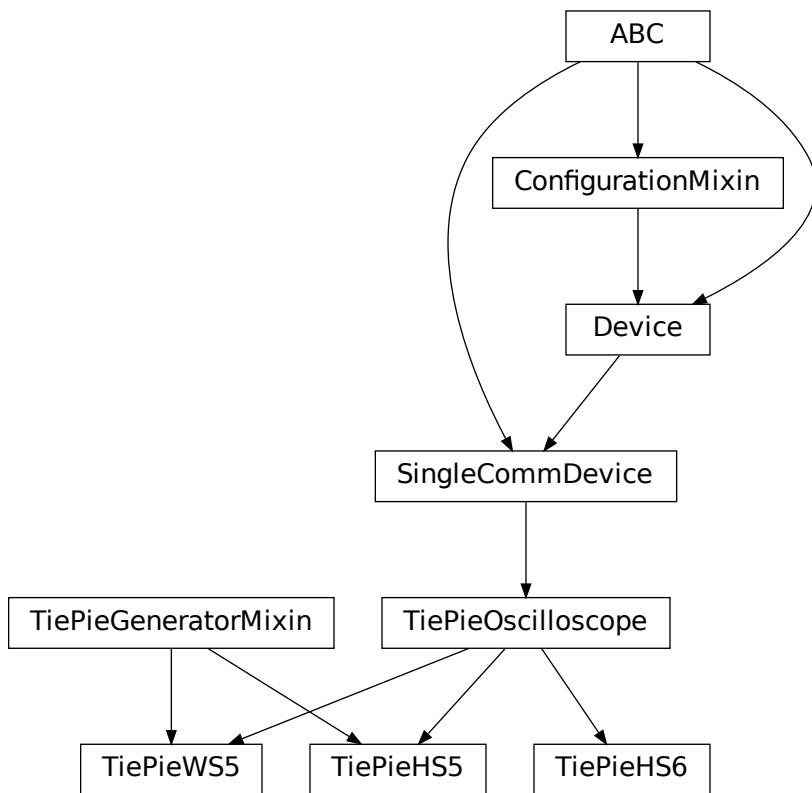
An enumeration.

ABSOLUTE = 2

RELATIVE = 1

UNKNOWN = 0

hvl_ccb.dev.tiepie.device



TiePie devices.

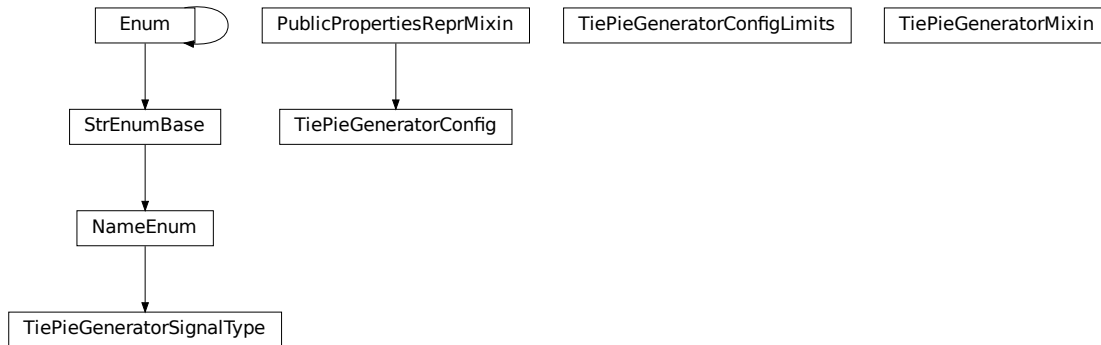
```

class TiePieHS5(com, dev_config)
    Bases: TiePieGeneratorMixin, TiePieOscilloscope
    TiePie HS5 device.

class TiePieHS6(com, dev_config)
    Bases: TiePieOscilloscope
    TiePie HS6 DIFF device.

class TiePieWS5(com, dev_config)
    Bases: TiePieGeneratorMixin, TiePieOscilloscope
    TiePie WS5 device.
  
```

hvl_ccb.dev.tiepie.generator



```
class TiePieGeneratorConfig(dev_gen: Generator)
```

Bases: [PublicPropertiesReprMixin](#)

Generator's configuration with cleaning of values in properties setters.

property `amplitude`: `float`

clean_amplitude(*amplitude*: `float`) → `float`

static clean_enabled(*enabled*: `bool`) → `bool`

clean_frequency(*frequency*: `float`) → `float`

clean_offset(*offset*: `float`) → `float`

static clean_signal_type(*signal_type*: `int` | [TiePieGeneratorSignalType](#)) → [TiePieGeneratorSignalType](#)

clean_waveform(*waveform*: `ndarray[Any, dtype[_ScalarType_co]]`) → `ndarray[Any, dtype[_ScalarType_co]]`

property `enabled`: `bool`

property `frequency`: `float`

property `offset`: `float`

property `signal_type`: [TiePieGeneratorSignalType](#)

property `waveform`: `ndarray[Any, dtype[_ScalarType_co]]` | `None`

```
class TiePieGeneratorConfigLimits(dev_gen: Generator)
```

Bases: `object`

Default limits for generator parameters.


```
class TiePieGeneratorMixin(com, dev_config)
```

Bases: `object`

TiePie Generator sub-device.

A wrapper for the *libtiepie.generator.Generator* class. To be mixed in with *TiePieOscilloscope* base class.

```
config_gen: TiePieGeneratorConfig | None
```

Generator's dynamical configuration.

```
generator_start()
```

Start signal generation.

```
generator_stop()
```

Stop signal generation.

```
start()  $\rightarrow$  None
```

Start the Generator.

```
stop()  $\rightarrow$  None
```

Stop the generator.

```
class TiePieGeneratorSignalType(value=<no_arg>, names=None, module=None, qualname=None,  
                                type=None, start=1, boundary=None)
```

Bases: *NameEnum*

An enumeration.

```
ARBITRARY = 32
```

```
DC = 8
```

```
NOISE = 16
```

```
PULSE = 64
```

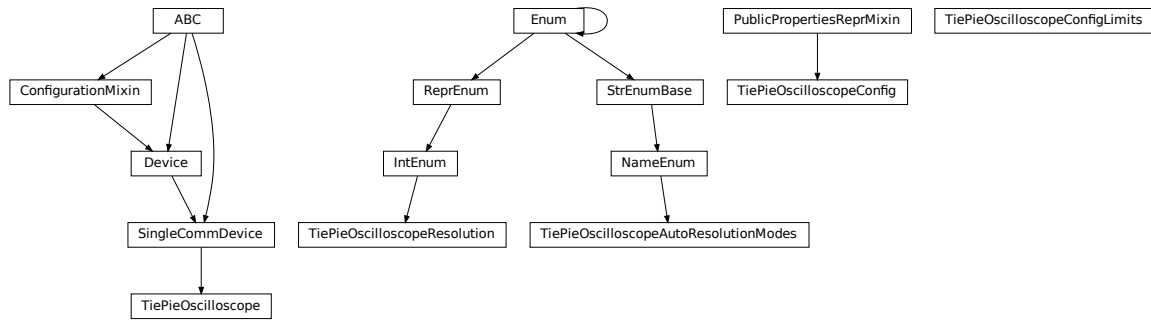
```
SINE = 1
```

```
SQUARE = 4
```

```
TRIANGLE = 2
```

```
UNKNOWN = 0
```

hvl_ccb.dev.tiepie.oscilloscope



class `TiePieOscilloscope`(*com*, *dev_config*)

Bases: `SingleCommDevice`

TiePie oscilloscope.

A wrapper for TiePie oscilloscopes, based on the class `libtiepie.oscilloscope.Oscilloscope` with simplifications for starting of the device (using serial number) and managing mutable configuration of both the device and its channels, including extra validation and typing hints support for configurations.

Note that, in contrast to `libtiepie` library, since all physical TiePie devices include an oscilloscope, this is the base class for all physical TiePie devices. The additional TiePie sub-devices: “Generator” and “I2CHost”, are mixed-in to this base class in subclasses.

The channels use $1..N$ numbering (not $0..N-1$), as in, e.g., the Multi Channel software.

property `channels_enabled`: `Generator[int, None, None]`

Yield numbers of enabled channels.

Returns

Numbers of enabled channels

collect_measurement_data(*timeout*: `int` | `float` | `None` = `0`) → `ndarray[Any, dtype[_ScalarType_co]]` | `None`

Try to collect the data from TiePie; return `None` if data is not ready.

Parameters

timeout – The timeout to wait until data is available. This option makes this function blocking the code. `timeout = None` blocks the code infinitely till data will be available. Per default, the `timeout` is set to `0`: The function will not block.

Returns

Measurement data of only enabled channels and time vector in a `2D-numpy.ndarray` with float sample data; or `None` if there is no data available.

static `config_cls`() → `type[TiePieDeviceConfig]`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

config_osc: *TiePieOscilloscopeConfig* | *None*

Oscilloscope's dynamical configuration.

config_osc_channel_dict: `dict[int, TiePieOscilloscopeChannelConfig]`

Channel configuration. A *dict* mapping actual channel number, numbered $1..N$, to channel configuration. The channel info is dynamically read from the device only on the first *start()*; beforehand the *dict* is empty.

static default_com_cls() \rightarrow `type[NullCommunicationProtocol]`

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

force_trigger() \rightarrow *None*

Forces the TiePie to trigger with a software sided trigger event.

Return None

Raises

TiePieError – when device is not started or status of underlying device gives an error

is_measurement_data_ready() \rightarrow `bool`

Reports if TiePie has data which is ready to collect

Returns

if the data is ready to collect.

Raises

TiePieError – when device is not started or status of underlying device gives an error

is_measurement_running() \rightarrow `bool`

Reports if TiePie measurement is running (ready for trigger)

Returns

if a TiePie measurement is running (ready for trigger)

is_triggered() \rightarrow `bool`

Reports if TiePie has triggered. Maybe data is not yet available. One can check with the function *is_measurement_data_ready()*.

Returns

if a trigger event occurred

static list_devices() \rightarrow `DeviceList`

List available TiePie devices.

Returns

libtiepie up to date list of devices

property n_channels

Number of channels in the oscilloscope.

Returns

Number of channels.

start() \rightarrow *None*

Start the oscilloscope.

start_measurement() \rightarrow *None*

Start a measurement using set configuration.

Raises

TiePieError – when device is not started, when measurement is already

running, or when status of underlying device gives an error.

stop() → *None*

Stop the oscilloscope.

stop_measurement() → *None*

Stop a measurement that is already running.

Raises

TiePieError – when device is not started, when measurement is not

running, or when status of underlying device gives an error

class TiePieOscilloscopeAutoResolutionModes(*value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None*)

Bases: *NameEnum*

An enumeration.

ALL = 4

DISABLED = 1

NATIVEONLY = 2

UNKNOWN = 0

class TiePieOscilloscopeConfig(*dev_osc: Oscilloscope*)

Bases: *PublicPropertiesReprMixin*

Oscilloscope's configuration with cleaning of values in properties setters.

property auto_resolution_mode: *TiePieOscilloscopeAutoResolutionModes*

static clean_auto_resolution_mode(*auto_resolution_mode: int | TiePieOscilloscopeAutoResolutionModes*) → *TiePieOscilloscopeAutoResolutionModes*

clean_pre_sample_ratio(*pre_sample_ratio: float*) → float

clean_record_length(*record_length: int | float*) → int

static clean_resolution(*resolution: int | TiePieOscilloscopeResolution*) → *TiePieOscilloscopeResolution*

clean_sample_rate(*sample_rate: float*) → float

clean_trigger_timeout(*trigger_timeout: int | float | None*) → float

property pre_sample_ratio: float

property record_length: int

property resolution: *TiePieOscilloscopeResolution*

property sample_frequency

For backwards compatibility. Use *sample_rate* instead

```
property sample_rate: float
property trigger_timeout: float | None
```

```
class TiePieOscilloscopeConfigLimits(dev_osc: Oscilloscope)
```

Bases: object

Default limits for oscilloscope parameters.

```
class TiePieOscilloscopeResolution(value=<no_arg>, names=None, module=None, qualname=None,  
type=None, start=1, boundary=None)
```

Bases: IntEnum

An enumeration.

```
EIGHT_BIT = 8
```

```
FOURTEEN_BIT = 14
```

```
SIXTEEN_BIT = 16
```

```
TWELVE_BIT = 12
```

hvl_ccb.dev.tiepie.utils

PublicPropertiesReprMixin

```
class PublicPropertiesReprMixin
```

Bases: object

General purpose utility mixin that overwrites object representation to a one analogous to *dataclass* instances, but using public properties and their values instead of *fields*.

Module contents

This module is a wrapper around LibTiePie SDK devices; see <https://www.tiepie.com/en/libtiepie-sdk> .

The device classes adds simplifications for starting of the device (using serial number) and managing mutable configuration of both the device and oscilloscope's channels. This includes extra validation and typing hints support.

Extra installation

LibTiePie SDK library is available only on Windows and on Linux.

To use this LibTiePie SDK devices wrapper:

1. install the `hvl_ccb` package with a `tiepie` extra feature:

```
$ pip install "hvl_ccb[tiepie]"
```

this will install the Python bindings for the library.

2. install the library

- on Linux: the `hvl_ccb` package uses the forked version

`python-libtiepie-bi` in version 1.1.8 which has the binaries included. No additional installation is needed anymore. * on Windows: the additional DLL is included in Python bindings package.

Troubleshooting

On a Windows system, if you encounter an `OSError` like this:

```
...
self._handle = _dlopen(self._name, mode)
OSError: [WinError 126] The specified module could not be found
```

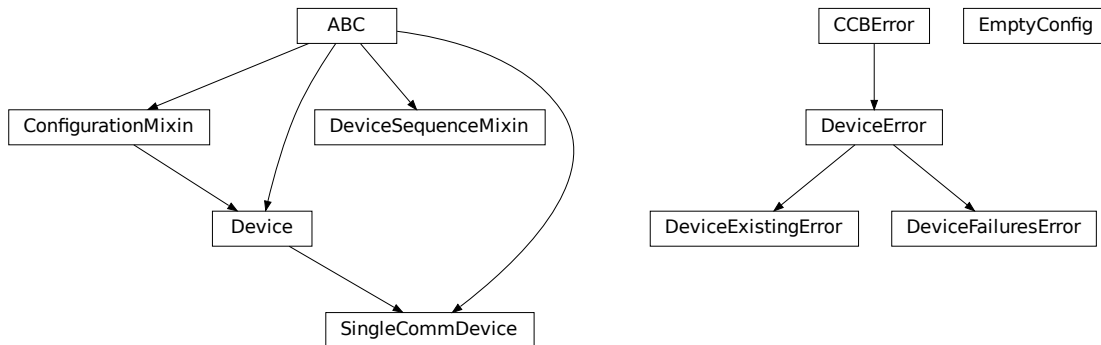
most likely the `python-libtiepie` package was installed in your `site-packages/` directory as a `python-libtiepie-*.egg` file via `python setup.py install` or `python setup.py develop` command. In such case uninstall the library and re-install it using `pip`:

```
$ pip uninstall python-libtiepie
$ pip install python-libtiepie
```

This should create `libtiepie/` folder. Alternatively, manually move the folder `libtiepie/` from inside of the `.egg` archive file to the containing it `site-packages/` directory (PyCharm's Project tool window supports reading and extracting from `.egg` archives).

Submodules

hvl_ccb.dev.base



Module with base classes for devices.

class Device(*dev_config=None*)

Bases: [ConfigurationMixin](#), [ABC](#)

Base class for devices. Implement this class for a concrete device, such as measurement equipment or voltage sources.

Specifies the methods to implement for a device.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

abstract start() → *None*

Start or restart this Device. To be implemented in the subclass.

abstract stop() → *None*

Stop this Device. To be implemented in the subclass.

exception DeviceError

Bases: [CCBError](#)

exception DeviceExistingError

Bases: [DeviceError](#)

Error to indicate that a device with that name already exists.

exception DeviceFailuresError(*failures: dict[str, Exception], *args*)

Bases: [DeviceError](#)

Error to indicate that one or several devices failed.

failures: **dict[str, Exception]**

A dictionary of named devices failures (exceptions).

class DeviceSequenceMixin(*devices: dict[str, Device]*)

Bases: ABC

Mixin that can be used on a device or other classes to provide facilities for handling multiple devices in a sequence.

add_device(*name: str, device: Device*) → *None*

Add a new device to the device sequence.

Parameters

- **name** – is the name of the device.
- **device** – is the instantiated Device object.

Raises

DeviceExistingError –

devices_failed_start: dict[str, Device]

Dictionary of named device instances from the sequence for which the most recent *start()* attempt failed.

Empty if *stop()* was called last; cf. *devices_failed_stop*.

devices_failed_stop: dict[str, Device]

Dictionary of named device instances from the sequence for which the most recent *stop()* attempt failed.

Empty if *start()* was called last; cf. *devices_failed_start*.

get_device(*name: str*) → *Device*

Get a device by name.

Parameters

name – is the name of the device.

Returns

the device object from this sequence.

get_devices() → list[tuple[str, Device]]

Get list of name, device pairs according to current sequence.

Returns

A list of tuples with name and device each.

remove_device(*name: str*) → *Device*

Remove a device from this sequence and return the device object.

Parameters

name – is the name of the device.

Returns

device object or *None* if such device was not in the sequence.

Raises

ValueError – when device with given name was not found

start() → *None*

Start all devices in this sequence in their added order.

Raises

DeviceFailuresError – if one or several devices failed to start

stop() → *None*

Stop all devices in this sequence in their reverse order.

Raises

DeviceFailuresError – if one or several devices failed to stop

class EmptyConfig

Bases: `object`

Empty configuration dataclass that is the default configuration for a Device.

clean_values()

Cleans and enforces configuration values. Does nothing by default, but may be overridden to add custom configuration value checks.

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True

classmethod keys() → `Sequence[str]`

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → `dict[str, object]`

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → `Sequence[str]`

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

class SingleCommDevice(*com*, *dev_config=None*)

Bases: *Device*, `ABC`

Base class for devices with a single communication protocol.

property com

Get the communication protocol of this device.

Returns

an instance of `CommunicationProtocol` subtype

abstract static default_com_cls() → type[*CommunicationProtocol*]

Get the class for the default communication protocol used with this device.

Returns

the type of the standard communication protocol for this device

start() → *None*

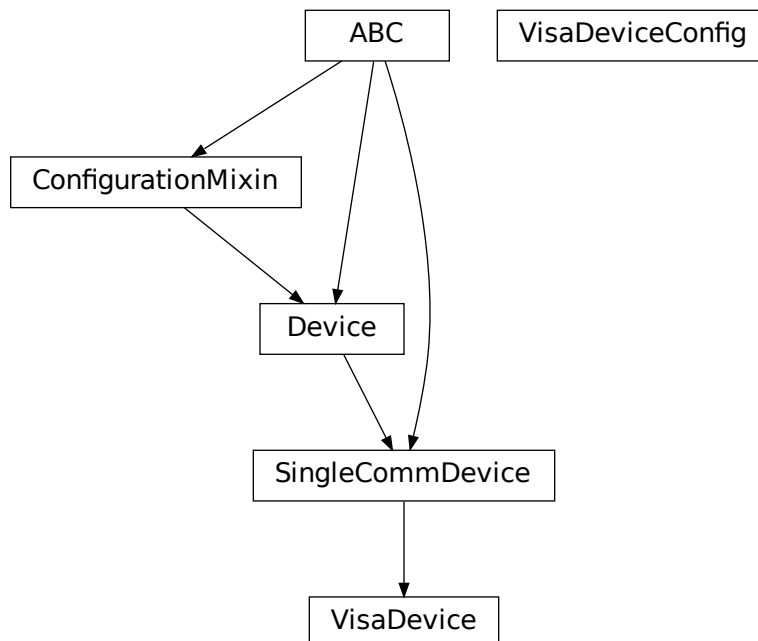
Open the associated communication protocol.

stop() → *None*

Close the associated communication protocol.

hvl_ccb.dev.utils

hvl_ccb.dev.visa



class VisaDevice(com: *VisaCommunication* | *VisaCommunicationConfig* | dict, dev_config: *VisaDeviceConfig* | dict | *None* = *None*)

Bases: *SingleCommDevice*

Device communicating over the VISA protocol using VisaCommunication.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls() → type[*VisaCommunication*]

Return the default communication protocol for this device type, which is VisaCommunication.

Returns

the VisaCommunication class

get_error_queue() → str

Read out error queue and logs the error.

Returns

Error string

get_identification() → str

Queries “*IDN?” and returns the identification string of the connected device.

Returns

the identification string of the connected device

reset() → *None*

Send “*RST” and “*CLS” to the device. Typically sets a defined state.

spoll_handler()

Reads the status byte and decodes it. The status byte STB is defined in IEEE 488.2. It provides a rough overview of the instrument status.

Returns

start() → *None*

Start the VisaDevice. Sets up the status poller and starts it.

Returns

stop() → *None*

Stop the VisaDevice. Stops the polling thread and closes the communication protocol.

Returns

wait_operation_complete(*timeout: float | None = None*) → bool

Waits for a operation complete event. Returns after timeout [s] has expired or the operation complete event has been caught.

Parameters

timeout – Time in seconds to wait for the event; *None* for no timeout.

Returns

True, if OPC event is caught, False if timeout expired

class VisaDeviceConfig(*spoll_interval: int | float = 0.5, spoll_start_delay: int | float = 2*)

Bases: *_VisaDeviceConfigDefaultsBase, _VisaDeviceConfigBase*

Configdataclass for a VISA device.

force_value(*fieldname, value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod **keys()** → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod **optional_defaults()** → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod **required_keys()** → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

Module contents

Devices subpackage.

hvl_ccb.utils

Subpackages

hvl_ccb.utils.conversion

Submodules

hvl_ccb.utils.conversion.map_range

MapBitAsymRange

MapBitSymRange

MapRanges

```
class MapBitAsymRange(value: int | float, bit: int, dtype_1: ~numpy.dtype[~typing.Any] | None |
    type[~typing.Any] |
    ~numpy._typing._dtype_like._SupportsDType[~numpy.dtype[~typing.Any]] | str |
    tuple[~typing.Any, int] | tuple[~typing.Any, ~typing.SupportsIndex |
    ~collections.abc.Sequence[~typing.SupportsIndex]] | list[~typing.Any] |
    ~numpy._typing._dtype_like._DTypeDict | tuple[~typing.Any, ~typing.Any] = <class
    'float'>, logger=None)
```

Bases: `_MapBitRange`

Class to convert an asymmetric arbitrary range (0 to value) to a bit-range (0 to 2**bit - 1).

```
class MapBitSymRange(value: int | float, bit: int, dtype_1: ~numpy.dtype[~typing.Any] | None |
    type[~typing.Any] |
    ~numpy._typing._dtype_like._SupportsDType[~numpy.dtype[~typing.Any]] | str |
    tuple[~typing.Any, int] | tuple[~typing.Any, ~typing.SupportsIndex] |
    ~collections.abc.Sequence[~typing.SupportsIndex]] | list[~typing.Any] |
    ~numpy._typing._dtype_like._DTypeDict | tuple[~typing.Any, ~typing.Any] = <class
    'float'>, logger=None)
```

Bases: `_MapBitRange`

Class to convert a symmetric arbitrary range (-value to value) to a bit-range (0 to $2^{bit} - 1$).

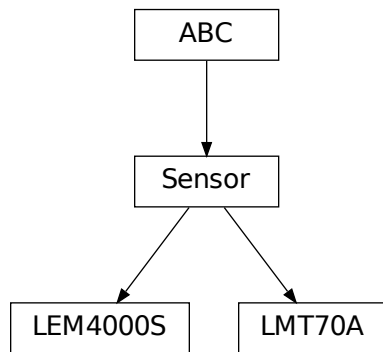
```
class MapRanges(range_1: tuple[int | float, int | float], range_2: tuple[int | float, int | float], dtype_1: dtype[Any] |
    None | type[Any] | _SupportsDType[dtype[Any]] | str | tuple[Any, int] | tuple[Any,
    SupportsIndex | Sequence[SupportsIndex]] | list[Any] | _DTypeDict | tuple[Any, Any], dtype_2:
    dtype[Any] | None | type[Any] | _SupportsDType[dtype[Any]] | str | tuple[Any, int] | tuple[Any,
    SupportsIndex | Sequence[SupportsIndex]] | list[Any] | _DTypeDict | tuple[Any, Any],
    logger=None)
```

Bases: `object`

convert_to_range1(value, **kwargs)

convert_to_range2(value, **kwargs)

hvl_ccb.utils.conversion.sensor



Sensors that are used by the devices implemented in the CCB

```
class LEM4000S
```

Bases: `Sensor`

CONVERSION

calibration_factor

convert(value, **kwargs)

shunt

class `LMT70A`

Bases: `Sensor`

Converts the output voltage (V) to the measured temperature (default °C) when using a TI Precision Analog Temperature Sensor LMT70(A)

LUT

convert(*value*, ***kwargs*)

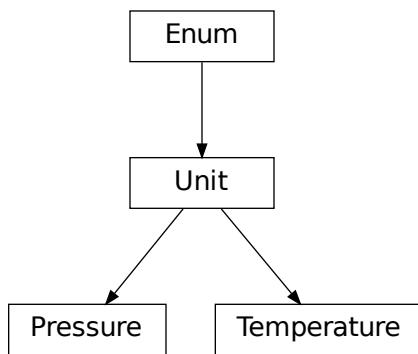
temperature_unit

class `Sensor`

Bases: `ABC`

abstract convert(*value*, ***kwargs*)

`hvl_ccb.utils.conversion.unit`



example Kelvin <-> Celsius

class `Pressure`(*value*)

Bases: `Unit`

An enumeration.

ATM = 'atm'

ATMOSPHERE = 'atm'

BAR = 'bar'

MILLIMETER_MERCURY = 'mmHg'

MMHG = 'mmHg'

PA = 'Pa'

PASCAL = 'Pa'

Unit conversion, within in the same group of units, for

```
POUNDS_PER_SQUARE_INCH = 'psi'
```

```
PSI = 'psi'
```

```
TORR = 'torr'
```

```
class Temperature(value)
```

```
Bases: Unit
```

```
An enumeration.
```

```
C = 'C'
```

```
CELSIUS = 'C'
```

```
F = 'F'
```

```
FAHRENHEIT = 'F'
```

```
K = 'K'
```

```
KELVIN = 'K'
```

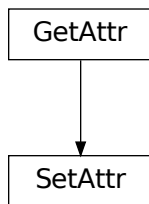
```
class Unit(value)
```

```
Bases: Enum
```

```
An enumeration.
```

```
abstract classmethod convert(value, **kwargs)
```

hvl_ccb.utils.conversion.utils



```
class GetAttr(default, name)
```

```
Bases: object
```

```
class SetAttr(default, name, limits, absolut=False, dtype=(<class 'int'>, <class 'float'>), validator=None)
```

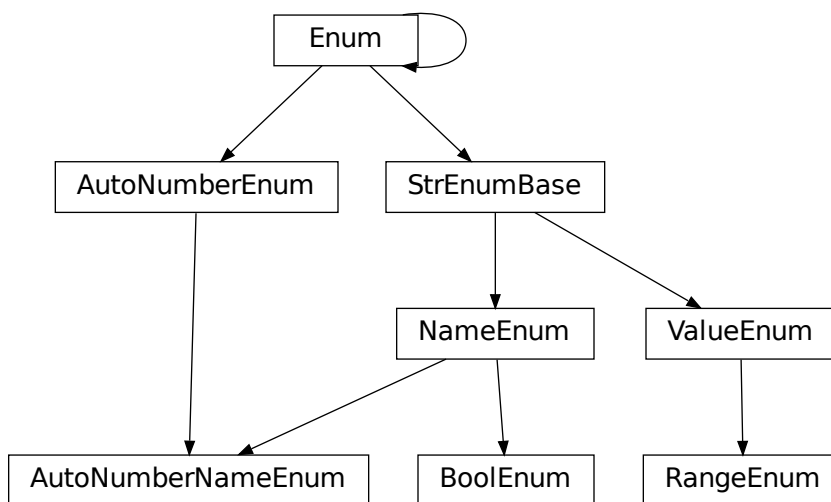
```
Bases: GetAttr
```

```
convert_value_to_str(*value: ndarray[Any, dtype[_ScalarType_co]]) → list[str | list[str]]
```

Converts two sets of values to strings. This is necessary because a 0-dim array needs different treatment than a 1-dim array :param value: array of values either 0-dim or 1-dim :return:converted se

preserve_type(*func*)

This wrapper preserves the first order type of the input. Upto now the type of the data stored in a list, tuple, array or dict is not preserved. Integer will be converted to float!

Module contents**Submodules****hvl_ccb.utils.enum**

```
class AutoNumberNameEnum(value=<no_arg>, names=None, module=None, qualname=None, type=None,  
                        start=1, boundary=None)
```

Bases: [NameEnum](#), AutoNumberEnum

Auto-numbered enum with names used as string representation, and with lookup and equality based on this representation.

```
class BoolEnum(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,  
              boundary=None)
```

Bases: [NameEnum](#)

BoolEnum inherits from NameEnum and the type of the first value is
enforced to be 'boolean'. For bool()-operation the `__bool__` is redefined here.

```
class NameEnum(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,  
              boundary=None)
```

Bases: [StrEnumBase](#)

Enum with names used as string representation, and with lookup and equality based on this representation. The lookup is implemented in StrEnumBase with the `_missing_value_` method. The equality is also defined at this place (`__eq__`).

Use-case:

```
class E(NameEnum):
    a = 2
    b = 4

E.a == "a"
E.a != 2
E.a != "2"
```

The access would be normally with E["a"], but E("a") works also. Therefore, E["a"] == E("a")

Attention: to avoid errors, best use together with *unique* enum decorator.

```
class RangeEnum(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                boundary=None)
```

Bases: float, [ValueEnum](#)

Range enumeration inherit from ValueEnum, find suitable voltage/current/resistance input range for devices such as multimeter and oscilloscope

abstract classmethod **unit()** → str

Returns the Unit of the values in the enumeration. :return: the unit of the values in the enumeration in string format

```
class StrEnumBase(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                  boundary=None)
```

Bases: Enum

String representation-based equality and lookup.

```
class ValueEnum(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                boundary=None)
```

Bases: [StrEnumBase](#)

Enum with string representation of values used as string representation, and with lookup and equality based on this representation. Values do not need to be of type 'str', but they need to have a str-representation to enable this feature. The lookup is implemented in StrEnumBase with the `_missing_value_` method. The equality is also defined at this place (`__eq__`).

Use-case:

```
class E(ValueEnum):
    ONE = 1

E.ONE == "1"
E.ONE != 1
E.ONE != "ONE"
```

The access would be normally with E(1), but E("1") works also. Therefore, E(1) == E("1")

Attention: to avoid errors, best use together with *unique* enum decorator.

hvl_ccb.utils.poller

Poller

```
class Poller(poll_handler: Callable, polling_delay_sec: int | float = 0, polling_interval_sec: int | float = 1,  
            polling_timeout_sec: int | float | None = None)
```

Bases: object

Poller class wrapping *concurrent.futures.ThreadPoolExecutor* which enables passing of results and errors out of the polling thread.

is_polling() → bool

Check if device status is being polled.

Returns

True when polling thread is set and alive

start_polling() → bool

Start polling.

Returns

True if was not polling before, *False* otherwise

stop_polling() → bool

Stop polling.

Wait for until polling function returns a result as well as any exception / error that might have been raised within a thread.

Returns

True if was polling before, *False* otherwise, and last result of the polling function call.

Raises

polling function exceptions

wait_for_polling_result()

Wait for until polling function returns a result as well as any exception / error that might have been raised within a thread.

Returns

polling function result

Raises

polling function errors

hvl_ccb.utils.typing

Additional Python typing module utilities

ConvertibleTypes

Typing hint for data type that can be used in conversion

alias of Union[int, float, list[Union[int, float]], tuple[Union[int, float], ...], dict[str, Union[int, float]], ndarray[Any, dtype[_ScalarType_co]]]

Number

Typing hint auxiliary for a Python base number types: *int* or *float*.

alias of Union[int, float]

hvl_ccb.utils.validation

validate_and_resolve_host(*host*: str | IPv4Address | IPv6Address, *logger*: Logger | None = None) → str

validate_bool(*x_name*: str, *x*: object, *logger*: Logger | None = None) → None

Validate if given input *x* is a *bool*.

Parameters

- **x_name** – string name of the validate input, use for the error message
- **x** – an input object to validate as boolean
- **logger** – logger of the calling submodule

Raises

TypeError – when the validated input does not have boolean type

validate_number(*x_name*: str, *x*: object, *limits*: tuple | None = (None, None), *number_type*: type[int | float] | tuple[type[int | float], ...] = (<class 'int'>, <class 'float'>), *logger*: ~logging.Logger | None = None) → None

Validate if given input *x* is a number of given *number_type* type, with value between given *limits*[0] and *limits*[1] (inclusive), if not *None*. For array-like objects (npt.NDArray, list, tuple, dict) it is checked if all elements are within the limits and have the correct type.

Parameters

- **x_name** – string name of the validate input, use for the error message
- **x** – an input object to validate as number of given type within given range
- **logger** – logger of the calling submodule
- **limits** – [lower, upper] limit, with *None* denoting no limit: [-inf, +inf]
- **number_type** – expected type or tuple of types of a number, by default (*int*, *float*)

Raises

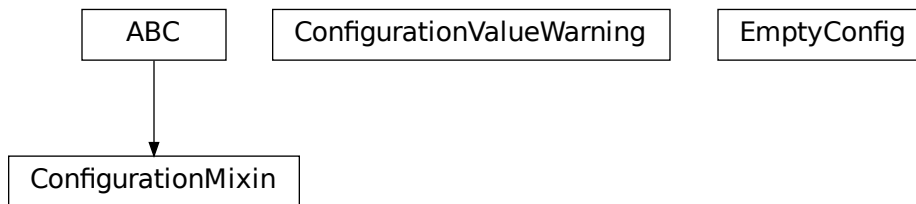
- **TypeError** – when the validated input does not have expected type
- **ValueError** – when the validated input has correct number type but is not within given range or has wrong input limits

validate_tcp_port(*port*: int, *logger*: Logger | None = None)

Module contents

4.1.2 Submodules

`hvl_ccb.configuration`



Facilities

providing classes for handling configuration for communication protocols and devices.

class `ConfigurationMixin(configuration)`

Bases: `ABC`

Mixin providing configuration to a class.

property `config`

`ConfigDataclass` property.

Returns

the configuration

abstract static `config_cls()`

Return the default `configdataclass` class.

Returns

a reference to the default `configdataclass` class

configuration_save_json(path: str) → None

Save current configuration as JSON file.

Parameters

path – path to the JSON file.

classmethod `from_json(filename: str)`

Instantiate communication protocol using configuration from a JSON file.

Parameters

filename – Path and filename to the JSON configuration

exception `ConfigurationValueWarning`

Bases: `UserWarning`

User warnings category for values of `@configdataclass` fields.

class `EmptyConfig`

Bases: `object`

Empty configuration dataclass.

clean_values()

Cleans and enforces configuration values. Does nothing by default, but may be overridden to add custom configuration value checks.

force_value(*fieldname*, *value*)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define *post_force_value* method with same signature as this method to do extra processing after *value* has been forced on *fieldname*.

Parameters

- **fieldname** – name of the field
- **value** – value to assign

is_configdataclass = True**classmethod keys()** → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

configdataclass(*direct_decoration=None*, *frozen=True*)

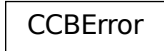
Decorator to make a class a configdataclass. Types in these dataclasses are enforced. Implement a function `clean_values(self)` to do additional checking on value ranges etc.

It is possible to inherit from a configdataclass and re-decorate it with `@configdataclass`. In a subclass, default values can be added to existing fields. Note: adding additional non-default fields is prone to errors, since the order has to be respected through the whole chain (first non-default fields, only then default-fields).

Parameters

frozen – defaults to True. False allows to later change configuration values. Attention: if configdataclass is not frozen and a value is changed, typing is not enforced anymore!

hvl_ccb.error

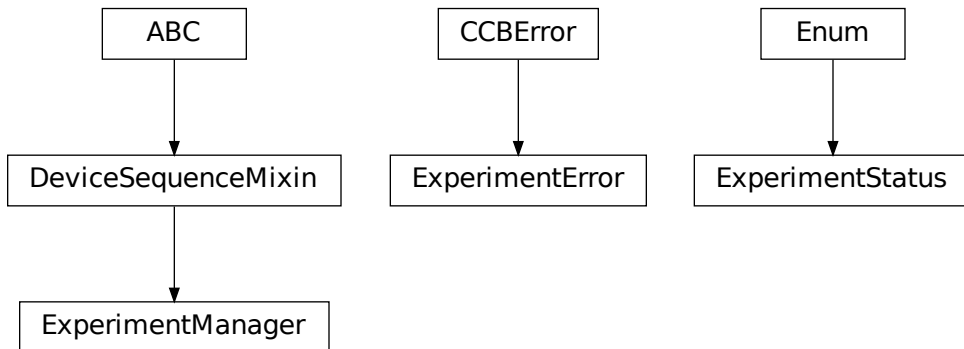


Introduce a common code base error for the CCB

exception CCBError

Bases: Exception

hvl_ccb.experiment_manager



Main module containing the top level ExperimentManager class. Inherit from this class to implement your own experiment functionality in another project and it will help you start, stop and manage your devices.

exception ExperimentError

Bases: *CCBError*

Error to indicate that the current status of the experiment manager is on ERROR and thus no operations can be made until reset.

class ExperimentManager(*args, **kwargs)

Bases: *DeviceSequenceMixin*

Experiment Manager can start and stop communication protocols and devices. It provides methods to queue commands to devices and collect results.

add_device(name: str, device: *Device*) → *None*

Add a new device to the manager. If the experiment is running, automatically start the device. If a device with this name already exists, raise an error.

Parameters

- **name** – is the name of the device.

- **device** – is the instantiated Device object.

Raises*ExperimentError* –**devices_failed_start:** dict[str, *Device*]Dictionary of named device instances from the sequence for which the most recent *start()* attempt failed.Empty if *stop()* was called last; cf. *devices_failed_stop*.**devices_failed_stop:** dict[str, *Device*]Dictionary of named device instances from the sequence for which the most recent *stop()* attempt failed.Empty if *start()* was called last; cf. *devices_failed_start*.**finish()** → *None*

Stop experimental setup, stop all devices.

is_error() → boolReturns true, if the status of the experiment manager is *error*.**Returns**

True if on error, false otherwise

is_finished() → boolReturns true, if the status of the experiment manager is *finished*.**Returns**

True if finished, false otherwise

is_running() → boolReturns true, if the status of the experiment manager is *running*.**Returns**

True if running, false otherwise

run() → *None*

Start experimental setup, start all devices.

start() → *None*

Alias for ExperimentManager.run()

property status: *ExperimentStatus*

Get experiment status.

Returns

experiment status enum code.

stop() → *None*

Alias for ExperimentManager.finish()

class ExperimentStatus(*value*)

Bases: Enum

Enumeration for the experiment status

ERROR = 5**FINISHED** = 4**FINISHING** = 3

INITIALIZED = 0

INITIALIZING = -1

RUNNING = 2

STARTING = 1

4.1.3 Module contents

Top-level package for HVL Common Code Base.

CONTRIBUTING

Contributions are welcome, and they are greatly appreciated! Every little bit helps, and credit will always be given. You can contribute in many ways:

5.1 Types of Contributions

5.1.1 Report Bugs

Report bugs at https://gitlab.com/ethz_hvl/hvl_ccb/issues.

If you are reporting a bug, please include:

- Your operating system name and version.
- Any details about your local setup that might be helpful in troubleshooting.
- Detailed steps to reproduce the bug.

5.1.2 Fix Bugs

Look through the GitLab issues for bugs. Anything tagged with “bug” and “help wanted” is open to whoever wants to implement it.

5.1.3 Implement Features

Look through the GitLab issues for features. Anything tagged with “enhancement” and “help wanted” is open to whoever wants to implement it.

5.1.4 Write Documentation

HVL Common Code Base could always use more documentation, whether as part of the official HVL Common Code Base docs, in docstrings, or even on the web in blog posts, articles, and such.

5.1.5 Submit Feedback

The best way to send feedback is to file an issue at https://gitlab.com/ethz_hvl/hvl_ccb/issues.

If you are proposing a feature:

- Explain in detail how it would work.
- Keep the scope as narrow as possible, to make it easier to implement.
- Remember that this is a volunteer-driven project, and that contributions are welcome :)

5.2 Get Started!

Ready to contribute? Here's how to set up *hvl_ccb* for local development.

1. Clone *hvl_ccb* repo from GitLab:

```
$ git clone git@gitlab.com:ethz_hvl/hvl_ccb.git
```

2. Go into the cloned folder. Then install your virtual environment and activate it:

```
$ cd hvl_ccb
$ python -m venv .venv
$ . .venv/Scripts/activate # <-- for Windows
$ . .venv22/bin/activate   # <-- for Linux
```

3. Install the HVL-CommonCodeBase with its dependencies as well as the dependencies for development:

```
$ pip install -e .[all]
$ pip install -r requirements_dev.txt
```

4. Furthermore, it is recommended to install the git hook script shipped within the repository:

```
$ pre-commit install
```

5. After creating an Issue and Merge Request on GitLab, you can switch to you created development branch:

```
$ git switch name-of-your-bugfix-or-feature
```

Now you can make your changes locally.

6. When you're done making changes, check that your changes pass flake8, mypy, black, isort and the tests, including testing other Python versions with tox:

```
$ isort .
$ black --preview hvl_ccb/ tests/ examples/
$ flake8 hvl_ccb tests
$ mypy --show-error-codes hvl_ccb
$ python setup.py test or py.test
$ tox
```

You can also use the provided make-like shell script to run flake8 and tests:

```
$ ./make.sh black
$ ./make.sh isort
$ ./make.sh style
$ ./make.sh type
$ ./make.sh test
```

7. As we want to maintain a high quality of coding style we use *black* and *isort*. This style is checked with the pipelines on gitlab.com. Ensure that your commits include only properly formatted code. One way to comply is to install and use *pre-commit*. This package includes the necessary configuration.
8. Commit your changes and push your branch to GitLab:

```
$ git add .
$ git commit -m "Your detailed description of your changes."
$ git push
```

9. Request a review of your merge request through the GitLab website.

5.3 Merge Request Guidelines

Before you submit a merge request, check that it meets these guidelines:

1. The merge request should include tests.
2. If the merge request adds functionality, the docs should be updated. Put your new functionality into a function with a docstring, and add the feature to the list in README.rst.
3. The merge request should work for Python 3.9 to 3.10. Check https://gitlab.com/ethz_hvl/hvl_ccb/merge_requests and make sure that the tests pass for all supported Python versions.

5.4 Tips

- To run tests from a single file:

```
$ py.test tests/test_hvl_ccb.py
```

or a single test function:

```
$ py.test tests/test_hvl_ccb.py::test_command_line_interface
```

- If your tests are slow, profile them using the pytest-profiling plugin:

```
$ py.test tests/test_hvl_ccb.py --profile
```

or for a graphical overview (you need a SVG image viewer):

```
$ py.test tests/test_hvl_ccb.py --profile-svg
$ open prof/combined.svg
```

- To add dependency, edit appropriate **requirements* variable in the *setup.py* file and re-run:

```
$ python setup.py develop
```

- To generate a PDF version of the Sphinx documentation instead of HTML use:

```
$ rm -rf docs/hvl_ccb.rst docs/modules.rst docs/_build && sphinx-apidoc -o docs/hvl_
→ccb && python -msphinx -M latexpdf docs/ docs/_build
```

This command can also be run through the make-like shell script:

```
$ ./make.sh docs-pdf
```

This requires a local installation of a LaTeX distribution, e.g. MikTeX.

5.5 Deploying

A reminder for the maintainers on how to deploy.

Make sure all your changes are committed and that all relevant MR are merged. Then switch to `devel`, update it and create `release-N.M.K` branch:

```
$ git switch devel
$ git pull
$ git checkout -b release-N.M.K
```

- Update copyright information (if necessary) in `docs/conf.py` and `README.rst`
- Update or create entry in `HISTORY.rst` (commit message: Update HISTORY.rst: release N.M.K).
- Update, if applicable, `AUTHORS.rst` (commit message: Update AUTHORS.rst: release N.M.K)
- Update features tables in `README.rst` file (commit message: Update README.rst: release N.M.K)
- Update API docs (commit message: Update API-docs: release N.M.K)

```
$ ./make.sh docs # windows
$ make docs # unix-based-os
```

Commit all of the above, except for

- `docs/hvl_ccb.dev.picotech_pt104.rst`
- `docs/hvl_ccb.dev.tiepie.base.rst`
- `docs/hvl_ccb.dev.tiepie.channel.rst`
- `docs/hvl_ccb.dev.tiepie.device.rst`
- `docs/hvl_ccb.dev.tiepie.generator.rst`
- `docs/hvl_ccb.dev.tiepie.i2c.rst`
- `docs/hvl_ccb.dev.tiepie.oscilloscope.rst`
- `docs/hvl_ccb.dev.tiepie.utils.rst`.

Before you continue revert the changes in this file.

Then run:

```
$ bumpver update --patch # possible: major / minor / patch
$ git push --set-upstream origin release-N.M.K
$ git push --tags
```

Go to <https://readthedocs.org/projects/hvl-ccb/builds/> and check if RTD docs build for the pushed tag passed.

Wait for the CI pipeline to finish successfully.

The two following commands are best executed in a WSL or Unix based OS. Run a release check:

```
$ make release-check
```

Finally, prepare and push a release:

```
$ make release
```

Merge the release branch into master and devel branches with `--no-ff` flag and delete the release branch:

```
$ git switch master
$ git pull
$ git merge --no-ff release-N.M.K
$ git push
$ git switch devel
$ git merge --no-ff release-N.M.K
$ git push
$ git push --delete origin release-N.M.K
$ git branch --delete release-N.M.K
```

After this you can/should clean your folder (with WSL/Unix command):

```
$ make clean
```

Finally, prepare GitLab release and cleanup the corresponding milestone:

1. go to https://gitlab.com/ethz_hvl/hvl_ccb/-/tags/, select the latest release tag, press “Edit release notes” and add the release notes (copy a corresponding entry from `HISTORY.rst` file with formatting adjusted from ReStructuredText to Markdown); press “Save changes”;
2. go to https://gitlab.com/ethz_hvl/hvl_ccb/-/releases, select the latest release, press “Edit this release” and under “Milestones” select the corresponding milestone; press “Save changes”;
3. go to https://gitlab.com/ethz_hvl/hvl_ccb/-/milestones, make sure that it is 100% complete (otherwise, create a next patch-level milestone and assign it to the ongoing Issues and Merge Requests therein); press “Close Milestone”.

6.1 Active Maintainers

- Chi-Ching Hsu <hsu@eeh.ee.ethz.ch>
- Henning Janssen <janssen@eeh.ee.ethz.ch>

6.2 Authors and Contributors

- Alise Chachereau (Author)
- Maria Del (Contributor, Maintainer)
- Joseph Engelbrecht (Author)
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- Ruben Stadler (Contributor)
- David Taylor (Author)
- Hanut Vemulapalli (Contributor)

HISTORY

7.1 0.14.3 (2023-11-17)

- Fix Heinzinger conversion from mA to A and fix wrong docstrings
- Hot-fix to be compatible with the newly released version 23.11.0 of black
- Fix bumpver tag messages
- Implementation of Technix to fulfil protocols.Source

7.2 0.14.2 (2023-09-07)

- Change dependency to libtiepie with linux binaries using forked version python-libtiepie-bi
- Adapt makefile after removing setup.py
- Fix commit messages and tag with bumpver
- Hot-fix to be compatible with the newly released version 3.5.0 of pymodbus

7.3 0.14.1 (2023-08-21)

- Remove setup.cfg, setup.py, mypy.ini, pytest.ini, requirements_dev.txt and change to pyproject.toml
- Replace bump2version with bumpver
- Change dependency to libtiepie with linux binaries
- Hot-fix to be compatible with the newly released version 6.1.0 of flake8

7.4 0.14.0 (2023-07-28)

- **Rework of Heinzinger high voltage source control**
 - validation of input values (e.g. voltage-property)
 - merge HeinzingerPNC and HeinzingerDI to Heinzinger
 - always return values as V for voltage and A for current
 - RangeEnum for number_of_recordings
 - fulfil protocols.Source
 - raise Error for getter and setter (e.g. set_current, get_current ...), use property instead
- Hot-fix to be compatible with the newly released version 23.7.0 of black
- Hot-fix to be compatible with the newly released version 3.4.0 of pymodbus
- **Hot-fix to be compatible with the newly released version 1.1.6 of libtiepie**
 - drop support for I2C
- Remove default import from hv1_ccb.comm and hv1_ccb.dev for specific communication protocols and devices

7.5 0.13.3 (2023-03-31)

- Introduce common protocol for voltage and current sources hv1_ccb.dev.protocols.sources
- Update code style to black 23.3.0 and isort 5.12.0
- An _EarthingStick of BaseCube is implemented as a _Switch
- **Code improvements for device Heinzinger**
 - use property-based instead of getter and setter
 - DeprecationWarning for getter and setter (e.g. set_current, get_current ...)

7.6 0.13.2 (2023-03-17)

- Hot-fix to be compatible with the newly released version 3.0.0 of typeguard

7.7 0.13.1 (2023-03-03)

- **Repository maintenance**
 - add the option to manually set n_attempts_max and attempt_interval_sec in query of the SyncCommunicationProtocol
 - fix links in description for Heinzinger digital interface and universal high voltage power supplies
 - keep copyright year information only in docs/conf.py and README.rst
 - remove copyright year information from the files

- fix readthedocs build failed issue
- update code style to black 23.1.0

7.8 0.13.0 (2023-01-27)

- **Drop support for Python 3.7 and 3.8:**
 - remove version dependent implementations
 - changed typing acc. to PEP 585
- Un-freeze version number of dependencies and upgrade to most recent versions

7.9 0.12.3 (2022-12-27)

- **Code improvements for device cube:**
 - split alarms from constants
 - split errors from constants
 - split earthing_stick from constants
 - split support from constants
- Update code style to black 22.12.0
- **Smaller change of device tiepie:**
 - change hard coded trigger time out value for no time out/infinite (-1) to `ltp.const.TO_INFINITY`

7.10 0.12.2 (2022-11-29)

- Move the device modules into packages
- Bugfix in `validate_number` to check the order of the limits
- **Repository maintenance:**
 - imports are sorted with `isort`
 - some mypy fixing and additional typing

7.11 0.12.1 (2022-10-31)

- **Fix numpy version requirement problem**
 - for Python 3.7: 1.21.6
 - for Python 3.8 and onwards: 1.23.4

7.12 0.12.0 (2022-10-17)

- Last release for Python 3.7 and 3.8
- **Repository maintenance**
 - update Labjack LJM software installer link in the pipeline
 - fix dependencies to the fixed version
 - fix asynqua to 0.9.95 and pymodbus to 2.5.3 (newer versions break the code)
 - fix PICube checker for slope as it is always positive

7.13 0.11.1 (2022-09-15)

- **Repository maintenance**
 - fix issue with mypy and Python 3.10.7
 - update code style to black 22.8.0
 - project configurations merged into `setup.cfg`
 - fix coverage indicator

7.14 0.11.0 (2022-06-22)

- New device: Fluke 884X Bench 6.5 Digit Precision Multimeter
- `RangeEnum` is a new enum for e.g. measurement ranges which also finds a suitable range object
- **smaller changes of device tiepie:**
 - introduce status method `is_measurement_running()` to check if the device is armed
 - introduce `stop_measurement()` to disarm the trigger of the device
 - fix bug with docs due to change of `libtiepie`
- `NameEnum` and inherited enums can only have unique entries

7.15 0.10.3 (2022-03-21)

- fix bug in the Labjack pulse feature that occurred when the start time was set to 0s
- new conversion utility to map two ranges on each other
- update CONTRIBUTING.RST
- update makefile and make.sh
- improve the mockup telnet test server

7.16 0.10.2 (2022-02-28)

- introduction of `black` as code formatter
- increase the required version of the package `aenum`
- remove device `supercube2015` - as it is no longer used
- remove unused package `openpyxl` requirement
- fix bug in highland logging
- improve handling for communication error with `picotech`

7.17 0.10.1 (2022-01-24)

- **several improvements and fixes for device cube:**
 - privatize `Alarms` and `AlarmsOverview`
 - fix list of cube alarms
 - improve docs
 - fix bugs with earthing sticks
 - fix bug in config dataclass of cube
- introduction of `BoolEnum`
- introduction of `RangeEnum`
- `bumpversion` -> `bump2version`

7.18 0.10.0 (2022-01-17)

- Reimplementation of the Cube (before known as Supercube)
- **new names:**
 - Supercube Typ B -> `BaseCube`
 - Supercube Typ A -> `PICube` (power inverter Cube)
- **new import:**
 - `from hvl_ccb.dev.supercube import SupercubeB` -> `from hvl_ccb.dev.cube import BaseCube`
- **new programming style:**
 - getter / setter methods -> properties
 - e.g. get: `cube.get_support_output(port=1, contact=1)` -> `cube.support_1.output_1`
 - e.g. set: `cube.get_support_output(port=1, contact=1, state=True)` -> `cube.support_1.output_1 = True`
- unify Exceptions of Cube
- implement Fast Switch-Off of Cube

- remove method `support_output_impulse`
- all active alarms can now be queried `cube.active_alarms()`
- alarms will now result in different logging levels depending on the seriousness of the alarm.
- introduction of limits for slope and safety limit for RedReady
- during the startup the CCB will update the time of the cube.
- verification of inputs
- polarity of DC voltage
- Switch from `python-opcua` to `opcua-asyncio` (former package is no longer maintained)

7.19 0.9.0 (2022-01-07)

- New device: Highland T560 digital delay and pulse generator over Telnet.
- **Rework of the Technix Capacitor Charger.**
 - Moved into a separate sub-package
 - NEW import over `import hvl_ccb.dev.technix as XXX`
 - Slightly adapted behaviour
- Add `validate_tcp_port` to validate port number.
- **Add `validate_and_resolve_host` to validate and resolve host names and IPs.**
 - Remove requirement IPy
- Add a unified CCB Exception schema for all devices and communication protocols.
- Add data conversion functions to README.
- Update CI and devel images from Debian 10 buster to Debian 11 bullseye.
- Fix typing due to numpy update.
- Fix incorrect overloading of `clean_values()` in classes of type `XCommunicationConfig`.

7.20 0.8.5 (2021-11-05)

- Added arbitrary waveform for TiePie signal generation, configurable via `dev.tiepie.generator.TiePieGeneratorConfig.waveform` property.
- In `utils.conversion_sensor`: improvements for class constants; removed SciPy dependency.
- Added Python 3.10 support.

7.21 0.8.4 (2021-10-22)

- `utils.validation.validate_number` extension to handle NumPy arrays and array-like objects.
- `utils.conversion_unit` utility classes handle correctly `NamedTuple` instances.
- `utils.conversion_sensor` and `utils.conversion_unit` code simplification (no `transfer_function_order` attribute) and cleanups.
- Fixed incorrect error logging in `configuration.configdataclass`.
- `comm.telnet.TelnetCommunication` tests fixes for local run errors.

7.22 0.8.3 (2021-09-27)

- New data conversion functions in `utils.conversion_sensor` and `utils.conversion_unit` modules. Note: to use these functions you must install `hvl_ccb` with extra requirement, either `hvl_ccb[conversion]` or `hvl_ccb[all]`.
- Improved documentation with respect to installation of external libraries.

7.23 0.8.2 (2021-08-27)

- **New functionality in `dev.labjack.LabJack`:**
 - configure clock and send timed pulse sequences
 - set DAC/analog output voltage
- Bugfix: ignore random bits sent by to `dev.newport.NewportSMC100PP` controller during start-up/powering-up.

7.24 0.8.1 (2021-08-13)

- Add Python version check (min version error; max version warning).
- Daily checks for upstream dependencies compatibility and devel environment improvements.

7.25 0.8.0 (2021-07-02)

- TCP communication protocol.
- Lauda PRO RP 245 E circulation thermostat device over TCP.
- Pico Technology PT-104 Platinum Resistance Data Logger device as a wrapper of the Python bindings for the PicoSDK.
- In `com.visa.VisaCommunication`: periodic status polling when VISA/TCP keep alive connection is not supported by a host.

7.26 0.7.1 (2021-06-04)

- New `utils.validation` submodule with `validate_bool` and `validate_number` utilities extracted from internal use within a `dev.tiepie` subpackage.
- In `comm.serial.SerialCommunication`:
 - strict encoding errors handling strategy for subclasses,
 - user warning for a low communication timeout value.

7.27 0.7.0 (2021-05-25)

- The `dev.tiepie` module was splitted into a subpackage with, in particular, submodules for each of the device types – `oscilloscope`, `generator`, and `i2c` – and with backward-incompatible direct imports from the submodules.
- In `dev.technix`:
 - fixed communication crash on nested status byte query;
 - added enums for GET and SET register commands.
- Further minor logging improvements: added missing module level logger and removed some error logs in `except` blocks used for a flow control.
- In `examples/` folder renamed consistently all the examples.
- In API documentation: fix incorrect links mapping on inheritance diagrams.

7.28 0.6.1 (2021-05-08)

- In `dev.tiepie`:
 - dynamically set `oscilloscope`'s channel limits in `OscilloscopeChannelParameterLimits`: `input_range` and `trigger_level_abs`, incl. update of latter on each change of `input_range` value of a `TiePieOscilloscopeChannelConfig` instances;
 - quick fix for opening of combined instruments by disabling `OscilloscopeParameterLimits.trigger_delay` (an advanced feature);
 - enable automatic devices detection to be able to find network devices with `TiePieOscilloscope.list_devices()`.
- Fix `examples/example_labjack.py`.
- Improved logging: consistently use module level loggers, and always log exception tracebacks.
- Improve API documentation: separate pages per modules, each with an inheritance diagram as an overview.

7.29 0.6.0 (2021-04-23)

- Technix capacitor charger using either serial connection or Telnet protocol.
- **Extensions, improvements and fixes in existing devices:**
 - In `dev.tiepie.TiePieOscilloscope`:
 - * redesigned measurement start and data collection API, incl. time out argument, with no/infinite time out option;
 - * trigger allows now a no/infinite time out;
 - * record length and trigger level were fixed to accept, respectively, floating point and integer numbers;
 - * fixed resolution validation bug;
 - `dev.heinzinger.HeinzingerDI` and `dev.rs_rto1024.RTO1024` instances are now resilient to multiple `stop()` calls.
 - In `dev.crylas.CryLasLaser`: default configuration timeout and polling period were adjusted;
 - Fixed PSI9080 example script.
- **Package and source code improvements:**
 - Update to backward-incompatible `pyvisa-py` $\geq 0.5.2$. Developers, do update your local development environments!
 - External libraries, like LibTiePie SDK or LJM Library, are now not installed by default; they are now extra installation options.
 - Added Python 3.9 support.
 - Improved number formatting in logs.
 - Typing improvements and fixes for `mypy` ≥ 0.800 .

7.30 0.5.0 (2020-11-11)

- TiePie USB oscilloscope, generator and I2C host devices, as a wrapper of the Python bindings for the LibTiePie SDK.
- a FuG Elektronik Power Supply (e.g. Capacitor Charger HCK) using the built-in ADDAT controller with the Probus V protocol over a serial connection
- All devices polling status or measurements use now a `dev.utils.Poller` utility class.
- **Extensions and improvements in existing devices:**
 - In `dev.rs_rto1024.RTO1024`: added Channel state, scale, range, position and offset accessors, and measurements activation and read methods.
 - In `dev.sst_luminox.Luminox`: added querying for all measurements in polling mode, and made output mode activation more robust.
 - In `dev.newport.NewportSMC100PP`: an error-prone `wait_until_move_finished` method of replaced by a fixed waiting time, device operations are now robust to a power supply cut, and device restart is not required to apply a start configuration.
- **Other minor improvements:**

- Single failure-safe starting and stopping of devices sequenced via `dev.base.DeviceSequenceMixin`.
- Moved `read_text_nonempty` up to `comm.serial.SerialCommunication`.
- Added development Dockerfile.
- Updated package and development dependencies: `pymodbus`, `pytest-mock`.

7.31 0.4.0 (2020-07-16)

- **Significantly improved new Supercube device controller:**
 - more robust error-handling,
 - status polling with generic `Poller` helper,
 - messages and status boards.
 - tested with a physical device,
- Improved OPC UA client wrapper, with better error handling, incl. re-tries on `concurrent.futures.TimeoutError`.
- SST Luminex Oxygen sensor device controller.
- **Backward-incompatible changes:**
 - `CommunicationProtocol.access_lock` has changed type from `threading.Lock` to `threading.RLock`.
 - `ILS2T.relative_step` and `ILS2T.absolute_position` are now called, respectively, `ILS2T.write_relative_step` and `ILS2T.write_absolute_position`.
- **Minor bugfixes and improvements:**
 - fix use of max resolution in `Labjack.set_ain_resolution()`,
 - resolve ILS2T devices relative and absolute position setters race condition,
 - added acoustic horn function in the 2015 Supercube.
- **Toolchain changes:**
 - add Python 3.8 support,
 - drop `pytest-runner` support,
 - ensure compatibility with `labjack_ljm` 2019 version library.

7.32 0.3.5 (2020-02-18)

- Fix issue with reading integers from LabJack LJM Library (device's product ID, serial number etc.)
- Fix development requirements specification (tox version).

7.33 0.3.4 (2019-12-20)

- **New devices using serial connection:**
 - Heinzinger Digital Interface I/II and a Heinzinger PNC power supply
 - Q-switched Pulsed Laser and a laser attenuator from CryLas
 - Newport SMC100PP single axis motion controller for 2-phase stepper motors
 - Pfeiffer TPG controller (TPG 25x, TPG 26x and TPG 36x) for Compact pressure Gauges
- PEP 561 compatibility and related corrections for static type checking (now in CI)
- **Refactorings:**
 - Protected non-thread safe read and write in communication protocols
 - Device sequence mixin: start/stop, add/rm and lookup
 - *.format()* to f-strings
 - more enumerations and a quite some improvements of existing code
- Improved error docstrings (`:raises:` annotations) and extended tests for errors.

7.34 0.3.3 (2019-05-08)

- Use PyPI labjack-ljm (no external dependencies)

7.35 0.3.2 (2019-05-08)

- INSTALLATION.rst with LJMPython prerequisite info

7.36 0.3.1 (2019-05-02)

- readthedocs.org support

7.37 0.3 (2019-05-02)

- Prevent an automatic close of VISA connection when not used.
- Rhode & Schwarz RTO 1024 oscilloscope using VISA interface over `TCP::INSTR`.
- Extended tests incl. messages sent to devices.
- Added Supercube device using an OPC UA client
- Added Supercube 2015 device using an OPC UA client (for interfacing with old system version)

7.38 0.2.1 (2019-04-01)

- Fix issue with LJMPython not being installed automatically with setuptools.

7.39 0.2.0 (2019-03-31)

- LabJack LJM Library communication wrapper and LabJack device.
- Modbus TCP communication protocol.
- Schneider Electric ILS2T stepper motor drive device.
- Elektro-Automatik PSI9000 current source device and VISA communication wrapper.
- Separate configuration classes for communication protocols and devices.
- Simple experiment manager class.

7.40 0.1.0 (2019-02-06)

- Communication protocol base and serial communication implementation.
- Device base and MBW973 implementation.

INDICES AND TABLES

- `genindex`
- `modindex`
- `search`

PYTHON MODULE INDEX

h

- [hvl_ccb](#), 204
- [hvl_ccb.comm](#), 35
 - [hvl_ccb.comm.base](#), 11
 - [hvl_ccb.comm.labjack_ljm](#), 16
 - [hvl_ccb.comm.modbus_tcp](#), 19
 - [hvl_ccb.comm.opc](#), 21
 - [hvl_ccb.comm.serial](#), 24
 - [hvl_ccb.comm.tcp](#), 28
 - [hvl_ccb.comm.telnet](#), 30
 - [hvl_ccb.comm.visa](#), 32
- [hvl_ccb.configuration](#), 200
- [hvl_ccb.dev](#), 192
 - [hvl_ccb.dev.base](#), 187
 - [hvl_ccb.dev.crylas](#), 46
 - [hvl_ccb.dev.crylas.crylas](#), 35
 - [hvl_ccb.dev.cube](#), 61
 - [hvl_ccb.dev.cube.alarms](#), 46
 - [hvl_ccb.dev.cube.base](#), 47
 - [hvl_ccb.dev.cube.constants](#), 53
 - [hvl_ccb.dev.cube.earthing_stick](#), 55
 - [hvl_ccb.dev.cube.errors](#), 56
 - [hvl_ccb.dev.cube.picube](#), 57
 - [hvl_ccb.dev.cube.support](#), 60
 - [hvl_ccb.dev.cube.switches](#), 60
 - [hvl_ccb.dev.ea_psi9000](#), 67
 - [hvl_ccb.dev.ea_psi9000.ea_psi9000](#), 62
 - [hvl_ccb.dev.fluke884x](#), 76
 - [hvl_ccb.dev.fluke884x.base](#), 67
 - [hvl_ccb.dev.fluke884x.constants](#), 72
 - [hvl_ccb.dev.fluke884x.ranges](#), 73
 - [hvl_ccb.dev.fug](#), 89
 - [hvl_ccb.dev.fug.fug](#), 76
 - [hvl_ccb.dev.heinzinger](#), 97
 - [hvl_ccb.dev.heinzinger.base](#), 90
 - [hvl_ccb.dev.heinzinger.constants](#), 92
 - [hvl_ccb.dev.heinzinger.device](#), 93
 - [hvl_ccb.dev.heinzinger.mixin](#), 96
 - [hvl_ccb.dev.highland_t560](#), 102
 - [hvl_ccb.dev.highland_t560.base](#), 97
 - [hvl_ccb.dev.highland_t560.channel](#), 100
 - [hvl_ccb.dev.highland_t560.device](#), 100
 - [hvl_ccb.dev.labjack](#), 110
 - [hvl_ccb.dev.labjack.labjack](#), 103
 - [hvl_ccb.dev.lauda](#), 118
 - [hvl_ccb.dev.lauda.lauda](#), 111
 - [hvl_ccb.dev.mbw973](#), 122
 - [hvl_ccb.dev.mbw973.mbw973](#), 118
 - [hvl_ccb.dev.newport](#), 137
 - [hvl_ccb.dev.newport.newport](#), 123
 - [hvl_ccb.dev.pfeiffer_tpg](#), 144
 - [hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg](#), 138
 - [hvl_ccb.dev.protocols](#), 146
 - [hvl_ccb.dev.protocols.sources](#), 145
 - [hvl_ccb.dev.rs_rto1024](#), 154
 - [hvl_ccb.dev.rs_rto1024.rs_rto1024](#), 146
 - [hvl_ccb.dev.se_ils2t](#), 162
 - [hvl_ccb.dev.se_ils2t.se_ils2t](#), 155
 - [hvl_ccb.dev.sst_luminox](#), 167
 - [hvl_ccb.dev.sst_luminox.sst_luminox](#), 163
 - [hvl_ccb.dev.technix](#), 174
 - [hvl_ccb.dev.technix.base](#), 168
 - [hvl_ccb.dev.technix.device](#), 171
 - [hvl_ccb.dev.tiepie](#), 185
 - [hvl_ccb.dev.tiepie.base](#), 174
 - [hvl_ccb.dev.tiepie.channel](#), 176
 - [hvl_ccb.dev.tiepie.device](#), 179
 - [hvl_ccb.dev.tiepie.generator](#), 180
 - [hvl_ccb.dev.tiepie.oscilloscope](#), 182
 - [hvl_ccb.dev.tiepie.utils](#), 185
 - [hvl_ccb.dev.utils](#), 190
 - [hvl_ccb.dev.visa](#), 190
- [hvl_ccb.error](#), 202
- [hvl_ccb.experiment_manager](#), 202
- [hvl_ccb.utils](#), 200
 - [hvl_ccb.utils.conversion](#), 196
 - [hvl_ccb.utils.conversion.map_range](#), 192
 - [hvl_ccb.utils.conversion.sensor](#), 193
 - [hvl_ccb.utils.conversion.unit](#), 194
 - [hvl_ccb.utils.conversion.utils](#), 195
 - [hvl_ccb.utils.enum](#), 196
 - [hvl_ccb.utils.poller](#), 198
 - [hvl_ccb.utils.typing](#), 199
 - [hvl_ccb.utils.validation](#), 199

A

- ABSOLUTE (*TiePieOscilloscopeTriggerLevelMode* attribute), 178
- ABSOLUTE_POSITION (*ILS2T.ActionsPtp* attribute), 155
- AC (*NewportConfigCommands* attribute), 123
- AC_100KV (*PowerSetup* attribute), 54
- AC_150KV (*PowerSetup* attribute), 54
- AC_200KV (*PowerSetup* attribute), 54
- AC_50KV (*PowerSetup* attribute), 54
- ac_current_range (*Fluke8845a* attribute), 67
- ac_voltage_range (*Fluke8845a* attribute), 67
- ACA (*TiePieOscilloscopeChannelCoupling* attribute), 177
- acceleration (*NewportSMC100PPConfig* attribute), 131
- ACCESS_ENABLE (*ILS2TRegAddr* attribute), 161
- access_lock (*CommunicationProtocol* attribute), 14
- ACCurrentRange (class in *hvl_ccb.dev.fluke884x.ranges*), 73
- ACTION_JOG_VALUE (*ILS2T* attribute), 155
- activate_clock_output() (*T560* method), 100
- activate_measurements() (*RTO1024* method), 146
- activate_output() (*Luminox* method), 163
- activate_remote_mode() (*Fluke8845a* method), 67
- ACTIVE (*CryLasLaser.AnswersStatus* attribute), 39
- active_alarms() (*BaseCube* method), 47
- ACTIVE_HIGH (*Polarity* attribute), 98
- ACTIVE_LOW (*Polarity* attribute), 98
- actualsetvalue (*FuGProbusVSetRegisters* property), 85
- ACV (*TiePieOscilloscopeChannelCoupling* attribute), 178
- ACVoltageRange (class in *hvl_ccb.dev.fluke884x.ranges*), 73
- adc_mode (*FuGProbusVMonitorRegisters* property), 85
- add_device() (*DeviceSequenceMixin* method), 188
- add_device() (*ExperimentManager* method), 202
- ADDR_INCORRECT (*NewportSMC100PPSerialCommunication.ControllerErrors* attribute), 133
- address (*NewportSMC100PPConfig* attribute), 131
- address (*VisaCommunicationConfig* property), 34
- address() (*VisaCommunicationConfig.InterfaceType* method), 33
- ADMODE (*FuGProbusIVCommands* attribute), 82
- ALL (*TiePieOscilloscopeAutoResolutionModes* attribute), 184
- all_measurements (*LuminoxMeasurementType* attribute), 165
- all_measurements_types() (*LuminoxMeasurementType* class method), 165
- amplitude (*TiePieGeneratorConfig* property), 180
- ANALOG (*LaudaProRp245eConfig.ExtControlModeEnum* attribute), 115
- analog_control (*FuGProbusVDIRegisters* property), 84
- ANY (*LabJack.DeviceType* attribute), 105
- ANY (*LJMCommunicationConfig.ConnectionType* attribute), 17
- ANY (*LJMCommunicationConfig.DeviceType* attribute), 17
- ANY (*TiePieOscilloscopeTriggerKind* attribute), 178
- ApertureRange (class in *hvl_ccb.dev.fluke884x.ranges*), 74
- ARBITRARY (*TiePieGeneratorSignalType* attribute), 181
- AsyncCommunicationProtocol (class in *hvl_ccb.comm.base*), 11
- AsyncCommunicationProtocolConfig (class in *hvl_ccb.comm.base*), 13
- ATM (*Pressure* attribute), 194
- ATMOSPHERE (*Pressure* attribute), 194
- attenuation (*CryLasAttenuator* property), 36
- AUTO (*LaudaProRp245eConfig.OperationModeEnum* attribute), 115
- AUTO (*RTO1024.TriggerModes* attribute), 146
- AUTO (*SwitchOperatingStatus* attribute), 60
- auto_install_mode (*T560* property), 100
- auto_install_mode (*T560Config* attribute), 101
- auto_laser_on (*CryLasLaserConfig* attribute), 42
- auto_resolution_mode (*TiePieOscilloscopeConfig* property), 184
- AutoInstallMode (class in *hvl_ccb.dev.highland_t560.base*), 97
- AutoNumberNameEnum (class in *hvl_ccb.utils.enum*), 196

B

BA (*NewportConfigCommands* attribute), 123
 backlash_compensation (*NewportSMC100PPConfig* attribute), 132
 backup_waveform() (*RTO1024* method), 147
 BAR (*Pressure* attribute), 194
 barometric_pressure (*LuminosMeasurementType* attribute), 165
 base_velocity (*NewportSMC100PPConfig* attribute), 132
 BaseCube (class in *hvl_ccb.dev.cube.base*), 47
 BaseCubeConfiguration (class in *hvl_ccb.dev.cube.base*), 50
 BaseCubeOpcUaCommunication (class in *hvl_ccb.dev.cube.base*), 51
 BaseCubeOpcUaCommunicationConfig (class in *hvl_ccb.dev.cube.base*), 51
 BATH_TEMP (*LaudaProRp245eCommand* attribute), 113
 baudrate (*CryLasAttenuatorSerialCommunicationConfig* attribute), 38
 baudrate (*CryLasLaserSerialCommunicationConfig* attribute), 45
 baudrate (*FuGSerialCommunicationConfig* attribute), 87
 baudrate (*HeinzingerSerialCommunicationConfig* attribute), 91
 baudrate (*LuminosSerialCommunicationConfig* attribute), 166
 baudrate (*MBW973SerialCommunicationConfig* attribute), 121
 baudrate (*NewportSMC100PPSerialCommunicationConfig* attribute), 136
 baudrate (*PfeifferTPGSerialCommunicationConfig* attribute), 143
 baudrate (*SerialCommunicationConfig* attribute), 26
 BH (*NewportConfigCommands* attribute), 123
 board (*VisaCommunicationConfig* attribute), 34
 BoolEnum (class in *hvl_ccb.utils.enum*), 196
 breakdown_detection_active (*BaseCube* property), 47
 breakdown_detection_reset() (*BaseCube* method), 47
 breakdown_detection_triggered (*BaseCube* property), 47
 bufsize (*TcpCommunicationConfig* attribute), 29
 build_str() (*LaudaProRp245eCommand* method), 115
 BUS (*TriggerSource* attribute), 73
 bytesize (*CryLasAttenuatorSerialCommunicationConfig* attribute), 38
 bytesize (*CryLasLaserSerialCommunicationConfig* attribute), 45
 bytesize (*FuGSerialCommunicationConfig* attribute), 87

bytesize (*HeinzingerSerialCommunicationConfig* attribute), 91
 bytesize (*LuminosSerialCommunicationConfig* attribute), 166
 bytesize (*MBW973SerialCommunicationConfig* attribute), 121
 bytesize (*NewportSMC100PPSerialCommunicationConfig* attribute), 136
 bytesize (*PfeifferTPGSerialCommunicationConfig* attribute), 143
 Bytesize (*SerialCommunicationConfig* attribute), 26
 bytesize (*SerialCommunicationConfig* attribute), 26

C

C (*LabJack.TemperatureUnit* attribute), 105
 C (*LabJack.ThermocoupleType* attribute), 106
 C (*Temperature* attribute), 195
 calibration_factor (*CryLasLaserConfig* attribute), 42
 calibration_factor (*LEM4000S* attribute), 193
 calibration_mode (*FuGProbusVDIRegisters* property), 84
 cc_mode (*FuGProbusVDIRegisters* property), 84
 CCBEError, 202
 cee16_socket (*BaseCube* property), 47
 CELSIUS (*Temperature* attribute), 195
 ch_a (*T560* property), 100
 ch_b (*T560* property), 100
 ch_c (*T560* property), 101
 ch_d (*T560* property), 101
 channels_enabled (*TiePieOscilloscope* property), 182
 check_for_error() (*NewportSMC100PPSerialCommunication* method), 134
 check_master_slave_config() (*PSI9000* method), 62
 chunk_size (*VisaCommunicationConfig* attribute), 34
 clean_amplitude() (*TiePieGeneratorConfig* method), 180
 clean_auto_resolution_mode() (*TiePieOscilloscopeConfig* static method), 184
 clean_coupling() (*TiePieOscilloscopeChannelConfig* static method), 177
 clean_enabled() (*TiePieGeneratorConfig* static method), 180
 clean_enabled() (*TiePieOscilloscopeChannelConfig* static method), 177
 clean_frequency() (*TiePieGeneratorConfig* method), 180
 clean_input_range() (*TiePieOscilloscopeChannelConfig* method), 177
 clean_offset() (*TiePieGeneratorConfig* method), 180
 clean_pre_sample_ratio() (*TiePieOscilloscopeConfig* method), 184

- `clean_probe_offset()` (*TiePieOscilloscopeChannelConfig method*), 177
- `clean_record_length()` (*TiePieOscilloscopeConfig method*), 184
- `clean_resolution()` (*TiePieOscilloscopeConfig static method*), 184
- `clean_sample_rate()` (*TiePieOscilloscopeConfig method*), 184
- `clean_signal_type()` (*TiePieGeneratorConfig static method*), 180
- `clean_trigger_enabled()` (*TiePieOscilloscopeChannelConfig static method*), 177
- `clean_trigger_hysteresis()` (*TiePieOscilloscopeChannelConfig method*), 177
- `clean_trigger_kind()` (*TiePieOscilloscopeChannelConfig static method*), 177
- `clean_trigger_level()` (*TiePieOscilloscopeChannelConfig method*), 177
- `clean_trigger_level_mode()` (*TiePieOscilloscopeChannelConfig static method*), 177
- `clean_trigger_timeout()` (*TiePieOscilloscopeConfig method*), 184
- `clean_values()` (*AsyncCommunicationProtocolConfig method*), 13
- `clean_values()` (*BaseCubeConfiguration method*), 50
- `clean_values()` (*CryLasAttenuatorConfig method*), 36
- `clean_values()` (*CryLasLaserConfig method*), 42
- `clean_values()` (*EmptyConfig method*), 189, 200
- `clean_values()` (*Fluke8845aConfig method*), 69
- `clean_values()` (*FuGConfig method*), 78
- `clean_values()` (*HeinzingerConfig method*), 95
- `clean_values()` (*ILS2TConfig method*), 159
- `clean_values()` (*LaudaProRp245eConfig method*), 115
- `clean_values()` (*LaudaProRp245eTcpCommunicationConfig method*), 117
- `clean_values()` (*LJMCommunicationConfig method*), 18
- `clean_values()` (*LuminoxConfig method*), 164
- `clean_values()` (*MBW973Config method*), 120
- `clean_values()` (*ModbusTcpCommunicationConfig method*), 20
- `clean_values()` (*NewportSMC100PPConfig method*), 132
- `clean_values()` (*OpcUaCommunicationConfig method*), 22
- `clean_values()` (*PfeifferTPGConfig method*), 141
- `clean_values()` (*PICubeConfiguration method*), 58
- `clean_values()` (*PSI9000Config method*), 64
- `clean_values()` (*SerialCommunicationConfig method*), 26
- `clean_values()` (*T560Config method*), 101
- `clean_values()` (*TcpCommunicationConfig method*), 29
- `clean_values()` (*TechnixConfig method*), 172
- `clean_values()` (*TelnetCommunicationConfig method*), 31
- `clean_values()` (*TiePieDeviceConfig method*), 174
- `clean_values()` (*VisaCommunicationConfig method*), 34
- `clean_waveform()` (*TiePieGeneratorConfig method*), 180
- `clear_display_message()` (*Fluke8845a method*), 67
- `clear_error_queue()` (*Fluke8845a method*), 68
- `Client` (*class in hvl_ccb.comm.opc*), 21
- `CLOSE` (*SwitchOperation attribute*), 61
- `close()` (*CommunicationProtocol method*), 14
- `close()` (*LaudaProRp245eTcpCommunication method*), 117
- `close()` (*LJMCommunication method*), 16
- `close()` (*ModbusTcpCommunication method*), 19
- `close()` (*NullCommunicationProtocol method*), 14
- `close()` (*OpcUaCommunication method*), 21
- `close()` (*SerialCommunication method*), 24
- `close()` (*Tcp method*), 28
- `close()` (*TelnetCommunication method*), 30
- `close()` (*VisaCommunication method*), 32
- `close_shutter()` (*CryLasLaser method*), 40
- `CLOSED` (*CryLasLaser.AnswersShutter attribute*), 39
- `CLOSED` (*CryLasLaserShutterStatus attribute*), 46
- `CLOSED` (*DoorStatus attribute*), 53
- `CLOSED` (*SwitchStatus attribute*), 61
- `CMD_EXEC_ERROR` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 133
- `CMD_NOT_ALLOWED` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 133
- `CMD_NOT_ALLOWED_CC` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 133
- `CMD_NOT_ALLOWED_CONFIGURATION` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 133
- `CMD_NOT_ALLOWED_DISABLE` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 133
- `CMD_NOT_ALLOWED_HOMING` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 133
- `CMD_NOT_ALLOWED_MOVING` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 133
- `CMD_NOT_ALLOWED_NOT_REFERENCED` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 133
- `CMD_NOT_ALLOWED_PP` (*New-*

`portSMC100PPSerialCommunication.ControllerErrors` (attribute), 133
`CMD_NOT_ALLOWED_READY` (NewportSMC100PPSerialCommunication.ControllerErrors attribute), 133
`CMR` (PfeifferTPG.SensorTypes attribute), 139
`CODE_OR_ADDR_INVALID` (NewportSMC100PPSerialCommunication.ControllerErrors attribute), 133
`collect_measurement_data()` (TiePieOscilloscope method), 182
`com` (SingleCommDevice property), 189
`COM_TIME_OUT` (LaudaProRp245eCommand attribute), 114
`com_time_out` (LaudaProRp245eConfig attribute), 115
`COM_TIMEOUT` (NewportSMC100PPSerialCommunication.ControllerErrors attribute), 133
`command` (LuminoxMeasurementType property), 165
`COMMAND` (TriggerMode attribute), 99
`command()` (FuGProbusIV method), 81
`communication_channel` (TechnixConfig attribute), 172
`CommunicationError`, 14
`CommunicationProtocol` (class in `hvl_ccb.comm.base`), 14
`config` (ConfigurationMixin property), 200
`CONFIG` (FuGProbusVRegisterGroups attribute), 85
`CONFIG` (NewportSMC100PP.StateMessages attribute), 124
`CONFIG` (NewportStates attribute), 137
`config_cls()` (AsyncCommunicationProtocol static method), 11
`config_cls()` (BaseCube static method), 48
`config_cls()` (BaseCubeOpcUaCommunication static method), 51
`config_cls()` (ConfigurationMixin static method), 200
`config_cls()` (CryLasAttenuator static method), 36
`config_cls()` (CryLasAttenuatorSerialCommunication static method), 37
`config_cls()` (CryLasLaser static method), 40
`config_cls()` (CryLasLaserSerialCommunication static method), 44
`config_cls()` (Device static method), 187
`config_cls()` (Fluke8845a static method), 68
`config_cls()` (Fluke8845aTelnetCommunication static method), 70
`config_cls()` (FuGProbusIV static method), 81
`config_cls()` (FuGSerialCommunication static method), 87
`config_cls()` (Heinzinger static method), 94
`config_cls()` (HeinzingerSerialCommunication static method), 90
`config_cls()` (ILS2T static method), 156
`config_cls()` (ILS2TModbusTcpCommunication static method), 160
`config_cls()` (LaudaProRp245e static method), 111
`config_cls()` (LaudaProRp245eTcpCommunication static method), 117
`config_cls()` (LJMCommunication static method), 16
`config_cls()` (Luminox static method), 163
`config_cls()` (LuminoxSerialCommunication static method), 166
`config_cls()` (MBW973 static method), 119
`config_cls()` (MBW973SerialCommunication static method), 121
`config_cls()` (ModbusTcpCommunication static method), 19
`config_cls()` (NewportSMC100PP static method), 125
`config_cls()` (NewportSMC100PPSerialCommunication static method), 134
`config_cls()` (NullCommunicationProtocol static method), 14
`config_cls()` (OpcUaCommunication static method), 21
`config_cls()` (PfeifferTPG static method), 139
`config_cls()` (PfeifferTPGSerialCommunication static method), 142
`config_cls()` (PICube static method), 57
`config_cls()` (PICubeOpcUaCommunication static method), 59
`config_cls()` (PSI9000 static method), 62
`config_cls()` (PSI9000VisaCommunication static method), 66
`config_cls()` (RTO1024 static method), 147
`config_cls()` (RTO1024VisaCommunication static method), 153
`config_cls()` (SerialCommunication static method), 25
`config_cls()` (SyncCommunicationProtocol static method), 15
`config_cls()` (T560 static method), 101
`config_cls()` (T560Communication static method), 98
`config_cls()` (Tcp static method), 28
`config_cls()` (Technix static method), 171
`config_cls()` (TechnixSerialCommunication static method), 168
`config_cls()` (TechnixTelnetCommunication static method), 169
`config_cls()` (TelnetCommunication static method), 30
`config_cls()` (TiePieOscilloscope static method), 182
`config_cls()` (VisaCommunication static method), 32
`config_cls()` (VisaDevice static method), 190
`config_gen` (TiePieGeneratorMixin attribute), 181
`config_high_pulse()` (LabJack method), 106
`config_osc` (TiePieOscilloscope attribute), 182
`config_osc_channel_dict` (TiePieOscilloscope attribute), 183
`config_status` (FuG property), 76
`configdataclass()` (in module `hvl_ccb.configuration`), 11

- 201
 configuration_save_json() (*ConfigurationMixin* method), 200
 ConfigurationMixin (class in *hvl_ccb.configuration*), 200
 ConfigurationValueWarning, 200
 connection_type (*LJMCommunicationConfig* attribute), 18
 CONT_MODE (*LaudaProRp245eCommand* attribute), 114
 continue_ramp() (*LaudaProRp245e* method), 111
 control_mode (*LaudaProRp245eConfig* attribute), 116
 CONVERSION (*LEM4000S* attribute), 193
 convert() (*LEM4000S* method), 193
 convert() (*LMT70A* method), 194
 convert() (*Sensor* method), 194
 convert() (*Unit* class method), 195
 convert_to_range1() (*MapRanges* method), 193
 convert_to_range2() (*MapRanges* method), 193
 convert_value_to_str() (in module *hvl_ccb.utils.conversion.utils*), 195
 ConvertableTypes (in module *hvl_ccb.utils.typing*), 199
 COOLOFF (*LaudaProRp245eConfig.OperationModeEnum* attribute), 115
 COOLON (*LaudaProRp245eConfig.OperationModeEnum* attribute), 115
 coupling (*TiePieOscilloscopeChannelConfig* property), 177
 CR (*FuGTerminators* attribute), 88
 create_serial_port() (*SerialCommunicationConfig* method), 26
 create_telnet() (*TelnetCommunicationConfig* method), 31
 CRLF (*FuGTerminators* attribute), 88
 CryLasAttenuator (class in *hvl_ccb.dev.crylas.crylas*), 36
 CryLasAttenuatorConfig (class in *hvl_ccb.dev.crylas.crylas*), 36
 CryLasAttenuatorError, 37
 CryLasAttenuatorSerialCommunication (class in *hvl_ccb.dev.crylas.crylas*), 37
 CryLasAttenuatorSerialCommunicationConfig (class in *hvl_ccb.dev.crylas.crylas*), 37
 CryLasLaser (class in *hvl_ccb.dev.crylas.crylas*), 39
 CryLasLaser.AnswersShutter (class in *hvl_ccb.dev.crylas.crylas*), 39
 CryLasLaser.AnswersStatus (class in *hvl_ccb.dev.crylas.crylas*), 39
 CryLasLaser.LaserStatus (class in *hvl_ccb.dev.crylas.crylas*), 39
 CryLasLaser.RepetitionRates (class in *hvl_ccb.dev.crylas.crylas*), 39
 CryLasLaserConfig (class in *hvl_ccb.dev.crylas.crylas*), 42
 CryLasLaserError, 43
 CryLasLaserNotReadyError, 43
 CryLasLaserPoller (class in *hvl_ccb.dev.crylas.crylas*), 43
 CryLasLaserSerialCommunication (class in *hvl_ccb.dev.crylas.crylas*), 43
 CryLasLaserSerialCommunicationConfig (class in *hvl_ccb.dev.crylas.crylas*), 44
 CryLasLaserShutterStatus (class in *hvl_ccb.dev.crylas.crylas*), 46
 CubeEarthingStickOperationError, 56
 CubeError, 56
 CubeRemoteControlError, 56
 CubeStatusChangeError, 56
 CubeStopError, 56
 current (*FuG* property), 76
 CURRENT (*FuGProbusIVCommands* attribute), 82
 CURRENT (*FuGReadbackChannels* attribute), 87
 current (*Heinzinger* property), 94
 current (*Source* property), 145
 current (*Technix* property), 171
 CURRENT_AC (*MeasurementFunction* attribute), 72
 CURRENT_DC (*MeasurementFunction* attribute), 72
 current_filter (*Fluke8845a* attribute), 68
 current_lower_limit (*PSI9000Config* attribute), 65
 current_monitor (*FuG* property), 76
 current_primary (*PICube* property), 57
 current_upper_limit (*PSI9000Config* attribute), 65
 CurrentPosition (New-portSMC100PPConfig.HomeSearch attribute), 131
 cv_mode (*FuGProbusVDIRegisters* property), 84
- ## D
- datachange_notification() (*OpcUaSubHandler* method), 24
 date_of_manufacture (*LuminosMeasurementType* attribute), 165
 datetime_to_opc() (*BaseCube* class method), 48
 DC (*TiePieGeneratorSignalType* attribute), 181
 DC_140KV (*PowerSetup* attribute), 55
 DC_280KV (*PowerSetup* attribute), 55
 dc_current_range (*Fluke8845a* attribute), 68
 dc_voltage_range (*Fluke8845a* attribute), 68
 DC_VOLTAGE_TOO_LOW (New-portSMC100PP.MotorErrors attribute), 124
 DCA (*TiePieOscilloscopeChannelCoupling* attribute), 178
 DCCurrentRange (class in *hvl_ccb.dev.fluke884x.ranges*), 74
 DCV (*TiePieOscilloscopeChannelCoupling* attribute), 178
 DCVoltageRange (class in *hvl_ccb.dev.fluke884x.ranges*), 74
 default_com_cls() (*BaseCube* static method), 48

- default_com_cls() (*CryLasAttenuator static method*), 36
- default_com_cls() (*CryLasLaser static method*), 40
- default_com_cls() (*Fluke8845a static method*), 68
- default_com_cls() (*FuGProbusIV static method*), 81
- default_com_cls() (*Heinzinger static method*), 94
- default_com_cls() (*ILS2T static method*), 156
- default_com_cls() (*LabJack static method*), 106
- default_com_cls() (*LaudaProRp245e static method*), 111
- default_com_cls() (*Luminox static method*), 163
- default_com_cls() (*MBW973 static method*), 119
- default_com_cls() (*NewportSMC100PP static method*), 125
- default_com_cls() (*PfeifferTPG static method*), 139
- default_com_cls() (*PICube static method*), 57
- default_com_cls() (*PSI9000 static method*), 62
- default_com_cls() (*RTO1024 static method*), 147
- default_com_cls() (*SingleCommDevice static method*), 189
- default_com_cls() (*T560 static method*), 101
- default_com_cls() (*Technix method*), 171
- default_com_cls() (*TiePieOscilloscope static method*), 183
- default_com_cls() (*VisaDevice static method*), 190
- DEFAULT_IO_SCANNING_CONTROL_VALUES (*ILS2T attribute*), 155
- default_n_attempts_read_text_nonempty (*AsyncCommunicationProtocolConfig attribute*), 13
- default_n_attempts_read_text_nonempty (*FuGSerialCommunicationConfig attribute*), 88
- default_n_attempts_read_text_nonempty (*HeinzingerSerialCommunicationConfig attribute*), 91
- default_number_of_recordings (*HeinzingerConfig attribute*), 95
- DeprecatedHeinzingerMixin (*class in hvl_ccb.dev.heinzinger.mixin*), 96
- Device (*class in hvl_ccb.dev.base*), 187
- DEVICE_TYPE (*LaudaProRp245eCommand attribute*), 114
- device_type (*LJMCommunicationConfig attribute*), 18
- DeviceError, 187
- DeviceExistingError, 187
- DeviceFailuresError, 187
- devices_failed_start (*DeviceSequenceMixin attribute*), 188
- devices_failed_start (*ExperimentManager attribute*), 203
- devices_failed_stop (*DeviceSequenceMixin attribute*), 188
- devices_failed_stop (*ExperimentManager attribute*), 203
- DeviceSequenceMixin (*class in hvl_ccb.dev.base*), 187
- di (*FuG property*), 77
- digital_control (*FuGProbusVDIRegisters property*), 84
- DIOChannel (*LabJack attribute*), 105
- DIODE (*MeasurementFunction attribute*), 72
- DISABLE (*NewportStates attribute*), 137
- disable() (*ILS2T method*), 156
- DISABLE_FROM_JOGGING (*NewportSMC100PP.StateMessages attribute*), 124
- DISABLE_FROM_MOVING (*NewportSMC100PP.StateMessages attribute*), 124
- DISABLE_FROM_READY (*NewportSMC100PP.StateMessages attribute*), 125
- disable_pulses() (*LabJack method*), 106
- DISABLED (*TiePieOscilloscopeAutoResolutionModes attribute*), 184
- DisableEspStageCheck (*NewportSMC100PPConfig.EspStageConfig attribute*), 131
- disarm_trigger() (*T560 method*), 101
- disconnect() (*Client method*), 21
- DISPLACEMENT_OUT_OF_LIMIT (*NewportSMC100PPSerialCommunication.ControllerErrors attribute*), 133
- display_enable (*Fluke8845a property*), 68
- DISPLAY_MAX_LENGTH (*Fluke8845a attribute*), 67
- display_message (*Fluke8845a property*), 68
- display_message_board() (*BaseCube method*), 48
- display_status_board() (*BaseCube method*), 48
- do_ioscanning_write() (*ILS2T method*), 157
- door_1_status (*BaseCube attribute*), 48
- door_2_status (*BaseCube attribute*), 48
- door_3_status (*BaseCube attribute*), 48
- DoorStatus (*class in hvl_ccb.dev.cube.constants*), 53
- ## E
- E (*LabJack.ThermocoupleType attribute*), 106
- E0 (*FuGErrorcodes attribute*), 79
- E1 (*FuGErrorcodes attribute*), 79
- E10 (*FuGErrorcodes attribute*), 79
- E100 (*FuGErrorcodes attribute*), 79
- E106 (*FuGErrorcodes attribute*), 79
- E11 (*FuGErrorcodes attribute*), 79
- E115 (*FuGErrorcodes attribute*), 79
- E12 (*FuGErrorcodes attribute*), 79
- E125 (*FuGErrorcodes attribute*), 79
- E13 (*FuGErrorcodes attribute*), 79
- E135 (*FuGErrorcodes attribute*), 79
- E14 (*FuGErrorcodes attribute*), 80
- E145 (*FuGErrorcodes attribute*), 80
- E15 (*FuGErrorcodes attribute*), 80

E155 (*FuErrorcodes attribute*), 80
 E16 (*FuErrorcodes attribute*), 80
 E165 (*FuErrorcodes attribute*), 80
 E2 (*FuErrorcodes attribute*), 80
 E206 (*FuErrorcodes attribute*), 80
 E306 (*FuErrorcodes attribute*), 80
 E4 (*FuErrorcodes attribute*), 80
 E5 (*FuErrorcodes attribute*), 80
 E504 (*FuErrorcodes attribute*), 80
 E505 (*FuErrorcodes attribute*), 80
 E6 (*FuErrorcodes attribute*), 80
 E666 (*FuErrorcodes attribute*), 80
 E7 (*FuErrorcodes attribute*), 80
 E8 (*FuErrorcodes attribute*), 80
 E9 (*FuErrorcodes attribute*), 80
 earthing_rod_1_status (*BaseCube attribute*), 48
 earthing_rod_2_status (*BaseCube attribute*), 48
 earthing_rod_3_status (*BaseCube attribute*), 48
 EarthingRodStatus (class in *hvl_ccb.dev.cube.constants*), 53
 EEPROM_ACCESS_ERROR (New-
portSMC100PPSerialCommunication.ControllerErrors
attribute), 134
 EIGHT (*RecordingsEnum attribute*), 93
 EIGHT_BIT (*TiePieOscilloscopeResolution attribute*),
 185
 EIGHT_HUNDRED_MILLI_VOLT (*TiePieOscilloscopeRange*
attribute), 178
 EIGHT_VOLT (*TiePieOscilloscopeRange attribute*), 178
 EIGHTBITS (*SerialCommunicationBytesize attribute*), 25
 EIGHTY_VOLT (*TiePieOscilloscopeRange attribute*), 178
 EmptyConfig (class in *hvl_ccb.configuration*), 200
 EmptyConfig (class in *hvl_ccb.dev.base*), 189
 enable() (*ILS2T method*), 157
 enable_clock() (*LabJack method*), 106
 enabled (*TiePieGeneratorConfig property*), 180
 enabled (*TiePieOscilloscopeChannelConfig property*),
 177
 EnableEspStageCheck (New-
portSMC100PPConfig.EspStageConfig attribute), 131
 encoding (*AsyncCommunicationProtocolConfig attribute*), 13
 encoding (*NewportSMC100PPSerialCommunicationConfig*
attribute), 136
 encoding_error_handling (*AsyncCommunicationProtocolConfig*
attribute), 13
 encoding_error_handling (New-
portSMC100PPSerialCommunicationConfig
attribute), 136
 EndOfRunSwitch (New-
portSMC100PPConfig.HomeSearch attribute),
 131
 EndOfRunSwitch_and_Index (New-
portSMC100PPConfig.HomeSearch attribute),
 131
 endpoint_name (*BaseCubeOpcUaCommunicationCon-*
fig attribute), 52
 endpoint_name (*OpcUaCommunicationConfig attribute*), 23
 endpoint_name (*PICubeOpcUaCommunicationConfig*
attribute), 59
 ERROR (*DoorStatus attribute*), 53
 ERROR (*ExperimentStatus attribute*), 203
 ERROR (*SafetyStatus attribute*), 55
 ERROR (*SwitchStatus attribute*), 61
 errorcode (*FuError attribute*), 79
 ESP_STAGE_NAME_INVALID (New-
portSMC100PPSerialCommunication.ControllerErrors
attribute), 134
 ETH (*LaudaProRp245eConfig.ExtControlModeEnum attribute*), 115
 ETHERNET (*LJMCommunicationConfig.ConnectionType*
attribute), 17
 EVEN (*SerialCommunicationParity attribute*), 27
 Event_notification() (*OpcUaSubHandler method*),
 24
 EXECUTE (*FuGProbusIVCommands attribute*), 82
 execute_absolute_position() (*ILS2T method*), 157
 execute_on_x (*FuGProbusVConfigRegisters property*),
 83
 execute_relative_step() (*ILS2T method*), 157
 EXECUTEONX (*FuGProbusIVCommands attribute*), 82
 exit_configuration() (*NewportSMC100PP method*),
 125
 exit_configuration_wait_sec (New-
portSMC100PPConfig attribute), 132
 EXPERIMENT_BLOCKED (*EarthingRodStatus attribute*), 53
 EXPERIMENT_READY (*EarthingRodStatus attribute*), 53
 ExperimentError, 202
 ExperimentManager (class in
hvl_ccb.experiment_manager), 202
 ExperimentStatus (class in
hvl_ccb.experiment_manager), 203
 EXPT100 (*LaudaProRp245eConfig.ExtControlModeEnum*
attribute), 115
 EXT_FALLING_EDGE (*TriggerMode attribute*), 99
 EXT_RISING_EDGE (*TriggerMode attribute*), 99
 EXTERNAL (*TriggerSource attribute*), 73
 EXTERNAL_SOURCE (*PowerSetup attribute*), 55
 EXTERNAL_TEMP (*LaudaProRp245eCommand attribute*),
 114
F
 F (*LabJack.TemperatureUnit attribute*), 105
 F (*Temperature attribute*), 195
 FAHRENHEIT (*Temperature attribute*), 195
 failures (*DeviceFailuresError attribute*), 187

- FALLING (*TiePieOscilloscopeTriggerKind* attribute), 178
- FAST (*ILS2T.Ref16Jog* attribute), 156
- FAST_FILTER (*FilterRange* attribute), 75
- fetch() (*Fluke8845a* method), 68
- file_copy() (*RTO1024* method), 147
- FilterRange (class in *hvl_ccb.dev.fluke884x.ranges*), 75
- finish() (*ExperimentManager* method), 203
- FINISHED (*ExperimentStatus* attribute), 203
- FINISHING (*ExperimentStatus* attribute), 203
- fire_trigger() (*T560* method), 101
- FIRMWARE (*FuGReadbackChannels* attribute), 87
- FIVE_MHZ (*LabJack.ClockFrequency* attribute), 104
- FIVEBITS (*SerialCommunicationBytesize* attribute), 25
- FLT_INFO (*ILS2TRegAddr* attribute), 161
- FLT_MEM_DEL (*ILS2TRegAddr* attribute), 161
- FLT_MEM_RESET (*ILS2TRegAddr* attribute), 161
- Fluke8845a (class in *hvl_ccb.dev.fluke884x.base*), 67
- Fluke8845aCheckError, 72
- Fluke8845aConfig (class in *hvl_ccb.dev.fluke884x.base*), 69
- Fluke8845aError, 72
- Fluke8845aTelnetCommunication (class in *hvl_ccb.dev.fluke884x.base*), 70
- Fluke8845aTelnetCommunicationConfig (class in *hvl_ccb.dev.fluke884x.base*), 70
- Fluke8845aUnknownCommandError, 72
- FOLLOWING_ERROR (*NewportSMC100PP.MotorErrors* attribute), 124
- FOLLOWRAMP (*FuGRampModes* attribute), 86
- force_trigger() (*TiePieOscilloscope* method), 183
- force_value() (*AsyncCommunicationProtocolConfig* method), 13
- force_value() (*BaseCubeConfiguration* method), 50
- force_value() (*BaseCubeOpcUaCommunicationConfig* method), 52
- force_value() (*CryLasAttenuatorConfig* method), 36
- force_value() (*CryLasAttenuatorSerialCommunicationConfig* method), 38
- force_value() (*CryLasLaserConfig* method), 42
- force_value() (*CryLasLaserSerialCommunicationConfig* method), 45
- force_value() (*EmptyConfig* method), 189, 201
- force_value() (*Fluke8845aConfig* method), 69
- force_value() (*Fluke8845aTelnetCommunicationConfig* method), 71
- force_value() (*FuGConfig* method), 78
- force_value() (*FuGSerialCommunicationConfig* method), 88
- force_value() (*HeinzingerConfig* method), 95
- force_value() (*HeinzingerSerialCommunicationConfig* method), 91
- force_value() (*ILS2TConfig* method), 159
- force_value() (*ILS2TModbusTcpCommunicationConfig* method), 160
- force_value() (*LaudaProRp245eConfig* method), 116
- force_value() (*LaudaProRp245eTcpCommunicationConfig* method), 117
- force_value() (*LJMCommunicationConfig* method), 18
- force_value() (*LuminoxConfig* method), 164
- force_value() (*LuminoxSerialCommunicationConfig* method), 166
- force_value() (*MBW973Config* method), 120
- force_value() (*MBW973SerialCommunicationConfig* method), 121
- force_value() (*ModbusTcpCommunicationConfig* method), 20
- force_value() (*NewportSMC100PPConfig* method), 132
- force_value() (*NewportSMC100PPSerialCommunicationConfig* method), 136
- force_value() (*OpcUaCommunicationConfig* method), 23
- force_value() (*PfeifferTPGConfig* method), 141
- force_value() (*PfeifferTPGSerialCommunicationConfig* method), 143
- force_value() (*PICubeConfiguration* method), 58
- force_value() (*PICubeOpcUaCommunicationConfig* method), 59
- force_value() (*PSI9000Config* method), 65
- force_value() (*PSI9000VisaCommunicationConfig* method), 66
- force_value() (*RTO1024Config* method), 153
- force_value() (*RTO1024VisaCommunicationConfig* method), 154
- force_value() (*SerialCommunicationConfig* method), 26
- force_value() (*T560CommunicationConfig* method), 99
- force_value() (*T560Config* method), 102
- force_value() (*TcpCommunicationConfig* method), 29
- force_value() (*TechnixConfig* method), 172
- force_value() (*TechnixSerialCommunicationConfig* method), 169
- force_value() (*TechnixTelnetCommunicationConfig* method), 170
- force_value() (*TelnetCommunicationConfig* method), 31
- force_value() (*TiePieDeviceConfig* method), 175
- force_value() (*VisaCommunicationConfig* method), 34
- force_value() (*VisaDeviceConfig* method), 191
- FORTY_MHZ (*LabJack.ClockFrequency* attribute), 104
- FORTY_VOLT (*TiePieOscilloscopeRange* attribute), 178
- FOUR (*RecordingsEnum* attribute), 93
- FOUR_HUNDRED_MILLI_AMPERE (*ACCurrentRange* attribute), 73

FOUR_HUNDRED_MILLI_AMPERE (*DCCurrentRange* attribute), 74
 FOUR_HUNDRED_MILLI_VOLT (*TiePieOscilloscopeRange* attribute), 178
 FOUR_VOLT (*TiePieOscilloscopeRange* attribute), 178
 FOUR_WIRE_RESISTANCE (*MeasurementFunction* attribute), 72
 four_wire_resistance_range (*Fluke8845a* attribute), 68
 FOURTEEN_BIT (*TiePieOscilloscopeResolution* attribute), 185
 FREERUN (*RTO1024.TriggerModes* attribute), 146
 FREQUENCY (*MeasurementFunction* attribute), 72
 frequency (*PICube* property), 57
 frequency (*T560* property), 101
 frequency (*TiePieGeneratorConfig* property), 180
 frequency_aperture (*Fluke8845a* attribute), 68
 FRM (*NewportConfigCommands* attribute), 123
 from_json() (*ConfigurationMixin* class method), 200
 FRS (*NewportConfigCommands* attribute), 123
 FuG (class in *hvl_ccb.dev.fug.fug*), 76
 FuGConfig (class in *hvl_ccb.dev.fug.fug*), 78
 FuGDigitalVal (class in *hvl_ccb.dev.fug.fug*), 79
 FuGError, 79
 FuGErrorcodes (class in *hvl_ccb.dev.fug.fug*), 79
 FuGMonitorModes (class in *hvl_ccb.dev.fug.fug*), 80
 FuGPolarities (class in *hvl_ccb.dev.fug.fug*), 81
 FuGProbusIV (class in *hvl_ccb.dev.fug.fug*), 81
 FuGProbusIVCommands (class in *hvl_ccb.dev.fug.fug*), 82
 FuGProbusV (class in *hvl_ccb.dev.fug.fug*), 82
 FuGProbusVConfigRegisters (class in *hvl_ccb.dev.fug.fug*), 83
 FuGProbusVDIRegisters (class in *hvl_ccb.dev.fug.fug*), 84
 FuGProbusVDORegisters (class in *hvl_ccb.dev.fug.fug*), 84
 FuGProbusVMonitorRegisters (class in *hvl_ccb.dev.fug.fug*), 85
 FuGProbusVRegisterGroups (class in *hvl_ccb.dev.fug.fug*), 85
 FuGProbusVSetRegisters (class in *hvl_ccb.dev.fug.fug*), 85
 FuGRampModes (class in *hvl_ccb.dev.fug.fug*), 86
 FuGReadbackChannels (class in *hvl_ccb.dev.fug.fug*), 86
 FuGSerialCommunication (class in *hvl_ccb.dev.fug.fug*), 87
 FuGSerialCommunicationConfig (class in *hvl_ccb.dev.fug.fug*), 87
 FuGTerminators (class in *hvl_ccb.dev.fug.fug*), 88
 G
 gate_mode (*T560* property), 101
 gate_polarity (*T560* property), 101
 GateMode (class in *hvl_ccb.dev.highland_t560.base*), 98
 GENERATOR (*TiePieDeviceType* attribute), 175
 generator_start() (*TiePieGeneratorMixin* method), 181
 generator_stop() (*TiePieGeneratorMixin* method), 181
 get_acceleration() (*NewportSMC100PP* method), 126
 get_acquire_length() (*RTO1024* method), 147
 get_ain() (*LabJack* method), 106
 get_bath_temp() (*LaudaProRp245e* method), 111
 get_by_p_id() (*LabJack.DeviceType* class method), 105
 get_by_p_id() (*LJMCommunicationConfig.DeviceType* class method), 17
 get_cal_current_source() (*LabJack* method), 107
 get_channel_offset() (*RTO1024* method), 147
 get_channel_position() (*RTO1024* method), 148
 get_channel_range() (*RTO1024* method), 148
 get_channel_scale() (*RTO1024* method), 148
 get_channel_state() (*RTO1024* method), 148
 get_clock() (*LabJack* method), 107
 get_controller_information() (*NewportSMC100PP* method), 126
 get_dc_volt() (*ILS2T* method), 157
 get_device() (*DeviceSequenceMixin* method), 188
 get_device_by_serial_number() (in module *hvl_ccb.dev.tiepie.base*), 175
 get_device_type() (*LaudaProRp245e* method), 111
 get_devices() (*DeviceSequenceMixin* method), 188
 get_digital_input() (*LabJack* method), 107
 get_error_code() (*ILS2T* method), 157
 get_error_queue() (*VisaDevice* method), 191
 get_full_scale_mbar() (*PfeifferTPG* method), 139
 get_full_scale_unitless() (*PfeifferTPG* method), 139
 get_identification() (*VisaDevice* method), 191
 get_interface_version() (*Heinzinger* method), 94
 get_motor_configuration() (*NewportSMC100PP* method), 126
 get_move_duration() (*NewportSMC100PP* method), 126
 get_negative_software_limit() (*NewportSMC100PP* method), 127
 get_number_of_recordings() (*Deprecated-HeinzingerMixin* static method), 96
 get_objects_node() (*Client* method), 21
 get_objects_node() (*Server* method), 24
 get_output() (*PSI9000* method), 63
 get_position() (*ILS2T* method), 157
 get_position() (*NewportSMC100PP* method), 127
 get_positive_software_limit() (*NewportSMC100PP* method), 127

get_product_id() (*LabJack method*), 107
 get_product_name() (*LabJack method*), 107
 get_product_type() (*LabJack method*), 107
 get_pulse_energy_and_rate() (*CryLasLaser method*), 40
 get_reference_point() (*RTO1024 method*), 148
 get_register() (*FuGProbusV method*), 82
 get_repetitions() (*RTO1024 method*), 148
 get_sbus_rh() (*LabJack method*), 107
 get_sbus_temp() (*LabJack method*), 108
 get_serial_number() (*Heinzinger method*), 94
 get_serial_number() (*LabJack method*), 108
 get_state() (*NewportSMC100PP method*), 127
 get_status() (*ILS2T method*), 157
 get_system_lock() (*PSI9000 method*), 63
 get_temperature() (*ILS2T method*), 157
 get_timestamps() (*RTO1024 method*), 149
 get_ui_lower_limits() (*PSI9000 method*), 63
 get_uip_upper_limits() (*PSI9000 method*), 63
 get_voltage_current_setpoint() (*PSI9000 method*), 63
 GetAttr (*class in hvl_ccb.utils.conversion.utils*), 195
 go_home() (*NewportSMC100PP method*), 128
 go_to_configuration() (*NewportSMC100PP method*), 128
 GREEN_NOT_READY (*SafetyStatus attribute*), 55
 GREEN_READY (*SafetyStatus attribute*), 55

H

HARDWARE (*CryLasLaser.RepetitionRates attribute*), 40
 has_safeground (*TiePieOscilloscopeChannelConfig property*), 177
 HEAD (*CryLasLaser.AnswersStatus attribute*), 39
 Heinzinger (*class in hvl_ccb.dev.heinzinger.device*), 93
 HeinzingerConfig (*class in hvl_ccb.dev.heinzinger.device*), 95
 HeinzingerDeviceNotRecognizedError, 92
 HeinzingerError, 92
 HeinzingerSerialCommunication (*class in hvl_ccb.dev.heinzinger.base*), 90
 HeinzingerSerialCommunicationConfig (*class in hvl_ccb.dev.heinzinger.base*), 90
 HeinzingerSetValueError, 92
 HIGH (*LabJack.DIOStatus attribute*), 105
 high_resolution (*FuGProbusVSetRegisters property*), 86
 home_search_polling_interval (*NewportSMC100PPConfig attribute*), 132
 home_search_timeout (*NewportSMC100PPConfig attribute*), 132
 home_search_type (*NewportSMC100PPConfig attribute*), 132
 home_search_velocity (*NewportSMC100PPConfig attribute*), 132

HOME_STARTED (*NewportSMC100PPSerialCommunication.ControllerError attribute*), 134
 HomeSwitch (*NewportSMC100PPConfig.HomeSearch attribute*), 131
 HomeSwitch_and_Index (*NewportSMC100PPConfig.HomeSearch attribute*), 131
 HOMING (*NewportStates attribute*), 137
 HOMING_FROM_RS232 (*NewportSMC100PP.StateMessages attribute*), 125
 HOMING_FROM_SMC (*NewportSMC100PP.StateMessages attribute*), 125
 HOMING_TIMEOUT (*NewportSMC100PP.MotorErrors attribute*), 124
 host (*ModbusTcpCommunicationConfig attribute*), 20
 host (*OpcUaCommunicationConfig attribute*), 23
 host (*TcpCommunicationConfig attribute*), 29
 host (*TelnetCommunicationConfig attribute*), 31
 host (*VisaCommunicationConfig attribute*), 34
 HT (*NewportConfigCommands attribute*), 123
 HUNDRED_VOLT (*ACVoltageRange attribute*), 74
 HUNDRED_VOLT (*DCVoltageRange attribute*), 74
 hvl_ccb
 module, 204
 hvl_ccb.comm
 module, 35
 hvl_ccb.comm.base
 module, 11
 hvl_ccb.comm.labjack_ljm
 module, 16
 hvl_ccb.comm.modbus_tcp
 module, 19
 hvl_ccb.comm.opc
 module, 21
 hvl_ccb.comm.serial
 module, 24
 hvl_ccb.comm.tcp
 module, 28
 hvl_ccb.comm.telnet
 module, 30
 hvl_ccb.comm.visa
 module, 32
 hvl_ccb.configuration
 module, 200
 hvl_ccb.dev
 module, 192
 hvl_ccb.dev.base
 module, 187
 hvl_ccb.dev.crylas
 module, 46
 hvl_ccb.dev.crylas.crylas
 module, 35
 hvl_ccb.dev.cube

module, 61	module, 103
hvl_ccb.dev.cube.alarms	hvl_ccb.dev.lauda
module, 46	module, 118
hvl_ccb.dev.cube.base	hvl_ccb.dev.lauda.lauda
module, 47	module, 111
hvl_ccb.dev.cube.constants	hvl_ccb.dev.mbw973
module, 53	module, 122
hvl_ccb.dev.cube.earthing_stick	hvl_ccb.dev.mbw973.mbw973
module, 55	module, 118
hvl_ccb.dev.cube.errors	hvl_ccb.dev.newport
module, 56	module, 137
hvl_ccb.dev.cube.picube	hvl_ccb.dev.newport.newport
module, 57	module, 123
hvl_ccb.dev.cube.support	hvl_ccb.dev.pfeiffer_tpg
module, 60	module, 144
hvl_ccb.dev.cube.switches	hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg
module, 60	module, 138
hvl_ccb.dev.ea_psi9000	hvl_ccb.dev.protocols
module, 67	module, 146
hvl_ccb.dev.ea_psi9000.ea_psi9000	hvl_ccb.dev.protocols.sources
module, 62	module, 145
hvl_ccb.dev.fluke884x	hvl_ccb.dev.rs_rto1024
module, 76	module, 154
hvl_ccb.dev.fluke884x.base	hvl_ccb.dev.rs_rto1024.rs_rto1024
module, 67	module, 146
hvl_ccb.dev.fluke884x.constants	hvl_ccb.dev.se_ils2t
module, 72	module, 162
hvl_ccb.dev.fluke884x.ranges	hvl_ccb.dev.se_ils2t.se_ils2t
module, 73	module, 155
hvl_ccb.dev.fug	hvl_ccb.dev.sst_luminos
module, 89	module, 167
hvl_ccb.dev.fug.fug	hvl_ccb.dev.sst_luminos.sst_luminos
module, 76	module, 163
hvl_ccb.dev.heinzinger	hvl_ccb.dev.technix
module, 97	module, 174
hvl_ccb.dev.heinzinger.base	hvl_ccb.dev.technix.base
module, 90	module, 168
hvl_ccb.dev.heinzinger.constants	hvl_ccb.dev.technix.device
module, 92	module, 171
hvl_ccb.dev.heinzinger.device	hvl_ccb.dev.tiepie
module, 93	module, 185
hvl_ccb.dev.heinzinger.mixin	hvl_ccb.dev.tiepie.base
module, 96	module, 174
hvl_ccb.dev.highland_t560	hvl_ccb.dev.tiepie.channel
module, 102	module, 176
hvl_ccb.dev.highland_t560.base	hvl_ccb.dev.tiepie.device
module, 97	module, 179
hvl_ccb.dev.highland_t560.channel	hvl_ccb.dev.tiepie.generator
module, 100	module, 180
hvl_ccb.dev.highland_t560.device	hvl_ccb.dev.tiepie.oscilloscope
module, 100	module, 182
hvl_ccb.dev.labjack	hvl_ccb.dev.tiepie.utils
module, 110	module, 185
hvl_ccb.dev.labjack.labjack	hvl_ccb.dev.utils

module, 190
 hvl_ccb.dev.visa
 module, 190
 hvl_ccb.error
 module, 202
 hvl_ccb.experiment_manager
 module, 202
 hvl_ccb.utils
 module, 200
 hvl_ccb.utils.conversion
 module, 196
 hvl_ccb.utils.conversion.map_range
 module, 192
 hvl_ccb.utils.conversion.sensor
 module, 193
 hvl_ccb.utils.conversion.unit
 module, 194
 hvl_ccb.utils.conversion.utils
 module, 195
 hvl_ccb.utils.enum
 module, 196
 hvl_ccb.utils.poller
 module, 198
 hvl_ccb.utils.typing
 module, 199
 hvl_ccb.utils.validation
 module, 199
 hysteresis_compensation (New-
 portSMC100PPConfig attribute), 132

I

ID (FuGProbusIVCommands attribute), 82
 identification (Fluke8845a property), 68
 Identification_error (PfeifferTPG.SensorStatus attribute), 138
 identifier (LJMCommunicationConfig attribute), 18
 identify_device() (FuG method), 77
 identify_device() (Heinzinger method), 94
 identify_sensors() (PfeifferTPG method), 139
 IKR (PfeifferTPG.SensorTypes attribute), 139
 IKR11 (PfeifferTPG.SensorTypes attribute), 139
 IKR9 (PfeifferTPG.SensorTypes attribute), 139
 ILS2T (class in hvl_ccb.dev.se_ils2t.se_ils2t), 155
 ILS2T.ActionsPtp (class in hvl_ccb.dev.se_ils2t.se_ils2t), 155
 ILS2T.Mode (class in hvl_ccb.dev.se_ils2t.se_ils2t), 155
 ILS2T.Ref16Jog (class in hvl_ccb.dev.se_ils2t.se_ils2t), 155
 ILS2T.State (class in hvl_ccb.dev.se_ils2t.se_ils2t), 156
 ILS2TConfig (class in hvl_ccb.dev.se_ils2t.se_ils2t), 159
 ILS2TError, 160
 ILS2TModbusTcpCommunication (class in hvl_ccb.dev.se_ils2t.se_ils2t), 160
 ILS2TModbusTcpCommunicationConfig (class in hvl_ccb.dev.se_ils2t.se_ils2t), 160
 ILS2TRegAddr (class in hvl_ccb.dev.se_ils2t.se_ils2t), 161
 ILS2TRegDatatype (class in hvl_ccb.dev.se_ils2t.se_ils2t), 161
 IMMEDIATE (TriggerSource attribute), 73
 IMMEDIATELY (FuGRampModes attribute), 86
 IMPULSE_140KV (PowerSetup attribute), 55
 IMR (PfeifferTPG.SensorTypes attribute), 139
 INACTIVE (CryLasLaser.AnswersStatus attribute), 39
 INACTIVE (DoorStatus attribute), 53
 INACTIVE (SwitchStatus attribute), 61
 inhibit (Technix property), 171
 init_attenuation (CryLasAttenuatorConfig attribute), 37
 init_monitored_nodes() (OpcUaCommunication method), 21
 init_shutter_status (CryLasLaserConfig attribute), 43
 initialize() (NewportSMC100PP method), 128
 INITIALIZED (ExperimentStatus attribute), 203
 INITIALIZING (ExperimentStatus attribute), 204
 INITIALIZING (SafetyStatus attribute), 55
 initiate_trigger() (Fluke8845a method), 68
 INPUT (FuGProbusVRegisterGroups attribute), 85
 INPUT (GateMode attribute), 98
 input_range (TiePieOscilloscopeChannelConfig property), 177
 INSTALL (AutoInstallMode attribute), 97
 INT32 (ILS2TRegDatatype attribute), 162
 INT_SYNTHESIZER (TriggerMode attribute), 100
 interface_type (PSI9000VisaCommunicationConfig attribute), 66
 interface_type (RTO1024VisaCommunicationConfig attribute), 154
 interface_type (VisaCommunicationConfig attribute), 34
 internal (LabJack.CjcType attribute), 104
 INTERNAL (LaudaProRp245eConfig.ExtControlModeEnum attribute), 115
 IO_SCANNING (ILS2TRegAddr attribute), 161
 IoScanningModeValueError, 162
 is_configdataclass (AsyncCommunicationProtocolConfig attribute), 14
 is_configdataclass (BaseCubeConfiguration attribute), 50
 is_configdataclass (CryLasAttenuatorConfig attribute), 37
 is_configdataclass (CryLasLaserConfig attribute), 43
 is_configdataclass (EmptyConfig attribute), 189, 201
 is_configdataclass (Fluke8845aConfig attribute), 70
 is_configdataclass (FuGConfig attribute), 78

[is_configdataclass \(HeinzingerConfig attribute\), 96](#)
[is_configdataclass \(ILS2TConfig attribute\), 159](#)
[is_configdataclass \(LaudaProRp245eConfig attribute\), 116](#)
[is_configdataclass \(LJMCommunicationConfig attribute\), 18](#)
[is_configdataclass \(LuminoxConfig attribute\), 164](#)
[is_configdataclass \(MBW973Config attribute\), 120](#)
[is_configdataclass \(ModbusTcpCommunicationConfig attribute\), 20](#)
[is_configdataclass \(NewportSMC100PPConfig attribute\), 132](#)
[is_configdataclass \(OpcUaCommunicationConfig attribute\), 23](#)
[is_configdataclass \(PfeifferTPGConfig attribute\), 141](#)
[is_configdataclass \(T560Config attribute\), 102](#)
[is_configdataclass \(TcpCommunicationConfig attribute\), 29](#)
[is_configdataclass \(TechnixConfig attribute\), 173](#)
[is_configdataclass \(TiePieDeviceConfig attribute\), 175](#)
[is_configdataclass \(VisaCommunicationConfig attribute\), 34](#)
[is_data_ready_polling_interval_sec \(TiePieDeviceConfig attribute\), 175](#)
[is_done\(\) \(MBW973 method\), 119](#)
[is_error\(\) \(ExperimentManager method\), 203](#)
[is_finished\(\) \(ExperimentManager method\), 203](#)
[is_in_range\(\) \(ILS2TRegDatatype method\), 162](#)
[is_inactive \(CryLasLaser.LaserStatus property\), 39](#)
[is_measurement_data_ready\(\) \(TiePieOscilloscope method\), 183](#)
[is_measurement_running\(\) \(TiePieOscilloscope method\), 183](#)
[is_open \(Client property\), 21](#)
[is_open \(LJMCommunication property\), 16](#)
[is_open \(OpcUaCommunication property\), 22](#)
[is_open \(SerialCommunication property\), 25](#)
[is_open \(TelnetCommunication property\), 30](#)
[is_polling\(\) \(Poller method\), 198](#)
[is_ready \(CryLasLaser.LaserStatus property\), 39](#)
[is_running\(\) \(ExperimentManager method\), 203](#)
[is_started \(Technix property\), 171](#)
[is_triggered\(\) \(TiePieOscilloscope method\), 183](#)
[is_valid_scale_range_reversed_str\(\) \(PfeifferTPGConfig.Model method\), 141](#)

J

[J \(LabJack.ThermocoupleType attribute\), 106](#)
[jerk_time \(NewportSMC100PPConfig attribute\), 132](#)
[JOG \(ILS2T.Mode attribute\), 155](#)
[jog_run\(\) \(ILS2T method\), 158](#)
[jog_stop\(\) \(ILS2T method\), 158](#)

[JOGGING \(NewportStates attribute\), 137](#)
[JOGGING_FROM_DISABLE \(NewportSMC100PP.StateMessages attribute\), 125](#)
[JOGGING_FROM_READY \(NewportSMC100PP.StateMessages attribute\), 125](#)
[JOGN_FAST \(ILS2TRegAddr attribute\), 161](#)
[JOGN_SLOW \(ILS2TRegAddr attribute\), 161](#)
[JR \(NewportConfigCommands attribute\), 123](#)

K

[K \(LabJack.TemperatureUnit attribute\), 105](#)
[K \(LabJack.ThermocoupleType attribute\), 106](#)
[K \(Temperature attribute\), 195](#)
[KELVIN \(Temperature attribute\), 195](#)
[keys\(\) \(AsyncCommunicationProtocolConfig class method\), 14](#)
[keys\(\) \(BaseCubeConfiguration class method\), 50](#)
[keys\(\) \(BaseCubeOpcUaCommunicationConfig class method\), 52](#)
[keys\(\) \(CryLasAttenuatorConfig class method\), 37](#)
[keys\(\) \(CryLasAttenuatorSerialCommunicationConfig class method\), 38](#)
[keys\(\) \(CryLasLaserConfig class method\), 43](#)
[keys\(\) \(CryLasLaserSerialCommunicationConfig class method\), 45](#)
[keys\(\) \(EmptyConfig class method\), 189, 201](#)
[keys\(\) \(Fluke8845aConfig class method\), 70](#)
[keys\(\) \(Fluke8845aTelnetCommunicationConfig class method\), 71](#)
[keys\(\) \(FuGConfig class method\), 78](#)
[keys\(\) \(FuGSerialCommunicationConfig class method\), 88](#)
[keys\(\) \(HeinzingerConfig class method\), 96](#)
[keys\(\) \(HeinzingerSerialCommunicationConfig class method\), 91](#)
[keys\(\) \(ILS2TConfig class method\), 159](#)
[keys\(\) \(ILS2TModbusTcpCommunicationConfig class method\), 160](#)
[keys\(\) \(LaudaProRp245eConfig class method\), 116](#)
[keys\(\) \(LaudaProRp245eTcpCommunicationConfig class method\), 117](#)
[keys\(\) \(LJMCommunicationConfig class method\), 18](#)
[keys\(\) \(LuminoxConfig class method\), 164](#)
[keys\(\) \(LuminoxSerialCommunicationConfig class method\), 167](#)
[keys\(\) \(MBW973Config class method\), 120](#)
[keys\(\) \(MBW973SerialCommunicationConfig class method\), 122](#)
[keys\(\) \(ModbusTcpCommunicationConfig class method\), 20](#)
[keys\(\) \(NewportSMC100PPConfig class method\), 132](#)

keys() (*NewportSMC100PPSerialCommunicationConfig* class method), 136
 keys() (*OpCuaCommunicationConfig* class method), 23
 keys() (*PfeifferTPGConfig* class method), 141
 keys() (*PfeifferTPGSerialCommunicationConfig* class method), 143
 keys() (*PICubeConfiguration* class method), 58
 keys() (*PICubeOpCuaCommunicationConfig* class method), 59
 keys() (*PSI9000Config* class method), 65
 keys() (*PSI9000VisaCommunicationConfig* class method), 66
 keys() (*RTO1024Config* class method), 153
 keys() (*RTO1024VisaCommunicationConfig* class method), 154
 keys() (*SerialCommunicationConfig* class method), 26
 keys() (*T560CommunicationConfig* class method), 99
 keys() (*T560Config* class method), 102
 keys() (*TcpCommunicationConfig* class method), 29
 keys() (*TechnixConfig* class method), 173
 keys() (*TechnixSerialCommunicationConfig* class method), 169
 keys() (*TechnixTelnetCommunicationConfig* class method), 170
 keys() (*TelnetCommunicationConfig* class method), 31
 keys() (*TiePieDeviceConfig* class method), 175
 keys() (*VisaCommunicationConfig* class method), 34
 keys() (*VisaDeviceConfig* class method), 192

L

LabJack (class in *hvl_ccb.dev.labjack.labjack*), 103
 LabJack.AInRange (class in *hvl_ccb.dev.labjack.labjack*), 104
 LabJack.BitLimit (class in *hvl_ccb.dev.labjack.labjack*), 104
 LabJack.CalMicroAmpere (class in *hvl_ccb.dev.labjack.labjack*), 104
 LabJack.CjcType (class in *hvl_ccb.dev.labjack.labjack*), 104
 LabJack.ClockFrequency (class in *hvl_ccb.dev.labjack.labjack*), 104
 LabJack.DeviceType (class in *hvl_ccb.dev.labjack.labjack*), 105
 LabJack.DIOStatus (class in *hvl_ccb.dev.labjack.labjack*), 105
 LabJack.TemperatureUnit (class in *hvl_ccb.dev.labjack.labjack*), 105
 LabJack.ThermocoupleType (class in *hvl_ccb.dev.labjack.labjack*), 105
 LabJackError, 110
 LabJackIdentifierDIOError, 110
 laser_off() (*CryLasLaser* method), 40
 laser_on() (*CryLasLaser* method), 40
 LaudaProRp245e (class in *hvl_ccb.dev.lauda.lauda*), 111
 LaudaProRp245eCommand (class in *hvl_ccb.dev.lauda.lauda*), 113
 LaudaProRp245eCommandError, 115
 LaudaProRp245eConfig (class in *hvl_ccb.dev.lauda.lauda*), 115
 LaudaProRp245eConfig.ExtControlModeEnum (class in *hvl_ccb.dev.lauda.lauda*), 115
 LaudaProRp245eConfig.OperationModeEnum (class in *hvl_ccb.dev.lauda.lauda*), 115
 LaudaProRp245eTcpCommunication (class in *hvl_ccb.dev.lauda.lauda*), 116
 LaudaProRp245eTcpCommunicationConfig (class in *hvl_ccb.dev.lauda.lauda*), 117
 LEM4000S (class in *hvl_ccb.utils.conversion.sensor*), 193
 LF (*FuGTerminators* attribute), 89
 LFCR (*FuGTerminators* attribute), 89
 LINE_1 (*MessageBoard* attribute), 54
 LINE_10 (*MessageBoard* attribute), 54
 LINE_11 (*MessageBoard* attribute), 54
 LINE_12 (*MessageBoard* attribute), 54
 LINE_13 (*MessageBoard* attribute), 54
 LINE_14 (*MessageBoard* attribute), 54
 LINE_15 (*MessageBoard* attribute), 54
 LINE_2 (*MessageBoard* attribute), 54
 LINE_3 (*MessageBoard* attribute), 54
 LINE_4 (*MessageBoard* attribute), 54
 LINE_5 (*MessageBoard* attribute), 54
 LINE_6 (*MessageBoard* attribute), 54
 LINE_7 (*MessageBoard* attribute), 54
 LINE_8 (*MessageBoard* attribute), 54
 LINE_9 (*MessageBoard* attribute), 54
 list_devices() (*TiePieOscilloscope* static method), 183
 list_directory() (*RTO1024* method), 149
 LJMCommunication (class in *hvl_ccb.comm.labjack_ljm*), 16
 LJMCommunicationConfig (class in *hvl_ccb.comm.labjack_ljm*), 17
 LJMCommunicationConfig.ConnectionType (class in *hvl_ccb.comm.labjack_ljm*), 17
 LJMCommunicationConfig.DeviceType (class in *hvl_ccb.comm.labjack_ljm*), 17
 LJMCommunicationError, 18
 lm34 (*LabJack.CjcType* attribute), 104
 LMT70A (class in *hvl_ccb.utils.conversion.sensor*), 193
 load_configuration() (*RTO1024* method), 149
 load_device_configuration() (*T560* method), 101
 local_display() (*RTO1024* method), 149
 LOCKED (*DoorStatus* attribute), 53
 LOW (*LabJack.DIOStatus* attribute), 105
 LOWER_TEMP (*LaudaProRp245eCommand* attribute), 114
 lower_temp (*LaudaProRp245eConfig* attribute), 116
 Luminos (class in *hvl_ccb.dev.sst_luminos.sst_luminos*), 163

LuminosConfig (class in `hvl_ccb.dev.sst_luminos.sst_luminos`), 164
 LuminosError, 165
 LuminosMeasurementType (class in `hvl_ccb.dev.sst_luminos.sst_luminos`), 165
 LuminosMeasurementTypeDict (in module `hvl_ccb.dev.sst_luminos.sst_luminos`), 165
 LuminosMeasurementTypeError, 165
 LuminosMeasurementTypeValue (in module `hvl_ccb.dev.sst_luminos.sst_luminos`), 165
 LuminosOutputMode (class in `hvl_ccb.dev.sst_luminos.sst_luminos`), 166
 LuminosOutputModeError, 166
 LuminosSerialCommunication (class in `hvl_ccb.dev.sst_luminos.sst_luminos`), 166
 LuminosSerialCommunicationConfig (class in `hvl_ccb.dev.sst_luminos.sst_luminos`), 166
 LUT (LMT70A attribute), 194

M

MANUAL (SwitchOperatingStatus attribute), 61
 MapBitAsymRange (class in `hvl_ccb.utils.conversion.map_range`), 192
 MapBitSymRange (class in `hvl_ccb.utils.conversion.map_range`), 193
 MapRanges (class in `hvl_ccb.utils.conversion.map_range`), 193
 MARK (SerialCommunicationParity attribute), 27
 max_current (FuG property), 77
 max_current (Heinzinger property), 94
 max_current (Source property), 145
 max_current (Technix property), 171
 max_current (TechnixConfig attribute), 173
 max_current_hardware (FuG property), 77
 max_current_hardware (Heinzinger property), 94
 max_pr_number (LaudaProRp245eConfig attribute), 116
 max_pump_level (LaudaProRp245eConfig attribute), 116
 max_timeout_retry_nr (OpcUaCommunicationConfig attribute), 23
 max_voltage (FuG property), 77
 max_voltage (Heinzinger property), 94
 max_voltage (Source property), 145
 max_voltage (Technix property), 172
 max_voltage (TechnixConfig attribute), 173
 max_voltage_hardware (FuG property), 77
 max_voltage_hardware (Heinzinger property), 94
 MAXIMUM (LabJack.ClockFrequency attribute), 104
 MBW973 (class in `hvl_ccb.dev.mbw973.mbw973`), 118
 MBW973Config (class in `hvl_ccb.dev.mbw973.mbw973`), 120
 MBW973ControlRunningError, 121
 MBW973Error, 121
 MBW973PumpRunningError, 121
 MBW973SerialCommunication (class in `hvl_ccb.dev.mbw973.mbw973`), 121
 MBW973SerialCommunicationConfig (class in `hvl_ccb.dev.mbw973.mbw973`), 121
 measure() (Fluke8845a method), 68
 measure() (PfeifferTPG method), 140
 measure_all() (PfeifferTPG method), 140
 measure_current() (DeprecatedHeinzingerMixin static method), 96
 measure_voltage() (DeprecatedHeinzingerMixin static method), 96
 measure_voltage_current() (PSI9000 method), 63
 measurement_function (Fluke8845a property), 69
 MeasurementFunction (class in `hvl_ccb.dev.fluke884x.constants`), 72
 MEDIUM_FILTER (FilterRange attribute), 75
 MessageBoard (class in `hvl_ccb.dev.cube.constants`), 53
 micro_step_per_full_step_factor (NewportSMC100PPConfig attribute), 132
 MILLIMETER_MERCURY (Pressure attribute), 194
 MINIMUM (LabJack.ClockFrequency attribute), 104
 MMHG (Pressure attribute), 194
 ModbusTcpCommunication (class in `hvl_ccb.comm.modbus_tcp`), 19
 ModbusTcpCommunicationConfig (class in `hvl_ccb.comm.modbus_tcp`), 20
 ModbusTcpConnectionFailedError, 21
 model (PfeifferTPGConfig attribute), 141
 module
 hvl_ccb, 204
 hvl_ccb.comm, 35
 hvl_ccb.comm.base, 11
 hvl_ccb.comm.labjack_ljm, 16
 hvl_ccb.comm.modbus_tcp, 19
 hvl_ccb.comm.opc, 21
 hvl_ccb.comm.serial, 24
 hvl_ccb.comm.tcp, 28
 hvl_ccb.comm.telnet, 30
 hvl_ccb.comm.visa, 32
 hvl_ccb.configuration, 200
 hvl_ccb.dev, 192
 hvl_ccb.dev.base, 187
 hvl_ccb.dev.crylas, 46
 hvl_ccb.dev.crylas.crylas, 35
 hvl_ccb.dev.cube, 61
 hvl_ccb.dev.cube.alarms, 46
 hvl_ccb.dev.cube.base, 47
 hvl_ccb.dev.cube.constants, 53
 hvl_ccb.dev.cube.earthing_stick, 55
 hvl_ccb.dev.cube.errors, 56
 hvl_ccb.dev.cube.picube, 57
 hvl_ccb.dev.cube.support, 60
 hvl_ccb.dev.cube.switches, 60
 hvl_ccb.dev.ea_psi9000, 67

hvl_ccb.dev.ea_psi9000.ea_psi9000, 62
 hvl_ccb.dev.fluke884x, 76
 hvl_ccb.dev.fluke884x.base, 67
 hvl_ccb.dev.fluke884x.constants, 72
 hvl_ccb.dev.fluke884x.ranges, 73
 hvl_ccb.dev.fug, 89
 hvl_ccb.dev.fug.fug, 76
 hvl_ccb.dev.heinzinger, 97
 hvl_ccb.dev.heinzinger.base, 90
 hvl_ccb.dev.heinzinger.constants, 92
 hvl_ccb.dev.heinzinger.device, 93
 hvl_ccb.dev.heinzinger.mixin, 96
 hvl_ccb.dev.highland_t560, 102
 hvl_ccb.dev.highland_t560.base, 97
 hvl_ccb.dev.highland_t560.channel, 100
 hvl_ccb.dev.highland_t560.device, 100
 hvl_ccb.dev.labjack, 110
 hvl_ccb.dev.labjack.labjack, 103
 hvl_ccb.dev.lauda, 118
 hvl_ccb.dev.lauda.lauda, 111
 hvl_ccb.dev.mbw973, 122
 hvl_ccb.dev.mbw973.mbw973, 118
 hvl_ccb.dev.newport, 137
 hvl_ccb.dev.newport.newport, 123
 hvl_ccb.dev.pfeiffer_tpg, 144
 hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg, 138
 hvl_ccb.dev.protocols, 146
 hvl_ccb.dev.protocols.sources, 145
 hvl_ccb.dev.rs_rto1024, 154
 hvl_ccb.dev.rs_rto1024.rs_rto1024, 146
 hvl_ccb.dev.se_ils2t, 162
 hvl_ccb.dev.se_ils2t.se_ils2t, 155
 hvl_ccb.dev.sst_luminox, 167
 hvl_ccb.dev.sst_luminox.sst_luminox, 163
 hvl_ccb.dev.technix, 174
 hvl_ccb.dev.technix.base, 168
 hvl_ccb.dev.technix.device, 171
 hvl_ccb.dev.tiepie, 185
 hvl_ccb.dev.tiepie.base, 174
 hvl_ccb.dev.tiepie.channel, 176
 hvl_ccb.dev.tiepie.device, 179
 hvl_ccb.dev.tiepie.generator, 180
 hvl_ccb.dev.tiepie.oscilloscope, 182
 hvl_ccb.dev.tiepie.utils, 185
 hvl_ccb.dev.utils, 190
 hvl_ccb.dev.visa, 190
 hvl_ccb.error, 202
 hvl_ccb.experiment_manager, 202
 hvl_ccb.utils, 200
 hvl_ccb.utils.conversion, 196
 hvl_ccb.utils.conversion.map_range, 192
 hvl_ccb.utils.conversion.sensor, 193
 hvl_ccb.utils.conversion.unit, 194

hvl_ccb.utils.conversion.utils, 195
 hvl_ccb.utils.enum, 196
 hvl_ccb.utils.poller, 198
 hvl_ccb.utils.typing, 199
 hvl_ccb.utils.validation, 199
 MONITOR_I (*FuGProbusVRegisterGroups* attribute), 85
 MONITOR_V (*FuGProbusVRegisterGroups* attribute), 85
 most_recent_error (*FuGProbusVConfigRegisters* property), 83
 motion_distance_per_full_step (*NewportSMC100PPConfig* attribute), 132
 motor_config (*NewportSMC100PPConfig* property), 132
 move_to_absolute_position() (*NewportSMC100PP* method), 128
 move_to_relative_position() (*NewportSMC100PP* method), 129
 move_wait_sec (*NewportSMC100PPConfig* attribute), 132
 MOVING (*NewportSMC100PP.StateMessages* attribute), 125
 MOVING (*NewportStates* attribute), 137
 MS_NOMINAL_CURRENT (*PSI9000* attribute), 62
 MS_NOMINAL_VOLTAGE (*PSI9000* attribute), 62
 MULTI_COMMANDS_MAX (*VisaCommunication* attribute), 32
 MULTI_COMMANDS_SEPARATOR (*VisaCommunication* attribute), 32

N

n_channels (*TiePieOscilloscope* property), 183
 n_max_try_get_device (*TiePieDeviceConfig* attribute), 175
 name (*Fluke8845aConfig* attribute), 70
 NameEnum (class in *hvl_ccb.utils.enum*), 196
 NAMES (*SerialCommunicationParity* attribute), 27
 names() (*RTO1024.TriggerModes* class method), 146
 namespace_index (*BaseCubeConfiguration* attribute), 50
 NATIVEONLY (*TiePieOscilloscopeAutoResolutionModes* attribute), 184
 NED_END_OF_TURN (*NewportSMC100PP.MotorErrors* attribute), 124
 NEG (*ILS2T.Ref16Jog* attribute), 156
 NEG_FAST (*ILS2T.Ref16Jog* attribute), 156
 NEGATIVE (*FuGPolarities* attribute), 81
 NEGATIVE (*Polarity* attribute), 54
 negative_software_limit (*NewportSMC100PPConfig* attribute), 132
 NewportConfigCommands (class in *hvl_ccb.dev.newport.newport*), 123
 NewportControllerError, 123
 NewportError, 124
 NewportMotorError, 124

NewportMotorPowerSupplyWasCutError, 124
 NewportSerialCommunicationError, 137
 NewportSMC100PP (class in *hvl_ccb.dev.newport.newport*), 124
 NewportSMC100PP.MotorErrors (class in *hvl_ccb.dev.newport.newport*), 124
 NewportSMC100PP.StateMessages (class in *hvl_ccb.dev.newport.newport*), 124
 NewportSMC100PPConfig (class in *hvl_ccb.dev.newport.newport*), 131
 NewportSMC100PPConfig.EspStageConfig (class in *hvl_ccb.dev.newport.newport*), 131
 NewportSMC100PPConfig.HomeSearch (class in *hvl_ccb.dev.newport.newport*), 131
 NewportSMC100PPSerialCommunication (class in *hvl_ccb.dev.newport.newport*), 133
 NewportSMC100PPSerialCommunication.ControllerError (class in *hvl_ccb.dev.newport.newport*), 133
 NewportSMC100PPSerialCommunicationConfig (class in *hvl_ccb.dev.newport.newport*), 135
 NewportStates (class in *hvl_ccb.dev.newport.newport*), 137
 NewportUncertainPositionError, 137
 NO (*FuGDigitalVal* attribute), 79
 NO_ERROR (*NewportSMC100PPSerialCommunication.ControllerError* attribute), 134
 NO_REF (*NewportStates* attribute), 137
 NO_REF_ESP_STAGE_ERROR (NewportSMC100PP.StateMessages attribute), 125
 NO_REF_FROM_CONFIG (NewportSMC100PP.StateMessages attribute), 125
 NO_REF_FROM_DISABLED (NewportSMC100PP.StateMessages attribute), 125
 NO_REF_FROM_HOMING (NewportSMC100PP.StateMessages attribute), 125
 NO_REF_FROM_JOGGING (NewportSMC100PP.StateMessages attribute), 125
 NO_REF_FROM_MOVING (NewportSMC100PP.StateMessages attribute), 125
 NO_REF_FROM_READY (NewportSMC100PP.StateMessages attribute), 125
 NO_REF_FROM_RESET (NewportSMC100PP.StateMessages attribute), 125
 No_sensor (*PfeifferTPG.SensorStatus* attribute), 138
 NO_SOURCE (*PowerSetup* attribute), 55
 NOISE (*TiePieGeneratorSignalType* attribute), 181
 noise_level_measurement_channel_1 (*BaseCube-Configuration* attribute), 51
 noise_level_measurement_channel_2 (*BaseCube-Configuration* attribute), 51
 noise_level_measurement_channel_3 (*BaseCube-Configuration* attribute), 51
 noise_level_measurement_channel_4 (*BaseCube-Configuration* attribute), 51
 NONE (*ILS2T.Ref16Jog* attribute), 156
 NONE (*LabJack.ThermocoupleType* attribute), 106
 None (*PfeifferTPG.SensorTypes* attribute), 139
 NONE (*SerialCommunicationParity* attribute), 27
 NORMAL (*RTO1024.TriggerModes* attribute), 146
 noSen (*PfeifferTPG.SensorTypes* attribute), 139
 noSENSOR (*PfeifferTPG.SensorTypes* attribute), 139
 nr_trials_activate (*LuminosConfig* attribute), 164
 NullCommunicationProtocol (class in *hvl_ccb.comm.base*), 14
 Number (in module *hvl_ccb.utils.typing*), 199
 number_of_decimals (*HeinzingerConfig* attribute), 96
 number_of_recordings (*Heinzinger* property), 94
 number_of_sensors (*PfeifferTPG* property), 140
 O
 OFF (*SerialCommunicationParity* attribute), 27
 OFF (*AutoInstallMode* attribute), 97
 OFF (*FuGDigitalVal* attribute), 79
 OFF (*GateMode* attribute), 98
 OFF (*TriggerMode* attribute), 100
 offset (*TiePieGeneratorConfig* property), 180
 OH (*NewportConfigCommands* attribute), 123
 Ok (*PfeifferTPG.SensorStatus* attribute), 138
 on (*FuG* property), 77
 ON (*FuGDigitalVal* attribute), 79
 on (*FuGProbusVDIRegisters* property), 84
 ON (*ILS2T.State* attribute), 156
 ONE (*LabJack.AInRange* attribute), 104
 ONE (*RecordingsEnum* attribute), 93
 ONE (*SerialCommunicationStopbits* attribute), 27
 ONE_AMPERE (*ACCurrentRange* attribute), 73
 ONE_AMPERE (*DCCurrentRange* attribute), 74
 ONE_HUNDRED_MICRO_AMPERE (*DCCurrentRange* attribute), 74
 ONE_HUNDRED_MILLI_AMPERE (*ACCurrentRange* attribute), 73
 ONE_HUNDRED_MILLI_AMPERE (*DCCurrentRange* attribute), 74
 ONE_HUNDRED_MILLI_SECOND (*ApertureRange* attribute), 74
 ONE_HUNDRED_MILLI_VOLT (*ACVoltageRange* attribute), 74
 ONE_HUNDRED_MILLI_VOLT (*DCVoltageRange* attribute), 75

- ONE_HUNDRED_MILLION_OHM (*ResistanceRange* attribute), 75
- ONE_HUNDRED_OHM (*ResistanceRange* attribute), 75
- ONE_HUNDRED_THOUSAND_OHM (*ResistanceRange* attribute), 75
- ONE_HUNDREDTH (*LabJack.AInRange* attribute), 104
- ONE_MILLI_AMPERE (*DCCurrentRange* attribute), 74
- ONE_MILLION_OHM (*ResistanceRange* attribute), 75
- ONE_POINT_FIVE (*SerialCommunicationStopbits* attribute), 27
- ONE_SECOND (*ApertureRange* attribute), 74
- ONE_TENTH (*LabJack.AInRange* attribute), 104
- ONE_THOUSAND_OHM (*ResistanceRange* attribute), 75
- ONE_THOUSAND_VOLT (*DCVoltageRange* attribute), 75
- ONE_VOLT (*ACVoltageRange* attribute), 74
- ONE_VOLT (*DCVoltageRange* attribute), 75
- ONLYUPWARDSOFFTOZERO (*FuGRampModes* attribute), 86
- OPC_MAX_YEAR (*BaseCube* attribute), 47
- OPC_MIN_YEAR (*BaseCube* attribute), 47
- OpcUaCommunication (class in *hvl_ccb.comm.opc*), 21
- OpcUaCommunicationConfig (class in *hvl_ccb.comm.opc*), 22
- OpcUaCommunicationIOError, 24
- OpcUaCommunicationTimeoutError, 24
- OpcUaSubHandler (class in *hvl_ccb.comm.opc*), 24
- OPEN (*DoorStatus* attribute), 53
- OPEN (*SwitchOperation* attribute), 61
- OPEN (*SwitchStatus* attribute), 61
- open() (*CommunicationProtocol* method), 14
- open() (*LaudaProRp245eTcpCommunication* method), 117
- open() (*LJMCommunication* method), 16
- open() (*ModbusTcpCommunication* method), 19
- open() (*NullCommunicationProtocol* method), 15
- open() (*OpcUaCommunication* method), 22
- open() (*SerialCommunication* method), 25
- open() (*Tcp* method), 28
- open() (*TelnetCommunication* method), 30
- open() (*VisaCommunication* method), 33
- open_interlock (*Technix* property), 172
- open_shutter() (*CryLasLaser* method), 41
- open_timeout (*VisaCommunicationConfig* attribute), 34
- OPENED (*CryLasLaser.AnswersShutter* attribute), 39
- OPENED (*CryLasLaserShutterStatus* attribute), 46
- operate (*BaseCube* property), 48
- operate (*PICube* property), 57
- OPERATION_MODE (*LaudaProRp245eCommand* attribute), 114
- operation_mode (*LaudaProRp245eConfig* attribute), 116
- optional_defaults() (*AsyncCommunicationProtocolConfig* class method), 14
- optional_defaults() (*BaseCubeConfiguration* class method), 51
- optional_defaults() (*BaseCubeOpcUaCommunicationConfig* class method), 52
- optional_defaults() (*CryLasAttenuatorConfig* class method), 37
- optional_defaults() (*CryLasAttenuatorSerialCommunicationConfig* class method), 38
- optional_defaults() (*CryLasLaserConfig* class method), 43
- optional_defaults() (*CryLasLaserSerialCommunicationConfig* class method), 45
- optional_defaults() (*EmptyConfig* class method), 189, 201
- optional_defaults() (*Fluke8845aConfig* class method), 70
- optional_defaults() (*Fluke8845aTelnetCommunicationConfig* class method), 71
- optional_defaults() (*FuGConfig* class method), 78
- optional_defaults() (*FuGSerialCommunicationConfig* class method), 88
- optional_defaults() (*HeinzingerConfig* class method), 96
- optional_defaults() (*HeinzingerSerialCommunicationConfig* class method), 91
- optional_defaults() (*ILS2TConfig* class method), 159
- optional_defaults() (*ILS2TModbusTcpCommunicationConfig* class method), 161
- optional_defaults() (*LaudaProRp245eConfig* class method), 116
- optional_defaults() (*LaudaProRp245eTcpCommunicationConfig* class method), 117
- optional_defaults() (*LJMCommunicationConfig* class method), 18
- optional_defaults() (*LuminoxConfig* class method), 164
- optional_defaults() (*LuminoxSerialCommunicationConfig* class method), 167
- optional_defaults() (*MBW973Config* class method), 120
- optional_defaults() (*MBW973SerialCommunicationConfig* class method), 122
- optional_defaults() (*ModbusTcpCommunicationConfig* class method), 20
- optional_defaults() (*NewportSMC100PPConfig* class method), 132
- optional_defaults() (*NewportSMC100PPSerialCommunicationConfig* class method), 136

- optional_defaults() (*OpcUaCommunicationConfig* class method), 23
- optional_defaults() (*PfeifferTPGConfig* class method), 141
- optional_defaults() (*PfeifferTPGSerialCommunicationConfig* class method), 143
- optional_defaults() (*PICubeConfiguration* class method), 58
- optional_defaults() (*PICubeOpcUaCommunicationConfig* class method), 59
- optional_defaults() (*PSI9000Config* class method), 65
- optional_defaults() (*PSI9000VisaCommunicationConfig* class method), 66
- optional_defaults() (*RTO1024Config* class method), 153
- optional_defaults() (*RTO1024VisaCommunicationConfig* class method), 154
- optional_defaults() (*SerialCommunicationConfig* class method), 26
- optional_defaults() (*T560CommunicationConfig* class method), 99
- optional_defaults() (*T560Config* class method), 102
- optional_defaults() (*TcpCommunicationConfig* class method), 29
- optional_defaults() (*TechnixConfig* class method), 173
- optional_defaults() (*TechnixSerialCommunicationConfig* class method), 169
- optional_defaults() (*TechnixTelnetCommunicationConfig* class method), 170
- optional_defaults() (*TelnetCommunicationConfig* class method), 31
- optional_defaults() (*TiePieDeviceConfig* class method), 175
- optional_defaults() (*VisaCommunicationConfig* class method), 34
- optional_defaults() (*VisaDeviceConfig* class method), 192
- OSCILLOSCOPE (*TiePieDeviceType* attribute), 175
- OT (*NewportConfigCommands* attribute), 123
- out (*FuGProbusVDORegisters* property), 84
- OUTPUT (*FuGProbusIVCommands* attribute), 82
- OUTPUT (*GateMode* attribute), 98
- output (*Heinzinger* property), 95
- output (*Source* property), 145
- output (*Technix* property), 172
- output_off() (*DeprecatedHeinzingerMixin* static method), 97
- output_off() (*FuGProbusIV* method), 82
- output_on() (*DeprecatedHeinzingerMixin* static method), 97
- OUTPUT_POWER_EXCEEDED (*NewportSMC100PP.MotorErrors* attribute), 124
- OUTPUTONCMD (*FuGProbusVRegisterGroups* attribute), 85
- OUTPUTX0 (*FuGProbusVRegisterGroups* attribute), 85
- OUTPUTX1 (*FuGProbusVRegisterGroups* attribute), 85
- OUTPUTX2 (*FuGProbusVRegisterGroups* attribute), 85
- OUTPUTXCMD (*FuGProbusVRegisterGroups* attribute), 85
- outX0 (*FuG* property), 77
- outX1 (*FuG* property), 77
- outX2 (*FuG* property), 77
- outXCMD (*FuG* property), 77
- Overrange (*PfeifferTPG.SensorStatus* attribute), 138
- ## P
- PA (*Pressure* attribute), 194
- PARAM_MISSING_OR_INVALID (*NewportSMC100PPSerialCommunication.ControllerErrors* attribute), 134
- parity (*CryLasAttenuatorSerialCommunicationConfig* attribute), 38
- parity (*CryLasLaserSerialCommunicationConfig* attribute), 45
- parity (*FuGSerialCommunicationConfig* attribute), 88
- parity (*HeinzingerSerialCommunicationConfig* attribute), 91
- parity (*LuminoxSerialCommunicationConfig* attribute), 167
- parity (*MBW973SerialCommunicationConfig* attribute), 122
- parity (*NewportSMC100PPSerialCommunicationConfig* attribute), 136
- parity (*PfeifferTPGSerialCommunicationConfig* attribute), 143
- Parity (*SerialCommunicationConfig* attribute), 26
- parity (*SerialCommunicationConfig* attribute), 27
- parse_read_measurement_value() (*LuminoxMeasurementType* method), 165
- partial_pressure_o2 (*LuminoxMeasurementType* attribute), 165
- PASCAL (*Pressure* attribute), 194
- pause() (*LaudaProRp245e* method), 111
- pause_ramp() (*LaudaProRp245e* method), 111
- PBR (*PfeifferTPG.SensorTypes* attribute), 139
- PEAK_CURRENT_LIMIT (*NewportSMC100PP.MotorErrors* attribute), 124
- peak_output_current_limit (*NewportSMC100PPConfig* attribute), 132
- percent_o2 (*LuminoxMeasurementType* attribute), 165
- PERIOD (*MeasurementFunction* attribute), 72
- period (*T560* property), 101
- period_aperture (*Fluke8845a* attribute), 69

PfeifferTPG (class *hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg*), 138
PfeifferTPG.SensorStatus (class *hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg*), 138
PfeifferTPG.SensorTypes (class *hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg*), 138
PfeifferTPGConfig (class *hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg*), 141
PfeifferTPGConfig.Model (class *hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg*), 141
PfeifferTPGError, 142
PfeifferTPGSerialCommunication (class *hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg*), 142
PfeifferTPGSerialCommunicationConfig (class *hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg*), 142
PICube (class in *hvl_ccb.dev.cube.picube*), 57
PICubeConfiguration (class *hvl_ccb.dev.cube.picube*), 58
PICubeOpcUaCommunication (class *hvl_ccb.dev.cube.picube*), 59
PICubeOpcUaCommunicationConfig (class *hvl_ccb.dev.cube.picube*), 59
PICubeTestParameterError, 56
PKR (*PfeifferTPG.SensorTypes* attribute), 139
Polarity (class in *hvl_ccb.dev.cube.constants*), 54
Polarity (class in *hvl_ccb.dev.highland_t560.base*), 98
POLARITY (*FuGProbusIVCommands* attribute), 82
polarity (*PICube* property), 58
Poller (class in *hvl_ccb.utils.poller*), 198
polling (*LuminoxOutputMode* attribute), 166
polling_delay_sec (*BaseCubeConfiguration* attribute), 51
polling_interval (*MBW973Config* attribute), 120
polling_interval_sec (*BaseCubeConfiguration* attribute), 51
polling_interval_sec (*TechnixConfig* attribute), 173
polling_period (*CryLasLaserConfig* attribute), 43
polling_timeout (*CryLasLaserConfig* attribute), 43
port (*Fluke8845aTelnetCommunicationConfig* attribute), 71
port (*ModbusTcpCommunicationConfig* attribute), 20
port (*OpcUaCommunicationConfig* attribute), 23
port (*SerialCommunicationConfig* attribute), 27
port (*T560CommunicationConfig* attribute), 99
port (*TcpCommunicationConfig* attribute), 29
port (*TechnixTelnetCommunicationConfig* attribute), 170
port (*TelnetCommunicationConfig* attribute), 31
port (*VisaCommunicationConfig* attribute), 34
POS (*ILS2T.Ref16Jog* attribute), 156
POS_END_OF_TURN (*NewportSMC100PP.MotorErrors* attribute), 124
POS_FAST (*ILS2T.Ref16Jog* attribute), 156
POSITION (*ILS2TRegAddr* attribute), 161
POSITION_OUT_OF_LIMIT (New-
 portSMC100PPSerialCommunication.ControllerErrors
 attribute), 134
POSITIVE (*FuGPolarities* attribute), 81
POSITIVE (*Polarity* attribute), 54
positive_software_limit (New-
 portSMC100PPConfig attribute), 133
post_force_value() (*NewportSMC100PPConfig*
 method), 133
post_stop_pause_sec (*TechnixConfig* attribute), 173
POUNDS_PER_SQUARE_INCH (*Pressure* attribute), 194
POWER_INVERTER_220V (*PowerSetup* attribute), 55
power_limit (*PSI9000Config* attribute), 65
power_setup (*PICube* property), 58
PowerSetup (class in *hvl_ccb.dev.cube.constants*), 54
pre_sample_ratio (*TiePieOscilloscopeConfig* prop-
 erty), 184
prepare_ultra_segmentation() (*RTO1024* method),
 149
preserve_type() (in module
 hvl_ccb.utils.conversion.utils), 195
Pressure (class in *hvl_ccb.utils.conversion.unit*), 194
probe_offset (*TiePieOscilloscopeChannelConfig* prop-
 erty), 177
PSI (*Pressure* attribute), 195
PSI9000 (class in *hvl_ccb.dev.ea_psi9000.ea_psi9000*),
 62
PSI9000Config (class in
 hvl_ccb.dev.ea_psi9000.ea_psi9000), 64
PSI9000Error, 65
PSI9000VisaCommunication (class in
 hvl_ccb.dev.ea_psi9000.ea_psi9000), 66
PSI9000VisaCommunicationConfig (class in
 hvl_ccb.dev.ea_psi9000.ea_psi9000), 66
PT100 (*LabJack.ThermocoupleType* attribute), 106
PT1000 (*LabJack.ThermocoupleType* attribute), 106
PT500 (*LabJack.ThermocoupleType* attribute), 106
PTP (*ILS2T.Mode* attribute), 155
PublicPropertiesReprMixin (class in
 hvl_ccb.dev.tiepie.utils), 185
PULSE (*TiePieGeneratorSignalType* attribute), 181
pump_init (*LaudaProRp245eConfig* attribute), 116
PUMP_LEVEL (*LaudaProRp245eCommand* attribute), 114

Q

QIL (*NewportConfigCommands* attribute), 123
QUERY (*FuGProbusIVCommands* attribute), 82
query() (*CryLasLaserSerialCommunication* method),
 44
query() (*Fluke8845aTelnetCommunication* method), 70
query() (*FuGSerialCommunication* method), 87
query() (*NewportSMC100PPSerialCommunication*
 method), 134
query() (*PfeifferTPGSerialCommunication* method),
 142

- query() (*SyncCommunicationProtocol* method), 15
 query() (*T560Communication* method), 98
 query() (*VisaCommunication* method), 33
 query_all() (*CryLasLaserSerialCommunication* method), 44
 query_command() (*LaudaProRp245eTcpCommunication* method), 117
 query_multiple() (*NewportSMC100PPSerialCommunication* method), 134
 query_polling() (*Luminex* method), 163
 query_status() (*Technix* method), 172
 QUEUE (*AutoInstallMode* attribute), 98
 QUICK_STOP (*SafetyStatus* attribute), 55
 QUICKSTOP (*ILS2T.State* attribute), 156
 quickstop() (*ILS2T* method), 158
 quit_error() (*BaseCube* method), 49
- ## R
- R (*LabJack.ThermocoupleType* attribute), 106
 raise_() (*FuGErrorcodes* method), 80
 RAMP_ACC (*ILS2TRegAddr* attribute), 161
 RAMP_CONTINUE (*LaudaProRp245eCommand* attribute), 114
 RAMP_DECEL (*ILS2TRegAddr* attribute), 161
 RAMP_DELETE (*LaudaProRp245eCommand* attribute), 114
 RAMP_ITERATIONS (*LaudaProRp245eCommand* attribute), 114
 RAMP_N_MAX (*ILS2TRegAddr* attribute), 161
 RAMP_PAUSE (*LaudaProRp245eCommand* attribute), 114
 RAMP_SELECT (*LaudaProRp245eCommand* attribute), 114
 RAMP_SET (*LaudaProRp245eCommand* attribute), 114
 RAMP_START (*LaudaProRp245eCommand* attribute), 114
 RAMP_STOP (*LaudaProRp245eCommand* attribute), 114
 RAMP_TYPE (*ILS2TRegAddr* attribute), 161
 rampmode (*FuGProbusVSetRegisters* property), 86
 ramprate (*FuGProbusVSetRegisters* property), 86
 rampstate (*FuGProbusVSetRegisters* property), 86
 RAMPUPWARDS (*FuGRampModes* attribute), 86
 RangeEnum (*class in hvl_ccb.utils.enum*), 197
 RATEDCURRENT (*FuGReadbackChannels* attribute), 87
 RATEDVOLTAGE (*FuGReadbackChannels* attribute), 87
 read() (*AsyncCommunicationProtocol* method), 11
 read() (*BaseCube* method), 49
 read() (*CryLasLaserSerialCommunication* method), 44
 read() (*LaudaProRp245eTcpCommunication* method), 117
 read() (*MBW973* method), 119
 read() (*OpCuaCommunication* method), 22
 read() (*Tcp* method), 28
 read_all() (*AsyncCommunicationProtocol* method), 12
 read_bytes() (*AsyncCommunicationProtocol* method), 12
 read_bytes() (*SerialCommunication* method), 25
 read_bytes() (*TelnetCommunication* method), 30
 read_float() (*MBW973* method), 119
 read_holding_registers() (*ModbusTcpCommunication* method), 19
 read_input_registers() (*ModbusTcpCommunication* method), 19
 read_int() (*MBW973* method), 119
 read_measurement() (*RTO1024* method), 149
 read_measurements() (*MBW973* method), 119
 read_name() (*LJMCommunication* method), 16
 read_nonempty() (*AsyncCommunicationProtocol* method), 12
 read_output_while_polling (*TechnixConfig* attribute), 173
 read_resistance() (*LabJack* method), 108
 read_single_bytes() (*SerialCommunication* method), 25
 read_streaming() (*Luminex* method), 164
 read_termination (*VisaCommunicationConfig* attribute), 35
 read_text() (*AsyncCommunicationProtocol* method), 12
 read_text() (*NewportSMC100PPSerialCommunication* method), 135
 read_text_nonempty() (*AsyncCommunicationProtocol* method), 12
 READ_TEXT_SKIP_PREFIXES (*CryLasLaserSerialCommunication* attribute), 44
 read_thermocouple() (*LabJack* method), 108
 readback_data (*FuGProbusVConfigRegisters* property), 83
 READBACKCHANNEL (*FuGProbusIVCommands* attribute), 82
 ready (*BaseCube* property), 49
 READY (*CryLasLaser.AnswersStatus* attribute), 39
 READY (*ILS2T.State* attribute), 156
 READY (*NewportStates* attribute), 137
 READY_ACTIVE (*CryLasLaser.LaserStatus* attribute), 39
 READY_FROM_DISABLE (*NewportSMC100PP.StateMessages* attribute), 125
 READY_FROM_HOMING (*NewportSMC100PP.StateMessages* attribute), 125
 READY_FROM_JOGGING (*NewportSMC100PP.StateMessages* attribute), 125
 READY_FROM_MOVING (*NewportSMC100PP.StateMessages* attribute), 125
 READY_INACTIVE (*CryLasLaser.LaserStatus* attribute),

39
 record_length (*TiePieOscilloscopeConfig* property), 184
 RecordingsEnum (class in *hvl_ccb.dev.heinzinger.constants*), 92
 RED_OPERATE (*SafetyStatus* attribute), 55
 RED_READY (*SafetyStatus* attribute), 55
 reg_3 (*FuGProbusVDIRegisters* property), 84
 RegAddr (*ILS2T* attribute), 156
 RegDatatype (*ILS2T* attribute), 156
 register_pulse_time (*TechnixConfig* attribute), 173
 RELATIVE (*TiePieOscilloscopeTriggerLevelMode* attribute), 178
 RELATIVE_POSITION_MOTOR (*ILS2T.ActionsPtp* attribute), 155
 RELATIVE_POSITION_TARGET (*ILS2T.ActionsPtp* attribute), 155
 remote (*Technix* property), 172
 remove_device() (*DeviceSequenceMixin* method), 188
 require_block_measurement_support (*TiePieDeviceConfig* attribute), 175
 required_keys() (*AsyncCommunicationProtocolConfig* class method), 14
 required_keys() (*BaseCubeConfiguration* class method), 51
 required_keys() (*BaseCubeOpcUaCommunicationConfig* class method), 52
 required_keys() (*CryLasAttenuatorConfig* class method), 37
 required_keys() (*CryLasAttenuatorSerialCommunicationConfig* class method), 38
 required_keys() (*CryLasLaserConfig* class method), 43
 required_keys() (*CryLasLaserSerialCommunicationConfig* class method), 45
 required_keys() (*EmptyConfig* class method), 189, 201
 required_keys() (*Fluke8845aConfig* class method), 70
 required_keys() (*Fluke8845aTelnetCommunicationConfig* class method), 71
 required_keys() (*FuGConfig* class method), 78
 required_keys() (*FuGSerialCommunicationConfig* class method), 88
 required_keys() (*HeinzingerConfig* class method), 96
 required_keys() (*HeinzingerSerialCommunicationConfig* class method), 91
 required_keys() (*ILS2TConfig* class method), 160
 required_keys() (*ILS2TModbusTcpCommunicationConfig* class method), 161
 required_keys() (*LaudaProRp245eConfig* class method), 116
 required_keys() (*LaudaProRp245eTcpCommunicationConfig* class method), 118
 required_keys() (*LJMCommunicationConfig* class method), 18
 required_keys() (*LuminosConfig* class method), 164
 required_keys() (*LuminosSerialCommunicationConfig* class method), 167
 required_keys() (*MBW973Config* class method), 121
 required_keys() (*MBW973SerialCommunicationConfig* class method), 122
 required_keys() (*ModbusTcpCommunicationConfig* class method), 20
 required_keys() (*NewportSMC100PPConfig* class method), 133
 required_keys() (*NewportSMC100PPSerialCommunicationConfig* class method), 136
 required_keys() (*OpcUaCommunicationConfig* class method), 23
 required_keys() (*PfeifferTPGConfig* class method), 142
 required_keys() (*PfeifferTPGSerialCommunicationConfig* class method), 143
 required_keys() (*PICubeConfiguration* class method), 59
 required_keys() (*PICubeOpcUaCommunicationConfig* class method), 60
 required_keys() (*PSI9000Config* class method), 65
 required_keys() (*PSI9000VisaCommunicationConfig* class method), 66
 required_keys() (*RTO1024Config* class method), 153
 required_keys() (*RTO1024VisaCommunicationConfig* class method), 154
 required_keys() (*SerialCommunicationConfig* class method), 27
 required_keys() (*T560CommunicationConfig* class method), 99
 required_keys() (*T560Config* class method), 102
 required_keys() (*TcpCommunicationConfig* class method), 29
 required_keys() (*TechnixConfig* class method), 173
 required_keys() (*TechnixSerialCommunicationConfig* class method), 169
 required_keys() (*TechnixTelnetCommunicationConfig* class method), 170
 required_keys() (*TelnetCommunicationConfig* class method), 31
 required_keys() (*TiePieDeviceConfig* class method), 175
 required_keys() (*VisaCommunicationConfig* class method), 35
 required_keys() (*VisaDeviceConfig* class method), 192
 RESET (*FuGProbusIVCommands* attribute), 82
 reset() (*Fluke8845a* method), 69
 reset() (*FuGProbusIV* method), 82

- reset() (*NewportSMC100PP method*), 129
 reset() (*VisaDevice method*), 191
 reset_error() (*ILS2T method*), 158
 reset_interface() (*Heinzinger method*), 95
 reset_ramp() (*LaudaProRp245e method*), 112
 ResistanceRange (class in *hvl_ccb.dev.fluke884x.ranges*), 75
 resolution (*TiePieOscilloscopeConfig property*), 184
 response_sleep_time (*CryLasAttenuatorConfig attribute*), 37
 RISING (*TiePieOscilloscopeTriggerKind attribute*), 178
 RMS_CURRENT_LIMIT (*NewportSMC100PP.MotorErrors attribute*), 124
 rpm_max_init (*ILS2TConfig attribute*), 160
 rs485_address (*NewportSMC100PPConfig attribute*), 133
 RTO1024 (class in *hvl_ccb.dev.rs_rto1024.rs_rto1024*), 146
 RTO1024.TriggerModes (class in *hvl_ccb.dev.rs_rto1024.rs_rto1024*), 146
 RTO1024Config (class in *hvl_ccb.dev.rs_rto1024.rs_rto1024*), 153
 RTO1024Error, 153
 RTO1024VisaCommunication (class in *hvl_ccb.dev.rs_rto1024.rs_rto1024*), 153
 RTO1024VisaCommunicationConfig (class in *hvl_ccb.dev.rs_rto1024.rs_rto1024*), 153
 run() (*ExperimentManager method*), 203
 run() (*LaudaProRp245e method*), 112
 run_continuous_acquisition() (*RTO1024 method*), 149
 run_single_acquisition() (*RTO1024 method*), 149
 RUNNING (*ExperimentStatus attribute*), 204
- ## S
- S (*LabJack.ThermocoupleType attribute*), 106
 SA (*NewportConfigCommands attribute*), 123
 SafeGround (class in *hvl_ccb.dev.tiepie.channel*), 176
 SafetyStatus (class in *hvl_ccb.dev.cube.constants*), 55
 sample_frequency (*TiePieOscilloscopeConfig property*), 184
 sample_rate (*TiePieOscilloscopeConfig property*), 184
 save_configuration() (*RTO1024 method*), 149
 save_device_configuration() (*T560 method*), 101
 save_waveform_history() (*RTO1024 method*), 150
 SCALE (*ILS2TRegAddr attribute*), 161
 ScalingFactorValueError, 162
 screw_scaling (*NewportSMC100PPConfig attribute*), 133
 send_command() (*NewportSMC100PPSerialCommunication method*), 135
 send_command() (*PfeifferTPGSerialCommunication method*), 142
 send_hello() (*Client method*), 21
 send_pulses() (*LabJack method*), 108
 send_stop() (*NewportSMC100PPSerialCommunication method*), 135
 Sensor (class in *hvl_ccb.utils.conversion.sensor*), 194
 Sensor_error (*PfeifferTPG.SensorStatus attribute*), 138
 Sensor_off (*PfeifferTPG.SensorStatus attribute*), 138
 sensor_status (*LuminomMeasurementType attribute*), 165
 SERIAL (*LaudaProRp245eConfig.ExtControlModeEnum attribute*), 115
 serial_number (*LuminomMeasurementType attribute*), 165
 serial_number (*TiePieDeviceConfig attribute*), 175
 SerialCommunication (class in *hvl_ccb.comm.serial*), 24
 SerialCommunicationBytesize (class in *hvl_ccb.comm.serial*), 25
 SerialCommunicationConfig (class in *hvl_ccb.comm.serial*), 26
 SerialCommunicationIOError, 27
 SerialCommunicationParity (class in *hvl_ccb.comm.serial*), 27
 SerialCommunicationStopbits (class in *hvl_ccb.comm.serial*), 27
 Server (class in *hvl_ccb.comm.opc*), 24
 set_acceleration() (*NewportSMC100PP method*), 129
 set_acquire_length() (*RTO1024 method*), 150
 set_ain_differential() (*LabJack method*), 108
 set_ain_range() (*LabJack method*), 108
 set_ain_resistance() (*LabJack method*), 109
 set_ain_resolution() (*LabJack method*), 109
 set_ain_thermocouple() (*LabJack method*), 109
 set_analog_output() (*LabJack method*), 109
 set_attenuation() (*CryLasAttenuator method*), 36
 set_channel_offset() (*RTO1024 method*), 150
 set_channel_position() (*RTO1024 method*), 150
 set_channel_range() (*RTO1024 method*), 151
 set_channel_scale() (*RTO1024 method*), 151
 set_channel_state() (*RTO1024 method*), 151
 set_clock() (*LabJack method*), 109
 set_control_mode() (*LaudaProRp245e method*), 112
 set_current (*Heinzinger property*), 95
 set_current (*Source property*), 145
 set_current (*Technix property*), 172
 set_digital_output() (*LabJack method*), 110
 set_external_temp() (*LaudaProRp245e method*), 112
 set_full_scale_mbar() (*PfeifferTPG method*), 140
 set_full_scale_unitless() (*PfeifferTPG method*), 140
 set_init_attenuation() (*CryLasAttenuator method*), 36

set_init_shutter_status() (*CryLasLaser* method), 41
 set_jog_speed() (*ILS2T* method), 158
 set_lower_limits() (*PSI9000* method), 63
 set_max_acceleration() (*ILS2T* method), 158
 set_max_deceleration() (*ILS2T* method), 158
 set_max_rpm() (*ILS2T* method), 158
 set_measuring_options() (*MBW973* method), 119
 set_message_board() (*BaseCube* method), 49
 set_motor_configuration() (*NewportSMC100PP* method), 129
 set_negative_software_limit() (*NewportSMC100PP* method), 130
 set_number_of_recordings() (*Deprecated-HeinzingerMixin* static method), 97
 set_output() (*PSI9000* method), 63
 set_positive_software_limit() (*NewportSMC100PP* method), 130
 set_pulse_energy() (*CryLasLaser* method), 41
 set_pump_level() (*LaudaProRp245e* method), 112
 set_ramp_iterations() (*LaudaProRp245e* method), 112
 set_ramp_program() (*LaudaProRp245e* method), 112
 set_ramp_segment() (*LaudaProRp245e* method), 113
 set_ramp_type() (*ILS2T* method), 158
 set_reference_point() (*RTO1024* method), 151
 set_register() (*FuGProbusV* method), 83
 set_repetition_rate() (*CryLasLaser* method), 41
 set_repetitions() (*RTO1024* method), 152
 set_status_board() (*BaseCube* method), 49
 set_system_lock() (*PSI9000* method), 64
 set_temp_set_point() (*LaudaProRp245e* method), 113
 set_transmission() (*CryLasAttenuator* method), 36
 set_trigger_level() (*RTO1024* method), 152
 set_trigger_mode() (*RTO1024* method), 152
 set_trigger_source() (*RTO1024* method), 152
 set_upper_limits() (*PSI9000* method), 64
 set_voltage (*Heinzinger* property), 95
 set_voltage (*Source* property), 145
 set_voltage (*Technix* property), 172
 set_voltage_current() (*PSI9000* method), 64
 SetAttr (*class in hvl_ccb.utils.conversion.utils*), 195
 SETCURRENT (*FuGProbusVRegisterGroups* attribute), 85
 setvalue (*FuGProbusVSetRegisters* property), 86
 SETVOLTAGE (*FuGProbusVRegisterGroups* attribute), 85
 SEVEN_HUNDRED_FIFTY_VOLT (*ACVoltageRange* attribute), 74
 SEVENBITS (*SerialCommunicationBytesize* attribute), 26
 SHORT_CIRCUIT (*NewportSMC100PP.MotorErrors* attribute), 124
 shunt (*LEM4000S* attribute), 193
 SHUTDOWN_CURRENT_LIMIT (*PSI9000* attribute), 62
 SHUTDOWN_VOLTAGE_LIMIT (*PSI9000* attribute), 62
 ShutterStatus (*CryLasLaser* attribute), 40
 ShutterStatus (*CryLasLaserConfig* attribute), 42
 signal_type (*TiePieGeneratorConfig* property), 180
 SINE (*TiePieGeneratorSignalType* attribute), 181
 SingleCommDevice (*class in hvl_ccb.dev.base*), 189
 SIXBITS (*SerialCommunicationBytesize* attribute), 26
 SIXTEEN (*RecordingsEnum* attribute), 93
 SIXTEEN_BIT (*TiePieOscilloscopeResolution* attribute), 185
 SL (*NewportConfigCommands* attribute), 123
 SLOW_FILTER (*FilterRange* attribute), 75
 SN (*FuGReadbackChannels* attribute), 87
 SOFTWARE_INTERNAL_SIXTY (*CryLasLaser.RepetitionRates* attribute), 40
 SOFTWARE_INTERNAL_TEN (*CryLasLaser.RepetitionRates* attribute), 40
 SOFTWARE_INTERNAL_TWENTY (*CryLasLaser.RepetitionRates* attribute), 40
 software_revision (*LuminexMeasurementType* attribute), 165
 Source (*class in hvl_ccb.dev.protocols.sources*), 145
 SPACE (*SerialCommunicationParity* attribute), 27
 SPECIALRAMPUPWARDS (*FuGRampModes* attribute), 86
 spoll() (*VisaCommunication* method), 33
 spoll_handler() (*VisaDevice* method), 191
 SQUARE (*TiePieGeneratorSignalType* attribute), 181
 SR (*NewportConfigCommands* attribute), 123
 srq_mask (*FuGProbusVConfigRegisters* property), 83
 srq_status (*FuGProbusVConfigRegisters* property), 83
 stage_configuration (*NewportSMC100PPConfig* attribute), 133
 START (*LaudaProRp245eCommand* attribute), 114
 start() (*BaseCube* method), 49
 start() (*CryLasAttenuator* method), 36
 start() (*CryLasLaser* method), 41
 start() (*Device* method), 187
 start() (*DeviceSequenceMixin* method), 188
 start() (*ExperimentManager* method), 203
 start() (*Fluke8845a* method), 69
 start() (*FuG* method), 78
 start() (*FuGProbusIV* method), 82
 start() (*Heinzinger* method), 95
 start() (*ILS2T* method), 158
 start() (*LabJack* method), 110
 start() (*LaudaProRp245e* method), 113
 start() (*Luminex* method), 164
 start() (*MBW973* method), 120
 start() (*NewportSMC100PP* method), 130
 start() (*PfeifferTPG* method), 140
 start() (*PSI9000* method), 64
 start() (*RTO1024* method), 152
 start() (*SingleCommDevice* method), 190
 start() (*Technix* method), 172
 start() (*TiePieGeneratorMixin* method), 181

- [start\(\)](#) (*TiePieOscilloscope* method), 183
[start\(\)](#) (*VisaDevice* method), 191
[start_control\(\)](#) (*MBW973* method), 120
[start_measurement\(\)](#) (*TiePieOscilloscope* method), 183
[start_polling\(\)](#) (*Poller* method), 198
[start_ramp\(\)](#) (*LaudaProRp245e* method), 113
[STARTING](#) (*ExperimentStatus* attribute), 204
[States](#) (*NewportSMC100PP* attribute), 125
[status](#) (*BaseCube* property), 49
[status](#) (*ExperimentManager* property), 203
[status](#) (*FuGProbusVConfigRegisters* property), 83
[status](#) (*FuGProbusVDOResisters* property), 85
[status](#) (*Technix* property), 172
[STATUSBYTE](#) (*FuGReadbackChannels* attribute), 87
[STOP](#) (*LaudaProRp245eCommand* attribute), 114
[stop\(\)](#) (*BaseCube* method), 50
[stop\(\)](#) (*CryLasLaser* method), 41
[stop\(\)](#) (*Device* method), 187
[stop\(\)](#) (*DeviceSequenceMixin* method), 188
[stop\(\)](#) (*ExperimentManager* method), 203
[stop\(\)](#) (*Fluke8845a* method), 69
[stop\(\)](#) (*FuGProbusIV* method), 82
[stop\(\)](#) (*Heinzinger* method), 95
[stop\(\)](#) (*ILS2T* method), 158
[stop\(\)](#) (*LabJack* method), 110
[stop\(\)](#) (*LaudaProRp245e* method), 113
[stop\(\)](#) (*Luminox* method), 164
[stop\(\)](#) (*MBW973* method), 120
[stop\(\)](#) (*NewportSMC100PP* method), 130
[stop\(\)](#) (*PfeifferTPG* method), 141
[stop\(\)](#) (*PSI9000* method), 64
[stop\(\)](#) (*RTO1024* method), 152
[stop\(\)](#) (*SingleCommDevice* method), 190
[stop\(\)](#) (*Technix* method), 172
[stop\(\)](#) (*TiePieGeneratorMixin* method), 181
[stop\(\)](#) (*TiePieOscilloscope* method), 184
[stop\(\)](#) (*VisaDevice* method), 191
[stop_acquisition\(\)](#) (*RTO1024* method), 153
[stop_measurement\(\)](#) (*TiePieOscilloscope* method), 184
[stop_motion\(\)](#) (*NewportSMC100PP* method), 130
[stop_polling\(\)](#) (*Poller* method), 198
[stop_ramp\(\)](#) (*LaudaProRp245e* method), 113
[STOP_SAFETY_STATUSES](#) (in module *hvl_ccb.dev.cube.constants*), 55
[stopbits](#) (*CryLasAttenuatorSerialCommunicationConfig* attribute), 38
[stopbits](#) (*CryLasLaserSerialCommunicationConfig* attribute), 45
[stopbits](#) (*FuGSerialCommunicationConfig* attribute), 88
[stopbits](#) (*HeinzingerSerialCommunicationConfig* attribute), 91
[stopbits](#) (*LuminoxSerialCommunicationConfig* attribute), 167
[stopbits](#) (*MBW973SerialCommunicationConfig* attribute), 122
[stopbits](#) (*NewportSMC100PPSerialCommunicationConfig* attribute), 137
[stopbits](#) (*PfeifferTPGSerialCommunicationConfig* attribute), 143
[Stopbits](#) (*SerialCommunicationConfig* attribute), 26
[stopbits](#) (*SerialCommunicationConfig* attribute), 27
[streaming](#) (*LuminoxOutputMode* attribute), 166
[StrEnumBase](#) (class in *hvl_ccb.utils.enum*), 197
[sub_handler](#) (*BaseCubeOpcUaCommunicationConfig* attribute), 52
[sub_handler](#) (*OpcUaCommunicationConfig* attribute), 23
[SwitchOperatingStatus](#) (class in *hvl_ccb.dev.cube.switches*), 60
[SwitchOperation](#) (class in *hvl_ccb.dev.cube.switches*), 61
[SwitchOperationError](#), 56
[SwitchStatus](#) (class in *hvl_ccb.dev.cube.switches*), 61
[SyncCommunicationProtocol](#) (class in *hvl_ccb.comm.base*), 15
[SyncCommunicationProtocolConfig](#) (class in *hvl_ccb.comm.base*), 15
- ## T
- [T](#) (*LabJack.ThermocoupleType* attribute), 106
[t13_socket_1](#) (*BaseCube* attribute), 50
[t13_socket_2](#) (*BaseCube* attribute), 50
[t13_socket_3](#) (*BaseCube* attribute), 50
[T1MS](#) (*FuGMonitorModes* attribute), 80
[T200MS](#) (*FuGMonitorModes* attribute), 81
[T20MS](#) (*FuGMonitorModes* attribute), 81
[T256US](#) (*FuGMonitorModes* attribute), 81
[T4](#) (*LabJack.DeviceType* attribute), 105
[T4](#) (*LJMCommunicationConfig.DeviceType* attribute), 17
[T40MS](#) (*FuGMonitorModes* attribute), 81
[T4MS](#) (*FuGMonitorModes* attribute), 81
[T560](#) (class in *hvl_ccb.dev.highland_t560.device*), 100
[T560Communication](#) (class in *hvl_ccb.dev.highland_t560.base*), 98
[T560CommunicationConfig](#) (class in *hvl_ccb.dev.highland_t560.base*), 98
[T560Config](#) (class in *hvl_ccb.dev.highland_t560.device*), 101
[T560Error](#), 99
[T7](#) (*LabJack.DeviceType* attribute), 105
[T7](#) (*LJMCommunicationConfig.DeviceType* attribute), 17
[T7_PRO](#) (*LabJack.DeviceType* attribute), 105
[T7_PRO](#) (*LJMCommunicationConfig.DeviceType* attribute), 17
[T800MS](#) (*FuGMonitorModes* attribute), 81

- T80MS (*FuGMonitorModes* attribute), 81
- target_pulse_energy (*CryLasLaser* property), 41
- Tcp (class in *hvl_ccb.comm.tcp*), 28
- TCP (*LJMCommunicationConfig.ConnectionType* attribute), 17
- TcpCommunicationConfig (class in *hvl_ccb.comm.tcp*), 28
- TCPIP_INSTR (*VisaCommunicationConfig.InterfaceType* attribute), 33
- TCPIP_SOCKET (*VisaCommunicationConfig.InterfaceType* attribute), 33
- TEC1 (*CryLasLaser.AnswersStatus* attribute), 39
- TEC2 (*CryLasLaser.AnswersStatus* attribute), 39
- Technix (class in *hvl_ccb.dev.technix.device*), 171
- TechnixConfig (class in *hvl_ccb.dev.technix.device*), 172
- TechnixError, 168
- TechnixFaultError, 168
- TechnixSerialCommunication (class in *hvl_ccb.dev.technix.base*), 168
- TechnixSerialCommunicationConfig (class in *hvl_ccb.dev.technix.base*), 168
- TechnixTelnetCommunication (class in *hvl_ccb.dev.technix.base*), 169
- TechnixTelnetCommunicationConfig (class in *hvl_ccb.dev.technix.base*), 169
- TelnetCommunication (class in *hvl_ccb.comm.telnet*), 30
- TelnetCommunicationConfig (class in *hvl_ccb.comm.telnet*), 31
- TelnetError, 32
- TEMP (*ILS2TRegAddr* attribute), 161
- TEMP_SET_POINT (*LaudaProRp245eCommand* attribute), 114
- temp_set_point_init (*LaudaProRp245eConfig* attribute), 116
- Temperature (class in *hvl_ccb.utils.conversion.unit*), 195
- temperature_sensor (*LuminosMeasurementType* attribute), 165
- temperature_unit (*LMT70A* attribute), 194
- TEN (*LabJack.AInRange* attribute), 104
- TEN (*LabJack.CalMicroAmpere* attribute), 104
- TEN_AMPERE (*ACCurentRange* attribute), 73
- TEN_AMPERE (*DCCurentRange* attribute), 74
- TEN_MHZ (*LabJack.ClockFrequency* attribute), 104
- TEN_MILLI_AMPERE (*ACCurentRange* attribute), 73
- TEN_MILLI_AMPERE (*DCCurentRange* attribute), 74
- TEN_MILLI_SECOND (*ApertureRange* attribute), 74
- TEN_MILLION_OHM (*ResistanceRange* attribute), 75
- TEN_THOUSAND_OHM (*ResistanceRange* attribute), 75
- TEN_VOLT (*ACVoltageRange* attribute), 74
- TEN_VOLT (*DCVoltageRange* attribute), 75
- terminator (*AsyncCommunicationProtocolConfig* attribute), 14
- terminator (*CryLasAttenuatorSerialCommunicationConfig* attribute), 39
- terminator (*CryLasLaserSerialCommunicationConfig* attribute), 46
- terminator (*Fluke8845aTelnetCommunicationConfig* attribute), 71
- TERMINATOR (*FuGProbusIVCommands* attribute), 82
- terminator (*FuGProbusVConfigRegisters* property), 83
- terminator (*FuGSerialCommunicationConfig* attribute), 88
- terminator (*HeinzingerSerialCommunicationConfig* attribute), 92
- terminator (*LaudaProRp245eTcpCommunicationConfig* attribute), 118
- terminator (*LuminosSerialCommunicationConfig* attribute), 167
- terminator (*MBW973SerialCommunicationConfig* attribute), 122
- terminator (*NewportSMC100PPSerialCommunicationConfig* attribute), 137
- terminator (*PfeifferTPGSerialCommunicationConfig* attribute), 144
- terminator (*T560CommunicationConfig* attribute), 99
- terminator_str() (*SerialCommunicationConfig* method), 27
- THIRTY_TWO_BIT (*LabJack.BitLimit* attribute), 104
- THREE_AMPERE (*ACCurentRange* attribute), 73
- THREE_AMPERE (*DCCurentRange* attribute), 74
- TiePieDeviceConfig (class in *hvl_ccb.dev.tiepie.base*), 174
- TiePieDeviceType (class in *hvl_ccb.dev.tiepie.base*), 175
- TiePieError, 175
- TiePieGeneratorConfig (class in *hvl_ccb.dev.tiepie.generator*), 180
- TiePieGeneratorConfigLimits (class in *hvl_ccb.dev.tiepie.generator*), 180
- TiePieGeneratorMixin (class in *hvl_ccb.dev.tiepie.generator*), 180
- TiePieGeneratorSignalType (class in *hvl_ccb.dev.tiepie.generator*), 181
- TiePieHS5 (class in *hvl_ccb.dev.tiepie.device*), 179
- TiePieHS6 (class in *hvl_ccb.dev.tiepie.device*), 179
- TiePieOscilloscope (class in *hvl_ccb.dev.tiepie.oscilloscope*), 182
- TiePieOscilloscopeAutoResolutionModes (class in *hvl_ccb.dev.tiepie.oscilloscope*), 184
- TiePieOscilloscopeChannelConfig (class in *hvl_ccb.dev.tiepie.channel*), 176
- TiePieOscilloscopeChannelConfigLimits (class in *hvl_ccb.dev.tiepie.channel*), 177
- TiePieOscilloscopeChannelCoupling (class in

hvl_ccb.dev.tiepie.channel), 177
 TiePieOscilloscopeConfig (class *hvl_ccb.dev.tiepie.oscilloscope*), 184
 TiePieOscilloscopeConfigLimits (class *hvl_ccb.dev.tiepie.oscilloscope*), 185
 TiePieOscilloscopeRange (class *hvl_ccb.dev.tiepie.channel*), 178
 TiePieOscilloscopeResolution (class *hvl_ccb.dev.tiepie.oscilloscope*), 185
 TiePieOscilloscopeTriggerKind (class *hvl_ccb.dev.tiepie.channel*), 178
 TiePieOscilloscopeTriggerLevelMode (class *hvl_ccb.dev.tiepie.channel*), 178
 TiePieWS5 (class in *hvl_ccb.dev.tiepie.device*), 179
 timeout (*CryLasAttenuatorSerialCommunicationConfig* attribute), 39
 timeout (*CryLasLaserSerialCommunicationConfig* attribute), 46
 timeout (*FuGSerialCommunicationConfig* attribute), 88
 timeout (*HeinzingerSerialCommunicationConfig* attribute), 92
 timeout (*LuminosSerialCommunicationConfig* attribute), 167
 timeout (*MBW973SerialCommunicationConfig* attribute), 122
 timeout (*NewportSMC100PPSerialCommunicationConfig* attribute), 137
 timeout (*PfeifferTPGSerialCommunicationConfig* attribute), 144
 timeout (*SerialCommunicationConfig* attribute), 27
 timeout (*TelnetCommunicationConfig* attribute), 31
 timeout (*VisaCommunicationConfig* attribute), 35
 timeout_interval (*BaseCubeConfiguration* attribute), 51
 timeout_status_change (*BaseCubeConfiguration* attribute), 51
 timeout_test_parameters (*PICubeConfiguration* attribute), 59
 TORR (*Pressure* attribute), 195
 TPG25xA (*PfeifferTPGConfig.Model* attribute), 141
 TPGx6x (*PfeifferTPGConfig.Model* attribute), 141
 TPR (*PfeifferTPG.SensorTypes* attribute), 139
 transmission (*CryLasAttenuator* property), 36
 TRIANGLE (*TiePieGeneratorSignalType* attribute), 181
 trigger() (*Fluke8845a* method), 69
 trigger_delay (*Fluke8845a* property), 69
 trigger_enabled (*TiePieOscilloscopeChannelConfig* property), 177
 trigger_hysteresis (*TiePieOscilloscopeChannelConfig* property), 177
 trigger_kind (*TiePieOscilloscopeChannelConfig* property), 177
 trigger_level (*T560* property), 101
 trigger_level (*TiePieOscilloscopeChannelConfig* property), 177
 in trigger_level_mode (*TiePieOscilloscopeChannelConfig* property), 177
 in trigger_mode (*T560* property), 101
 trigger_source (*Fluke8845a* property), 69
 in trigger_timeout (*TiePieOscilloscopeConfig* property), 185
 in TriggerMode (class in *hvl_ccb.dev.highland_t560.base*), 99
 in TriggerSource (class *hvl_ccb.dev.fluke884x.constants*), 72
 TWELVE_BIT (*TiePieOscilloscopeResolution* attribute), 185
 TWELVE_HUNDRED_FIFTY_KHZ (*LabJack.ClockFrequency* attribute), 105
 TWENTY_FIVE_HUNDRED_KHZ (*LabJack.ClockFrequency* attribute), 105
 TWENTY_MHZ (*LabJack.ClockFrequency* attribute), 105
 TWENTY_VOLT (*TiePieOscilloscopeRange* attribute), 178
 TWO (*RecordingsEnum* attribute), 93
 TWO (*SerialCommunicationStopbits* attribute), 28
 TWO_HUNDRED (*LabJack.CalMicroAmpere* attribute), 104
 TWO_HUNDRED_MILLI_VOLT (*TiePieOscilloscopeRange* attribute), 178
 TWO_VOLT (*TiePieOscilloscopeRange* attribute), 178
 TWO_WIRE_RESISTANCE (*MeasurementFunction* attribute), 72
 two_wire_resistance_range (*Fluke8845a* attribute), 69

U

 Underrange (*PfeifferTPG.SensorStatus* attribute), 138
 Unit (class in *hvl_ccb.utils.conversion.unit*), 195
 unit (*ILS2TModbusTcpCommunicationConfig* attribute), 161
 unit (*ModbusTcpCommunicationConfig* attribute), 20
 unit (*PfeifferTPG* property), 141
 unit() (*RangeEnum* class method), 197
 UNKNOWN (*TiePieGeneratorSignalType* attribute), 181
 UNKNOWN (*TiePieOscilloscopeAutoResolutionModes* attribute), 184
 UNKNOWN (*TiePieOscilloscopeTriggerLevelMode* attribute), 178
 UNREADY_INACTIVE (*CryLasLaser.LaserStatus* attribute), 39
 update_laser_status() (*CryLasLaser* method), 42
 update_parameter (*OpcUaCommunicationConfig* attribute), 23
 update_repetition_rate() (*CryLasLaser* method), 42
 update_shutter_status() (*CryLasLaser* method), 42
 update_target_pulse_energy() (*CryLasLaser* method), 42

UpdateEspStageInfo (NewportSMC100PPConfig.EspStageConfig attribute), 131
UPPER_TEMP (LaudaProRp245eCommand attribute), 114
upper_temp (LaudaProRp245eConfig attribute), 116
USB (LaudaProRp245eConfig.ExtControlModeEnum attribute), 115
USB (LJMCommunicationConfig.ConnectionType attribute), 17
use_external_clock() (T560 method), 101
user_position_offset (NewportSMC100PPConfig attribute), 133
user_steps() (ILS2T method), 159

V

VA (NewportConfigCommands attribute), 123
validate_and_resolve_host() (in module hvl_ccb.utils.validation), 199
validate_bool() (in module hvl_ccb.utils.validation), 199
validate_number() (in module hvl_ccb.utils.validation), 199
validate_pump_level() (LaudaProRp245e method), 113
validate_tcp_port() (in module hvl_ccb.utils.validation), 199
value (FuGProbusVMonitorRegisters property), 85
value (LabJack.AlnRange property), 104
value_raw (FuGProbusVMonitorRegisters property), 85
ValueEnum (class in hvl_ccb.utils.enum), 197
VB (NewportConfigCommands attribute), 123
velocity (NewportSMC100PPConfig attribute), 133
visa_backend (VisaCommunicationConfig attribute), 35
VisaCommunication (class in hvl_ccb.comm.visa), 32
VisaCommunicationConfig (class in hvl_ccb.comm.visa), 33
VisaCommunicationConfig.InterfaceType (class in hvl_ccb.comm.visa), 33
VisaCommunicationError, 35
VisaDevice (class in hvl_ccb.dev.visa), 190
VisaDeviceConfig (class in hvl_ccb.dev.visa), 191
VOLT (ILS2TRegAddr attribute), 161
voltage (FuG property), 78
VOLTAGE (FuGProbusIVCommands attribute), 82
VOLTAGE (FuGReadbackChannels attribute), 87
voltage (Heinzinger property), 95
voltage (Source property), 145
voltage (Technix property), 172
VOLTAGE_AC (MeasurementFunction attribute), 72
voltage_actual (PICube property), 58
VOLTAGE_DC (MeasurementFunction attribute), 72
voltage_filter (Fluke8845a attribute), 69
voltage_lower_limit (PSI9000Config attribute), 65
voltage_max (PICube property), 58

voltage_monitor (FuG property), 78
voltage_primary (PICube property), 58
voltage_regulation (Technix property), 172
voltage_upper_limit (PSI9000Config attribute), 65

W

WAIT_AFTER_WRITE (VisaCommunication attribute), 32
wait_for_polling_result() (Poller method), 198
wait_operation_complete() (VisaDevice method), 191
wait_sec_initialisation (PSI9000Config attribute), 65
wait_sec_max_disable (ILS2TConfig attribute), 160
wait_sec_post_absolute_position (ILS2TConfig attribute), 160
wait_sec_post_activate (LuminoxConfig attribute), 165
wait_sec_post_cannot_disable (ILS2TConfig attribute), 160
wait_sec_post_enable (ILS2TConfig attribute), 160
wait_sec_post_relative_step (ILS2TConfig attribute), 160
wait_sec_pre_read_or_write (LaudaProRp245eTcpCommunicationConfig attribute), 118
wait_sec_read_text_nonempty (AsyncCommunicationProtocolConfig attribute), 14
wait_sec_read_text_nonempty (FuGSerialCommunicationConfig attribute), 88
wait_sec_read_text_nonempty (HeinzingerSerialCommunicationConfig attribute), 92
wait_sec_retry_get_device (TiePieDeviceConfig attribute), 175
wait_sec_settings_effect (PSI9000Config attribute), 65
wait_sec_stop_commands (FuGConfig attribute), 78
wait_sec_stop_commands (HeinzingerConfig attribute), 96
wait_sec_system_lock (PSI9000Config attribute), 65
wait_sec_trials_activate (LuminoxConfig attribute), 165
wait_timeout_retry_sec (OpcUaCommunicationConfig attribute), 23
wait_until_motor_initialized() (NewportSMC100PP method), 130
wait_until_ready() (CryLasLaser method), 42
waveform (TiePieGeneratorConfig property), 180
WIFI (LJMCommunicationConfig.ConnectionType attribute), 17
wrap_libtiepie_exception() (in module hvl_ccb.dev.tiepie.base), 176
write() (AsyncCommunicationProtocol method), 13
write() (BaseCube method), 50
write() (MBW973 method), 120

[write\(\) \(OpcUaCommunication method\), 22](#)
[write\(\) \(Tcp method\), 28](#)
[write\(\) \(VisaCommunication method\), 33](#)
[write_absolute_position\(\) \(ILS2T method\), 159](#)
[write_bytes\(\) \(AsyncCommunicationProtocol method\), 13](#)
[write_bytes\(\) \(SerialCommunication method\), 25](#)
[write_bytes\(\) \(TelnetCommunication method\), 30](#)
[write_command\(\) \(Lau-daProRp245eTcpCommunication method\), 117](#)
[write_name\(\) \(LJMCommunication method\), 17](#)
[write_names\(\) \(LJMCommunication method\), 17](#)
[write_registers\(\) \(ModbusTcpCommunication method\), 20](#)
[write_relative_step\(\) \(ILS2T method\), 159](#)
[write_termination \(VisaCommunicationConfig attribute\), 35](#)
[write_text\(\) \(AsyncCommunicationProtocol method\), 13](#)
[WRONG_ESP_STAGE \(NewportSMC100PP.MotorErrors attribute\), 124](#)

X

[x_stat \(FuGProbusVDIRegisters property\), 84](#)
[XOUTPUTS \(FuGProbusIVCommands attribute\), 82](#)

Y

[YES \(FuGDigitalVal attribute\), 79](#)

Z

[ZX \(NewportConfigCommands attribute\), 123](#)