HVL Common Code Base Documentation

Release 0.11.1

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CHAPTER

ONE

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).

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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
I2C host	TiePie (HS5, WS5; requires LibTiePie SDK)
Laser	CryLaS pulsed laser CryLaS laser attenuator
Oscilloscope	Rhode & Schwarz RTO 1024 TiePie (HS5, HS6, WS5; requires LibTiePie SDK)
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	

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	CryLaS pulsed laser and laser attenuator FuG Elektronik power supply (e.g. capacitor charger HCK) using the Probus V protocol Heinzinger PNC power supply using Heinzinger Digital Interface I/II SST Luminox oxygen sensor MBW 973-SF6 gas dew point mirror analyzer Newport SMC100PP single axis driver for 2-phase stepper motors Pfeiffer Vacuum TPG (25x, 26x and 36x) controller for compact pressure gauges Technix capacitor charger
TCP	Lauda PRO RP 245 E circulation thermostat
Telnet	Technix capacitor charger Fluke 8845A and 8846
VISA TCP	Elektro-Automatik PSI9000 DC power supply Rhode & Schwarz RTO 1024 oscilloscope
propriety	LabJack (T4, T7, T7-PRO) devices, which communicate via LJM Library Pico Technology PT-104 Platinum Resistance Data Logger, which communicate via PicoSDK/libusbpt104 TiePie (HS5, HS6, WS5) oscilloscopes, generators and I2C hosts, which communicate via LibTiePie SDK

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 and 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.

CHAPTER

TWO

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[tiepie,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)
`tiepie`	LibTiePie SDK

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
```

CHAPTER

FOUR

API DOCUMENTATION

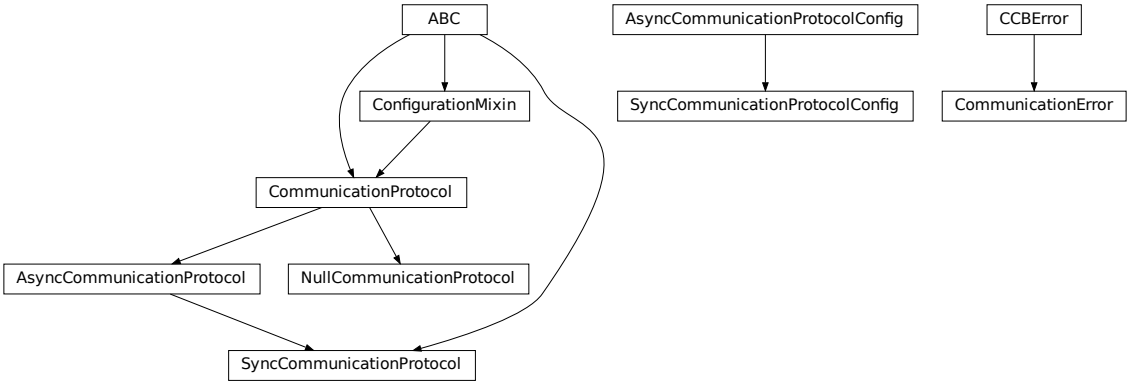
4.1 hvl_ccb

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: Optional[int] = None*, *attempt_interval_sec: Optional[Union[int, float]] = None*) → Optional[str]

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: Optional[int] = None*, *attempt_interval_sec: Optional[Union[int, float]] = None*) → Optional[str]

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: Optional[int] = None*, *attempt_interval_sec: Optional[Union[int, float]] = None*) → Optional[str]

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 – test 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'\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*)

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: Union[int, float] = 0.5

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

exception CommunicationError

Bases: *CCBError*

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*) → Optional[str]

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

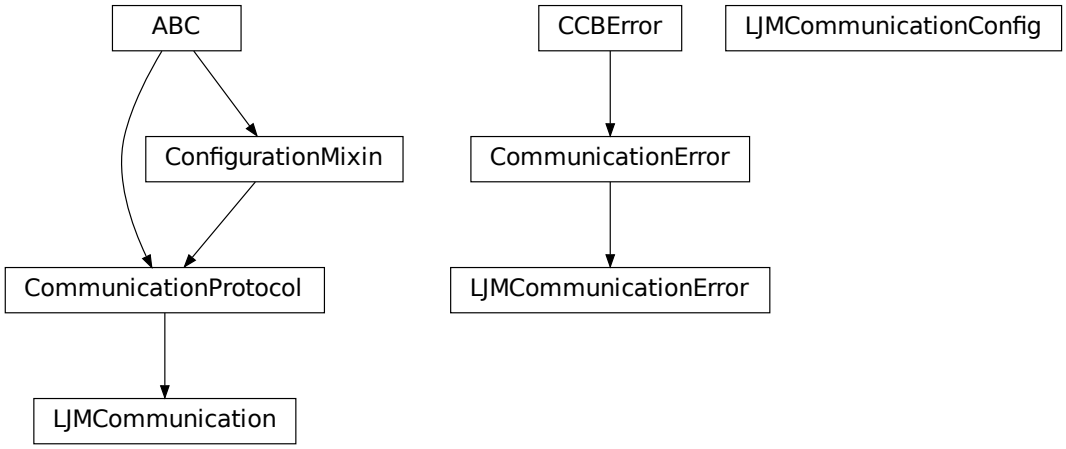
Parameters
command – Command to send

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: Union[int, float] = 0.5*, *default_n_attempts_read_text_nonempty: int = 10*)

Bases: *AsyncCommunicationProtocolConfig*

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: ~typing.Type[~numbers.Real] = <class 'float'>*) → Union[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: Union[str, DeviceType] = 'ANY'*, *connection_type: Union[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 ambigious 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*) → Union[*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: Union[str, *ConnectionType*] = 'ANY'

Can be either string or of enum *ConnectionType*.

device_type: Union[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.

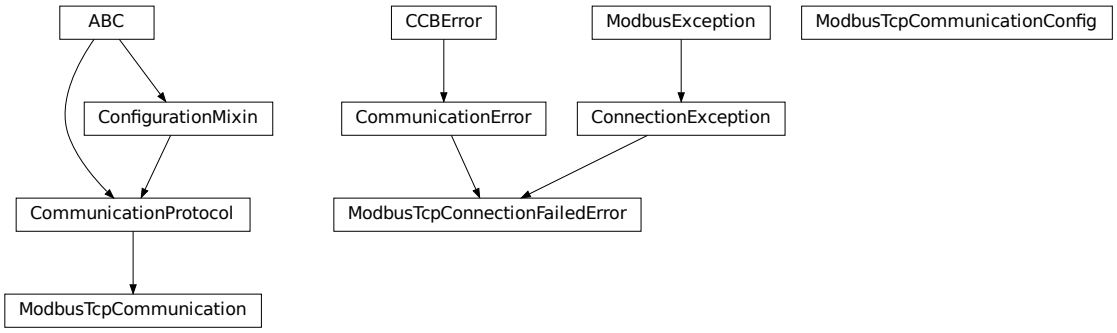
Returns
a list of strings containing all required keys.

exception LJMCommunicationError

Bases: *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

Returns
list 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: Union[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: Union[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: Union[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.

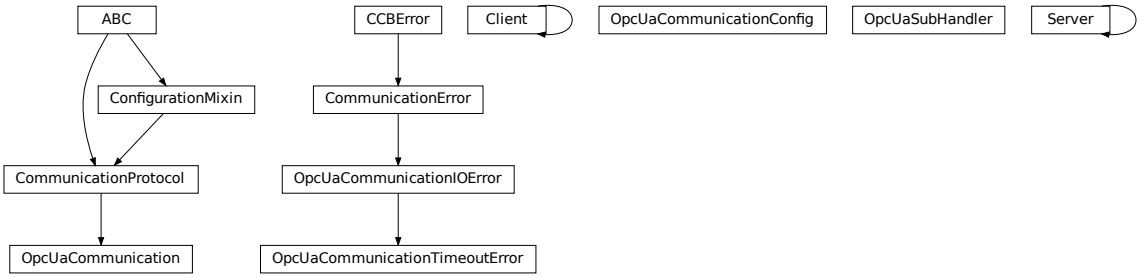
unit: int

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: Union[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: ~typing.Union[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.uaprotocol_auto.CreateSubscriptionParameters = CreateSubscriptionParameters(RequestedPublishingInterval=1000, RequestedLifetimeCount=300, RequestedMaxKeepAliveCount=22, MaxNotificationsPerPublish=10000, PublishingEnabled=True, Priority=0), wait_timeout_retry_sec: ~typing.Union[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: Union[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: Union[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*)

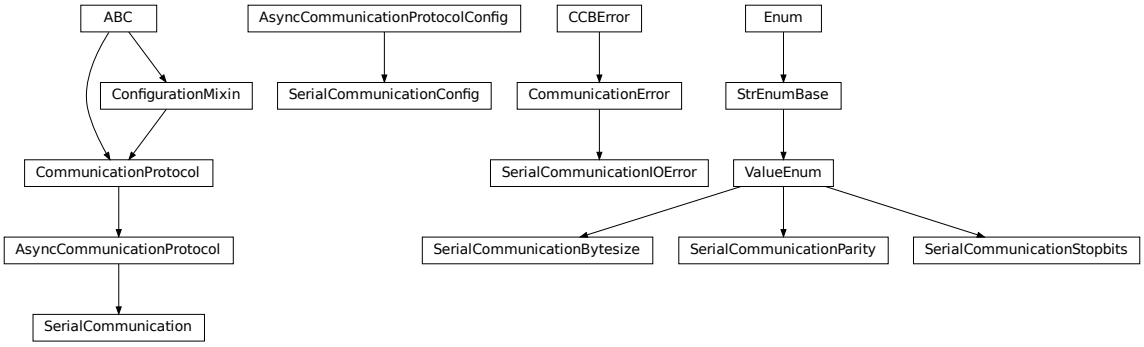
class Server(*shelf_file=None*, *tloop=None*)

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: Union[int, float] = 0.5*, *default_n_attempts_read_text_nonempty: int = 10*, *port: Optional[str] = None*, *baudrate: int = 9600*, *parity: Union[str, SerialCommunicationParity] = SerialCommunicationParity.NONE*, *stopbits: Union[int, float, SerialCommunicationStopbits] = SerialCommunicationStopbits.ONE*, *bytesize: Union[int, SerialCommunicationBytesize] = SerialCommunicationBytesize.EIGHTBITS*, *timeout: Union[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: Union[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: Union[str, *SerialCommunicationParity*] = 'N'

Parity to be used for the connection.

port: Optional[str] = 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: Union[int, float, *SerialCommunicationStopbits*] = 1

Stopbits setting, can be 1, 1.5 or 2.

terminator_str() → str

timeout: Union[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*

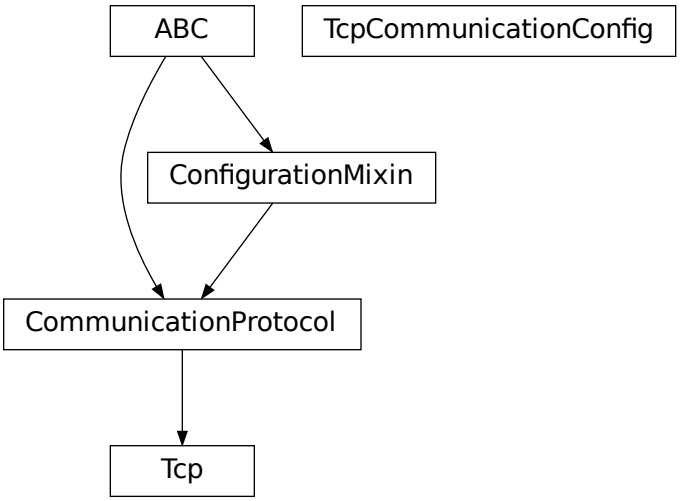
Serial communication stopbits.

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: Union[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: Union[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.

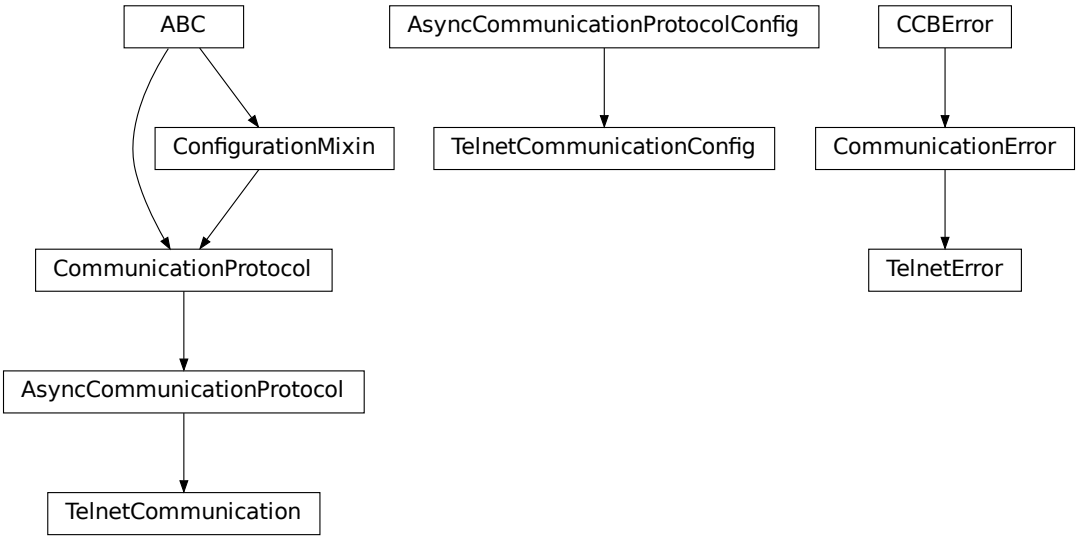
port: int = 54321

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: Union[int, float] = 0.5*, *default_n_attempts_read_text_nonempty: int = 10*, *host: Optional[Union[str, IPv4Address, IPv6Address]] = None*, *port: int = 0*, *timeout: Union[int, float] = 0.2*)

Bases: *AsyncCommunicationProtocolConfig*

Configuration dataclass for *TelnetCommunication*.

clean_values()

create_telnet() → Optional[Telnet]

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: Optional[Union[str, IPv4Address, IPv6Address]] = 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: Union[int, float] = 0.2

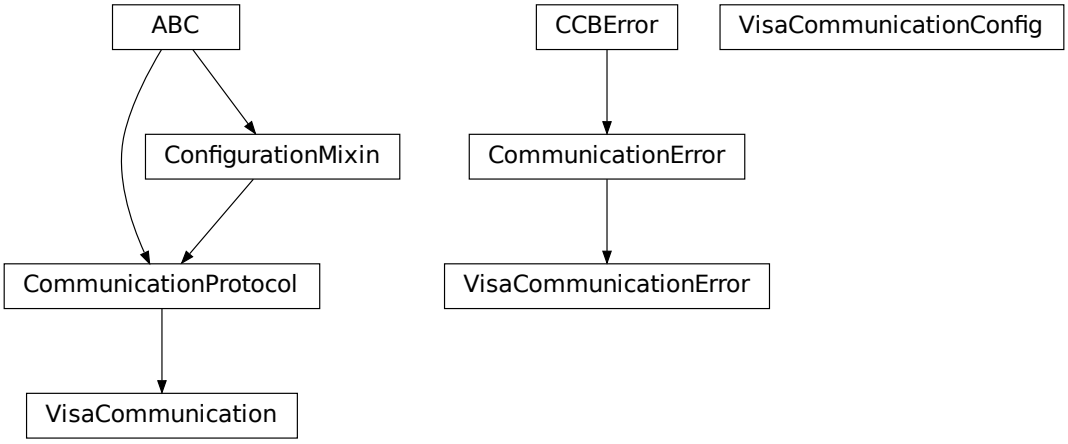
Timeout for reading a line

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*) → Union[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: Union[str, IPv4Address, IPv6Address]*, *interface_type: Union[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: Optional[int] = None*, *board: Optional[int] = 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: Union[str, IPv4Address, IPv6Address]

interface_type: Union[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() → 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.

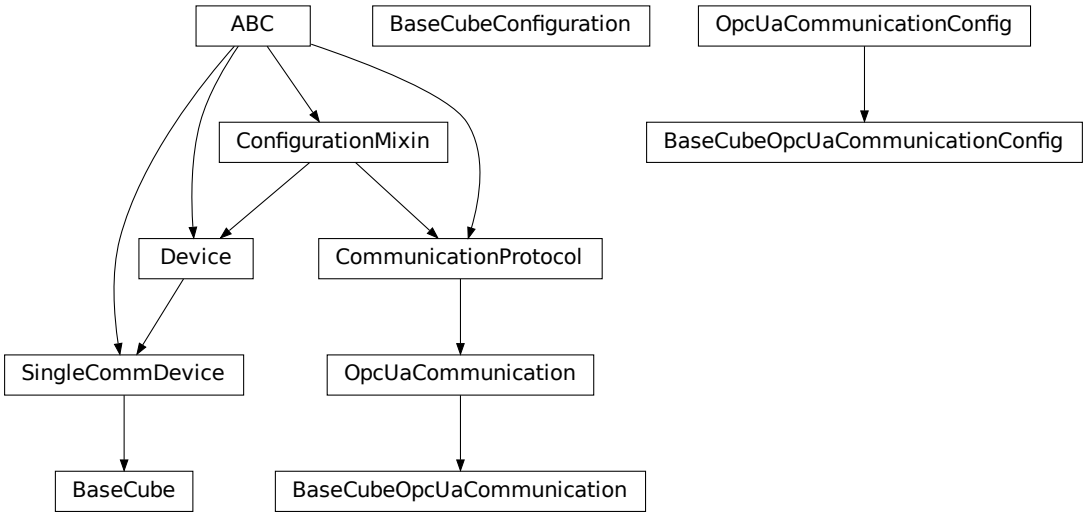
hvl_ccb.dev

Subpackages

hvl_ccb.dev.cube

Submodules

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[Union[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: Optional[bool]

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: Optional[bool]

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: Optional[List[int]] = 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: Union[int, float] = 5.0*, *polling_interval_sec: Union[int, float] = 1.0*, *timeout_status_change: Union[int, float] = 6*, *timeout_interval: Union[int, float] = 0.1*, *noise_level_measurement_channel_1: Union[int, float] = 100*, *noise_level_measurement_channel_2: Union[int, float] = 100*, *noise_level_measurement_channel_3: Union[int, float] = 100*, *noise_level_measurement_channel_4: Union[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: Union[int, float] = 100

noise_level_measurement_channel_2: Union[int, float] = 100

noise_level_measurement_channel_3: Union[int, float] = 100

noise_level_measurement_channel_4: Union[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: Union[int, float] = 5.0

polling_interval_sec: Union[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: Union[int, float] = 0.1

timeout_status_change: Union[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: ~typing.Union[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.uaprotocol_auto.CreateSubscriptionParameters = CreateSubscriptionParameters(RequestedPublishingInterval=1000, RequestedLifetimeCount=300, RequestedMaxKeepAliveCount=22, MaxNotificationsPerPublish=10000, PublishingEnabled=True, Priority=0), wait_timeout_retry_sec: ~typing.Union[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]

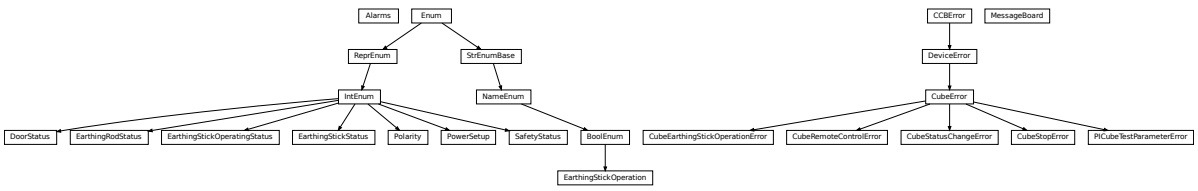
Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

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.

exception CubeEarthingStickOperationError

Bases: *CubeError*

exception CubeError

Bases: *DeviceError*

exception CubeRemoteControlError

Bases: *CubeError*

exception CubeStatusChangeError

Bases: *CubeError*

exception CubeStopError

Bases: *CubeError*

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

Bases: IntEnum

Operating Status for an earthing stick. Stick can be used in auto or manual mode.

AUTO = 0

MANUAL = 1

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

Bases: *BoolEnum*

Operation of the earthing stick in manual operating mode. Can be closed of opened.

CLOSE = True

OPEN = False

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

Bases: `IntEnum`

Status of an earthing stick. These are the possible values in the status integer e.g. in `_EarthingStick.status`.

CLOSED = 1

ERROR = 3

INACTIVE = 0

OPEN = 2

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"'

exception PICubeTestParameterError

Bases: *CubeError*

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: 1>, <SafetyStatus.GREEN_READY: 2>)

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

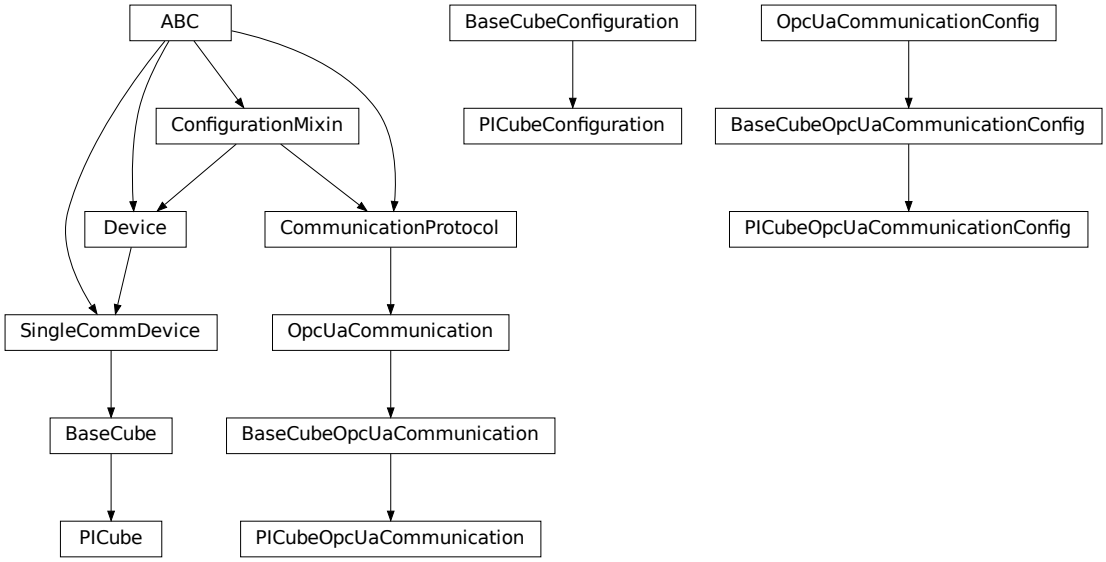
INITIALIZING = 0

QUICK_STOP = 5

RED_OPERATE = 4

RED_READY = 3

hvl_ccb.dev.cube.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: Optional[bool]

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: Optional[*Polarity*]

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: Union[int, float] = 5.0*, *polling_interval_sec: Union[int, float] = 1.0*, *timeout_status_change: Union[int, float] = 6*, *timeout_interval: Union[int, float] = 0.1*, *noise_level_measurement_channel_1: Union[int, float] = 100*, *noise_level_measurement_channel_2: Union[int, float] = 100*, *noise_level_measurement_channel_3: Union[int, float] = 100*, *noise_level_measurement_channel_4: Union[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: Union[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 0x7f3aaa233dd0>, update_parameter: asyncua.ua.uaprotocol_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.

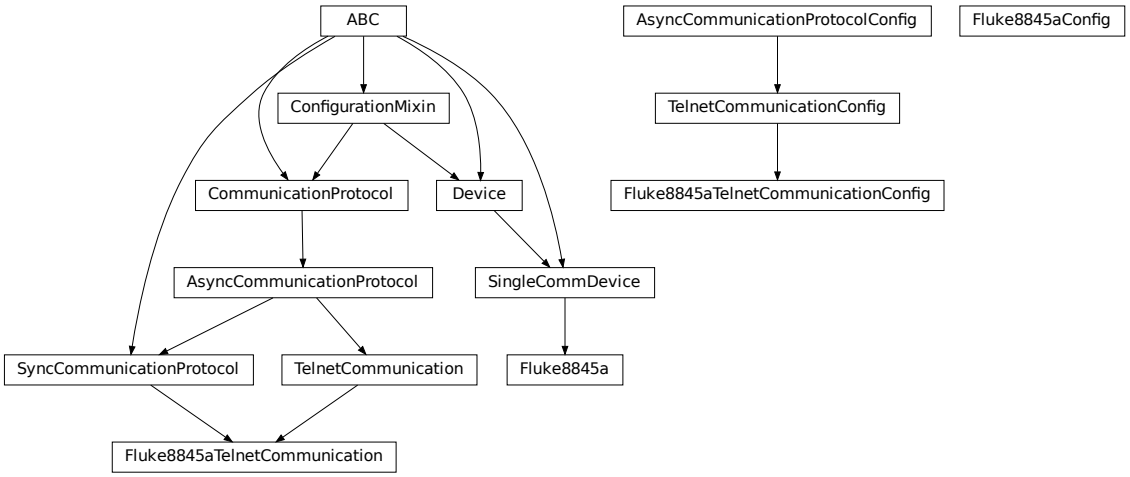
Module contents

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

hvl_ccb.dev.fluke884x

Submodules

hvl_ccb.dev.fluke884x.base



Python module for the Fluke8845a Multimeter. The communication to the device is through Telnet. 8845A/8846A Programmers Manual is available in the following link. All page numbers mentioned in this script refer to this manual. https://download.flukecal.com/pub/literature/8845A___pmeng0300.pdf

class Fluke8845a(*com*, *dev_config=None*)

Bases: *SingleCommDevice*

Device class to control Fluke8845a

DISPLAY_MAX_LENGTH = 12

ac_current_range

ac_voltage_range

activate_remote_mode() → *None*

Page 66

Places the Meter in the remote mode for RS-232 or Ethernet remote control. All front-panel keys, except the local key, are disabled.

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 1'*)

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*) → str

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

Parameters
command – Command to send

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: Union[int, float] = 0.5*, *default_n_attempts_read_text_nonempty: int = 10*, *host: Union[str, ipaddress.IPv4Address, ipaddress.IPv6Address, NoneType] = None*, *port: int = 3490*, *timeout: Union[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]

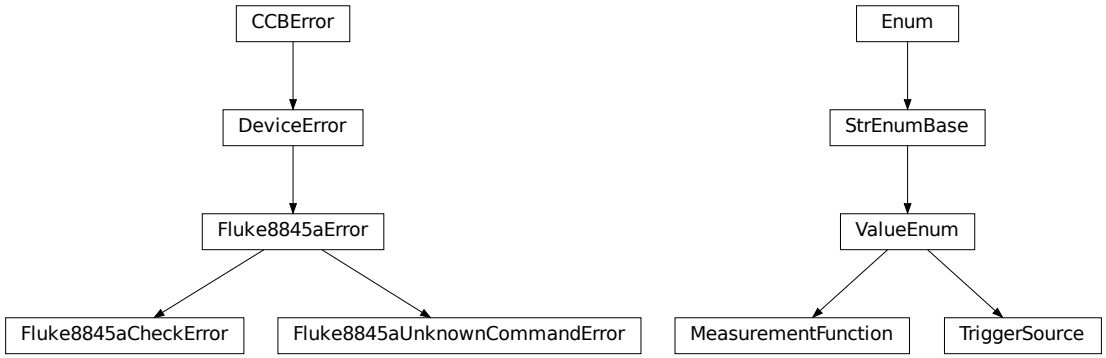
Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

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 TriggerSoruce 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

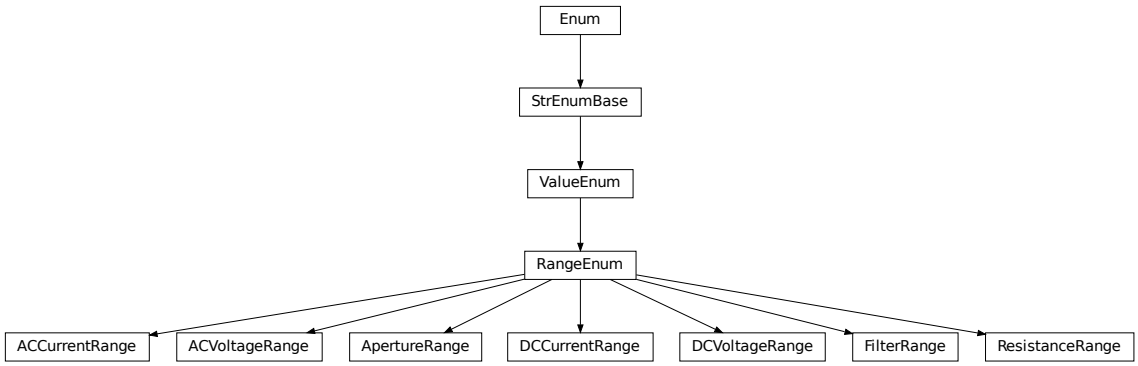
```
BUS: Sets the Meter to expect a trigger through the IEEE-488 bus or
upon execution of a *TRG command
IMM: Selects Meter's internal triggering system
EXT: Sets the Meter to sense triggers through the trigger jack on the rear
panel of the Meter
```

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

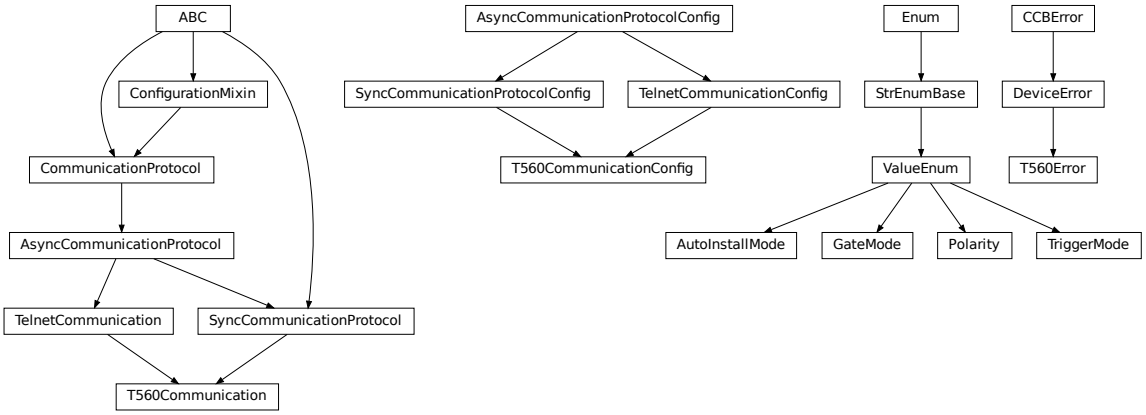
Module contents

Fluke 8845A multimeter implementation using Telnet communication

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*) → 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

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: Union[int, float] = 0.5*, *default_n_attempts_read_text_nonempty: int = 10*, *host: Union[str, ipaddress.IPv4Address, ipaddress.IPv6Address, NoneType] = None*, *port: int = 2000*, *timeout: Union[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'

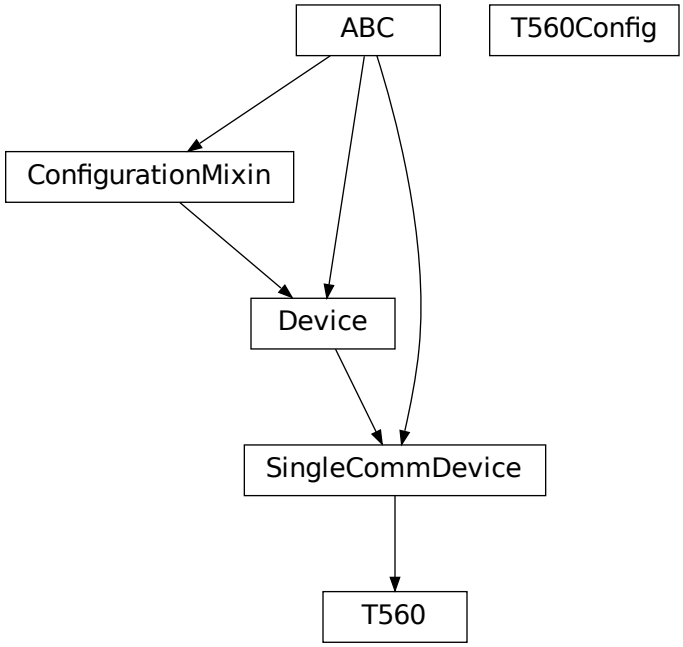
INT_SYNTHESIZER = 'SYN'

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.

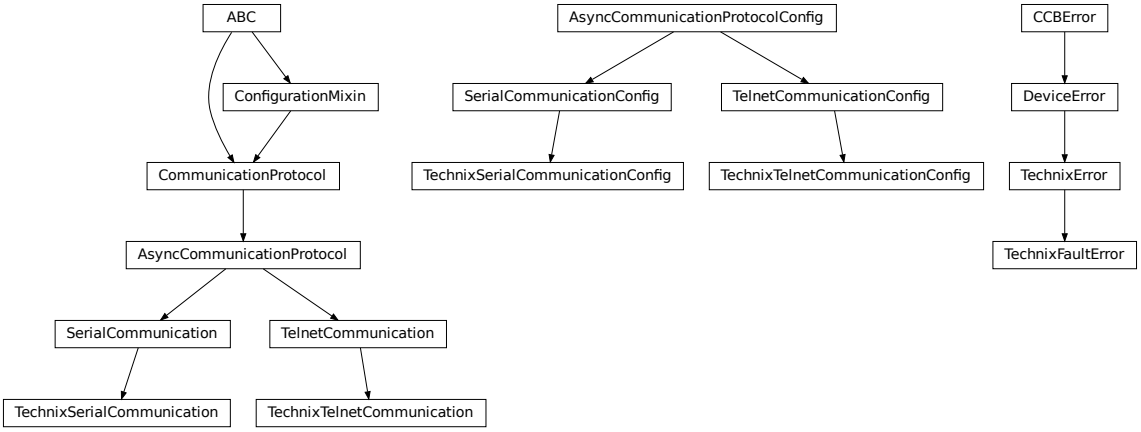
This module introduces methods for configuring channels, gating, and triggering. Further documentation and a more extensive command list may be obtained from:

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

hvl_ccb.dev.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: Union[int, float] = 0.5*, *default_n_attempts_read_text_nonempty: int = 10*, *port: Optional[str] = None*, *baudrate: int = 9600*, *parity: Union[str, SerialCommunicationParity] = SerialCommunicationParity.NONE*, *stopbits: Union[int, float, SerialCommunicationStopbits] = SerialCommunicationStopbits.ONE*, *bytesize: Union[int, SerialCommunicationBytesize] = SerialCommunicationBytesize.EIGHTBITS*, *timeout: Union[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: Union[int, float] = 0.5*, *default_n_attempts_read_text_nonempty: int = 10*, *host: Optional[Union[str, IPv4Address, IPv6Address]] = None*, *port: int = 4660*, *timeout: Union[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

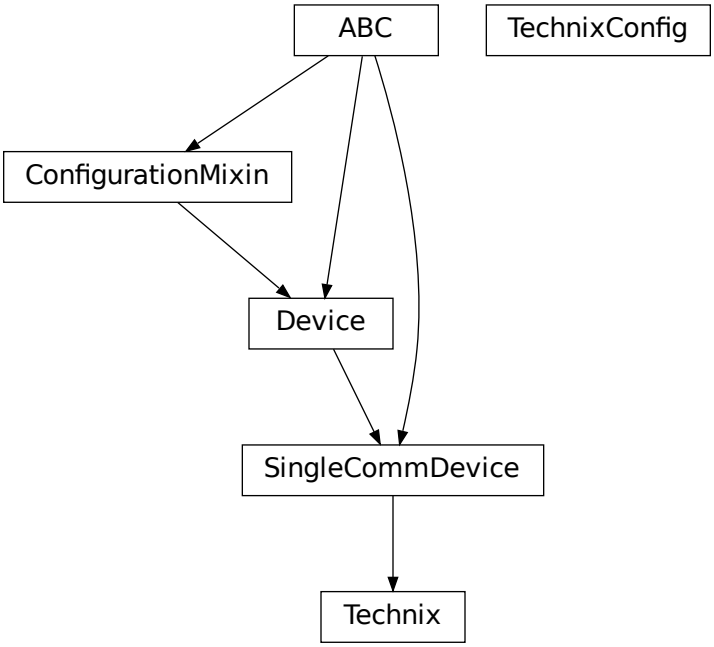
Port at which Technix is listening

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



The device class *Technix* and its corresponding configuration class

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: Optional[Union[int, float]]

Actual current of the output in A

default_com_cls() → Union[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: Optional[bool]

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: Union[int, float]

Maximal output current of the hardware in A

property max_voltage: Union[int, float]

Maximal output voltage of the hardware in V

property open_interlock: Optional[bool]

Is the interlock open? (in safe mode)

property output: Optional[bool]

State of the high voltage output

query_status(*, *_retry: bool = False*)

Query the status of the device.

Returns

This function returns nothing

property remote: Optional[bool]

Is the device in remote control mode?

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: Optional[_Status]

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: Optional[Union[int, float]]

Actual voltage at the output in V

property voltage_regulation: Optional[bool]

Status if the output is in voltage regulation mode (or current regulation)

class TechnixConfig(*communication_channel: Union[Type[*hvl_ccb.dev.technix.base.TechnixSerialCommunication*], Type[*hvl_ccb.dev.technix.base.TechnixTelnetCommunication*]], max_voltage: Union[int, float], max_current: Union[int, float], polling_interval_sec: Union[int, float] = 4, post_stop_pause_sec: Union[int, float] = 1, register_pulse_time: Union[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: Union[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: Union[int, float]`

Maximal Output current

`max_voltage: Union[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: Union[int, float] = 4`

Polling interval in s to maintain to watchdog of the device

`post_stop_pause_sec: Union[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: Union[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

NOTE: libtiepie tries to load the libtiepie SDK during import. Thus, the API docs can only be generated in a system with the latter installed.

To build the API docs for this subpackage locally edit all files that match `docs/hvl_ccb.dev.tiepie.XXX.rst` and remove the `.. code-block::` directive preceding the following directives:

```
.. inheritance-diagram:: hvl_ccb.dev.tiepie.base
   :parts: 1


.. automodule:: hvl_ccb.dev.tiepie.base
   :members:
   :undoc-members:
   :show-inheritance:
```

hvl_ccb.dev.tiepie.channel

NOTE: libtiepie tries to load the libtiepie SDK during import. Thus, the API docs can only be generated in a system with the latter installed.

To build the API docs for this subpackage locally edit all files that match `docs/hvl_ccb.dev.tiepie.XXX.rst` and remove the `.. code-block::` directive preceding the following directives:

```
.. inheritance-diagram:: hvl_ccb.dev.tiepie.channel
   :parts: 1


.. automodule:: hvl_ccb.dev.tiepie.channel
   :members:
   :undoc-members:
   :show-inheritance:
```

hvl_ccb.dev.tiepie.device

NOTE: libtiepie tries to load the libtiepie SDK during import. Thus, the API docs can only be generated in a system with the latter installed.

To build the API docs for this subpackage locally edit all files that match `docs/hvl_ccb.dev.tiepie.XXX.rst` and remove the `.. code-block::` directive preceding the following directives:

```
.. inheritance-diagram:: hvl_ccb.dev.tiepie.device
   :parts: 1


.. automodule:: hvl_ccb.dev.tiepie.device
   :members:
   :undoc-members:
   :show-inheritance:
```

hvl_ccb.dev.tiepie.generator

NOTE: libtiepie tries to load the libtiepie SDK during import. Thus, the API docs can only be generated in a system with the latter installed.

To build the API docs for this subpackage locally edit all files that match `docs/hvl_ccb.dev.tiepie.XXX.rst` and remove the `.. code-block::` directive preceding the following directives:

```
.. inheritance-diagram:: hvl_ccb.dev.tiepie.generator
   :parts: 1


.. automodule:: hvl_ccb.dev.tiepie.generator
   :members:
   :undoc-members:
   :show-inheritance:
```

hvl_ccb.dev.tiepie.i2c

NOTE: libtiepie tries to load the libtiepie SDK during import. Thus, the API docs can only be generated in a system with the latter installed.

To build the API docs for this subpackage locally edit all files that match `docs/hvl_ccb.dev.tiepie.XXX.rst` and remove the `.. code-block::` directive preceding the following directives:

```
.. inheritance-diagram:: hvl_ccb.dev.tiepie.i2c
   :parts: 1


.. automodule:: hvl_ccb.dev.tiepie.i2c
   :members:
   :undoc-members:
   :show-inheritance:
```

hvl_ccb.dev.tiepie.oscilloscope

NOTE: libtiepie tries to load the libtiepie SDK during import. Thus, the API docs can only be generated in a system with the latter installed.

To build the API docs for this subpackage locally edit all files that match `docs/hvl_ccb.dev.tiepie.XXX.rst` and remove the `.. code-block::` directive preceding the following directives:

```
.. inheritance-diagram:: hvl_ccb.dev.tiepie.oscilloscope
   :parts: 1


.. automodule:: hvl_ccb.dev.tiepie.oscilloscope
   :members:
   :undoc-members:
   :show-inheritance:
```

hvl_ccb.dev.tiepie.utils

NOTE: libtiepie tries to load the libtiepie SDK during import. Thus, the API docs can only be generated in a system with the latter installed.

To build the API docs for this subpackage locally edit all files that match `docs/hvl_ccb.dev.tiepie.XXX.rst` and remove the `.. code-block::` directive preceding the following directives:

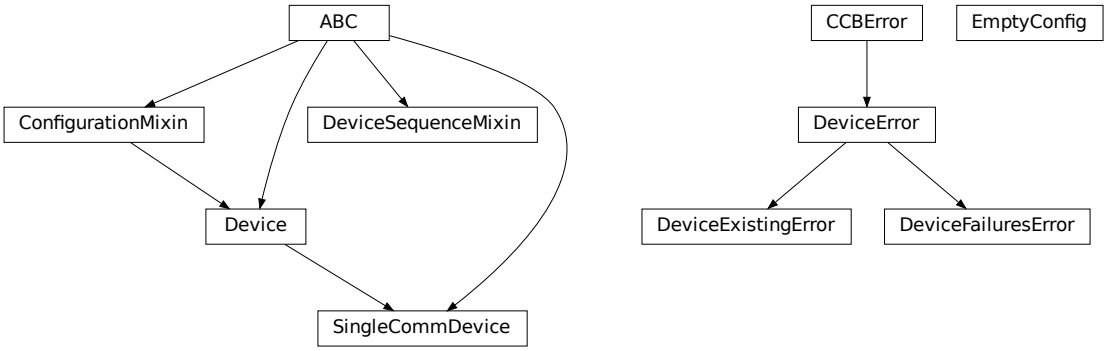
```
.. inheritance-diagram:: hvl_ccb.dev.tiepie.utils
   :parts: 1


.. automodule:: hvl_ccb.dev.tiepie.utils
   :members:
   :undoc-members:
   :show-inheritance:
```

Module contents

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

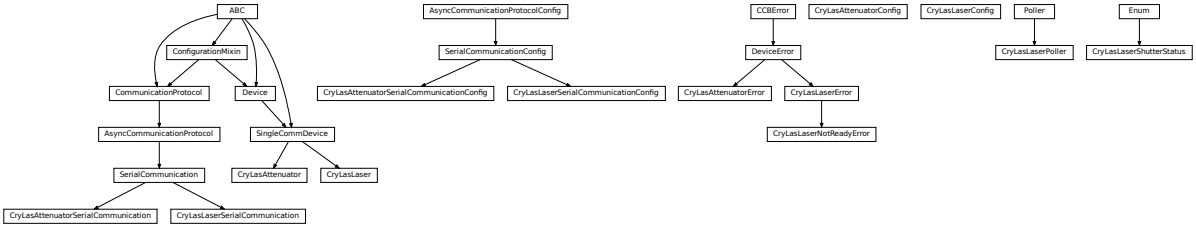
start() → *None*

Open the associated communication protocol.

stop() → *None*

Close the associated communication protocol.

hvl_ccb.dev.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: Union[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: Union[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: Union[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: Union[int, float]

class CryLasAttenuatorConfig(*init_attenuation: Union[int, float] = 0*, *response_sleep_time: Union[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: Union[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: Union[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: Union[str, NoneType] = 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: Union[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: Union[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: Union[int, *SerialCommunicationStopbits*] = 1

CryLas attenuator uses one stop bit

terminator: bytes = b''

No terminator

timeout: Union[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: Union[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: Union[int, float] = 4.35*, *polling_period: Union[int, float] = 12*, *polling_timeout: Union[int, float] = 300*, *auto_laser_on: bool = True*, *init_shutter_status: Union[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: Union[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: Union[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: Union[int, float] = 12

polling_timeout: Union[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: Union[int, float] = 0*, *polling_interval_sec: Union[int, float] = 1*, *polling_timeout_sec: Optional[Union[int, float]] = 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: Optional[str] = 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: Union[str, NoneType] = 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: Union[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: Union[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: Union[int, *SerialCommunicationStopbits*] = 1

CryLas laser uses one stop bit

terminator: bytes = b'\n'

The terminator is LF

timeout: Union[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

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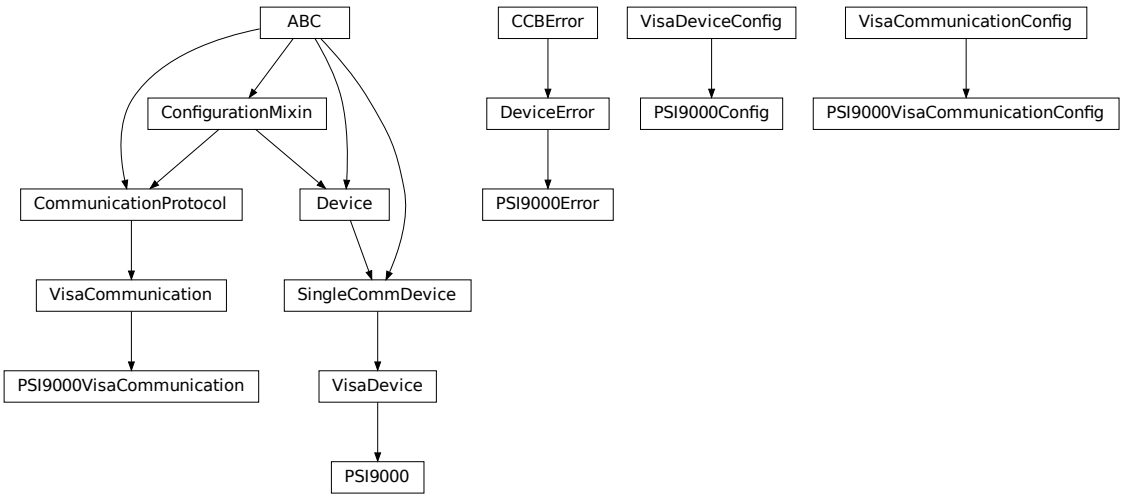

Device class for controlling a Elektro Automatik PSI 9000 power supply over VISA.

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: Union[PSI9000VisaCommunication, PSI9000VisaCommunicationConfig, dict], dev_config: Optional[Union[PSI9000Config, dict]] = 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: Optional[float] = None*, *current_limit: Optional[float] = 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: Optional[float] = None*, *current_limit: Optional[float] = None*, *power_limit: Optional[float] = 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: Union[int, float] = 0.5*, *spoll_start_delay: Union[int, float] = 2*, *power_limit: Union[int, float] = 43500*, *voltage_lower_limit: Union[int, float] = 0.0*, *voltage_upper_limit: Union[int, float] = 10.0*, *current_lower_limit: Union[int, float] = 0.0*, *current_upper_limit: Union[int, float] = 2040.0*, *wait_sec_system_lock: Union[int, float] = 0.5*, *wait_sec_settings_effect: Union[int, float] = 1*, *wait_sec_initialisation: Union[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: Union[int, float] = 0.0

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

current_upper_limit: Union[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: Union[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: Union[int, float] = 0.0

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

voltage_upper_limit: Union[int, float] = 10.0

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

wait_sec_initialisation: Union[int, float] = 2

wait_sec_settings_effect: Union[int, float] = 1

wait_sec_system_lock: Union[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: Union[str, IPv4Address, IPv6Address]*, *interface_type: Union[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: Union[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.

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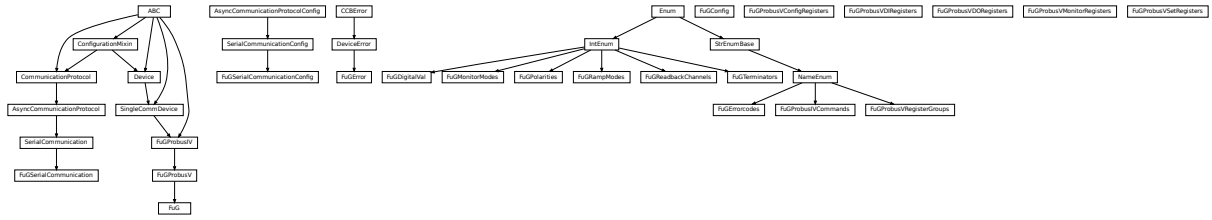

Device classes for "Probus V - ADDAT30" Interfaces which are used to control power supplies from FuG Elektronik GmbH

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 used by "normal" customers.

class FuG(*com*, *dev_config=None*)

Bases: *FuGProbusV*

FuG power supply device class.

The power supply is controlled over a FuG ADDA Interface with the PROBUS V protocol

property config_status: *FuGProbusVConfigRegisters*

Returns the registers for the registers with the configuration and status values

Returns
FuGProbusVConfigRegisters

property current: *FuGProbusVSetRegisters*

Returns the registers for the current output

Returns

property current_monitor: *FuGProbusVMonitorRegisters*

Returns the registers for the current monitor.

A typically usage will be "self.current_monitor.value" to measure the output current

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: Union[int, float]

Returns the maximal current which could provided within the test setup

Returns

property max_current_hardware: Union[int, float]

Returns the maximal current which could provided with the power supply

Returns

property max_voltage: Union[int, float]

Returns the maximal voltage which could provided within the test setup

Returns

property max_voltage_hardware: Union[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: Union[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: Union[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: Union[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: *FuGErrorcodes*

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: **Union[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: Union[str, NoneType] = 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: Union[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: Union[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: Union[int, *SerialCommunicationStopbits*] = 1

FuG uses one stop bit

terminator: bytes = b'\n'

The terminator is LF

timeout: Union[int, float] = 3

use 3 seconds timeout as default

wait_sec_read_text_nonempty: Union[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

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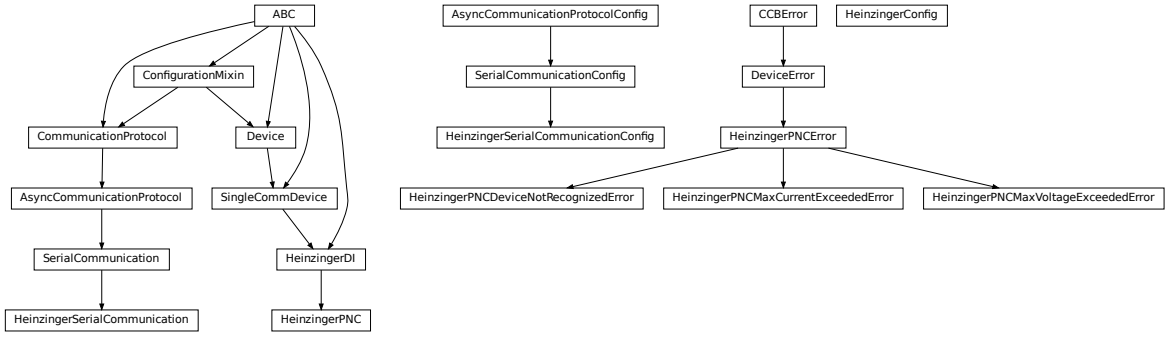


Device classes for Heinzinger Digital Interface I/II and Heinzinger PNC power supply.

The Heinzinger Digital Interface I/II is used for many Heinzinger power units. Manufacturer homepage: https://www.heinzinger.com/products/accessories-and-more/digital-interfaces/

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/products/high-voltage/universal-high-voltage-power-supplies/

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

Bases: object

Device configuration dataclass for Heinzinger power supplies.

class RecordingsEnum(*value*)

Bases: IntEnum

An enumeration.

EIGHT = 8

FOUR = 4

ONE = 1

SIXTEEN = 16

TWO = 2

clean_values()

default_number_of_recordings: Union[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: Union[int, float] = 0.5

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

class HeinzingerDI(*com*, *dev_config=None*)

Bases: *SingleCommDevice*, ABC

Heinzinger Digital Interface I/II device class

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

class OutputStatus(*value*)

Bases: IntEnum

Status of the voltage output

OFF = 0

ON = 1

UNKNOWN = -1

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_current() → float

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

Raises
SerialCommunicationIOError – when communication port is not opened

get_interface_version() → str

Queries the version number of the digital interface.

Raises
SerialCommunicationIOError – when communication port is not opened

get_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

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

get_voltage() → float

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

Raises
SerialCommunicationIOError – when communication port is not opened

measure_current() → float

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

Returns
measured current as float

Raises
SerialCommunicationIOError – when communication port is not opened

measure_voltage() → float

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

Returns
measured voltage as float

Raises
SerialCommunicationIOError – when communication port is not opened

output_off() → *None*

Switch DC voltage output off and updates the output status.

Raises
SerialCommunicationIOError – when communication port is not opened

output_on() → *None*

Switch DC voltage output on and updates the output status.

Raises
SerialCommunicationIOError – when communication port is not opened

property output_status: *OutputStatus*

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

set_current(*value: Union[int, float]*) → *None*

Sets the output current of the Heinzinger PNC to the given value.

Parameters
value – current expressed in *self.unit_current*

Raises
SerialCommunicationIOError – when communication port is not opened

set_number_of_recordings(*value: Union[int,* RecordingsEnum*]*) → *None*

Sets the number of recordings the device is using for average value calculation. The possible values are 1, 2, 4, 8 and 16.

Raises
SerialCommunicationIOError – when communication port is not opened

set_voltage(*value: Union[int, float]*) → *None*

Sets the output voltage of the Heinzinger PNC to the given value.

Parameters
value – voltage expressed in *self.unit_voltage*

Raises
SerialCommunicationIOError – when communication port is not opened

abstract start()

Opens the communication protocol.

Raises
SerialCommunicationIOError – when communication port cannot be opened.

stop() → *None*

Stop the device. Closes also the communication protocol.

class HeinzingerPNC(*com*, *dev_config=None*)

Bases: *HeinzingerDI*

Heinzinger PNC power supply device class.

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

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

Bases: *AutoNumberNameEnum*

An enumeration.

A = 3

UNKNOWN = 1

mA = 2

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

Bases: *AutoNumberNameEnum*

An enumeration.

UNKNOWN = 1

V = 2

kV = 3

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: Union[int, float]

property max_current_hardware: Union[int, float]

property max_voltage: Union[int, float]

property max_voltage_hardware: Union[int, float]

set_current(*value: Union[int, float]*) → *None*

Sets the output current of the Heinzinger PNC to the given value.

Parameters
value – current expressed in *self.unit_current*

Raises
SerialCommunicationIOError – when communication port is not opened

set_voltage(*value: Union[int, float]*) → *None*

Sets the output voltage of the Heinzinger PNC to the given value.

Parameters
value – voltage expressed in *self.unit_voltage*

Raises
SerialCommunicationIOError – when communication port is not opened

start() → *None*

Opens the communication protocol and configures the device.

property unit_current: *UnitCurrent*

property unit_voltage: *UnitVoltage*

exception HeinzingerPNCDeviceNotRecognizedError

Bases: *HeinzingerPNCError*

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

exception HeinzingerPNCError

Bases: *DeviceError*

General error with the Heinzinger PNC voltage source.

exception HeinzingerPNCMaxCurrentExceededError

Bases: *HeinzingerPNCError*

Error indicating that program attempted to set the current to a value exceeding 'max_current'.

exception HeinzingerPNCMaxVoltageExceededError

Bases: *HeinzingerPNCError*

Error indicating that program attempted to set the voltage to a value exceeding 'max_voltage'.

class HeinzingerSerialCommunication(*configuration*)

Bases: *SerialCommunication*

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: Union[str, NoneType] = 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: Union[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: Union[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: `Union[int, SerialCommunicationStopbits] = 1`

Heinzinger uses one stop bit

terminator: `bytes = b'\n'`

The terminator is LF

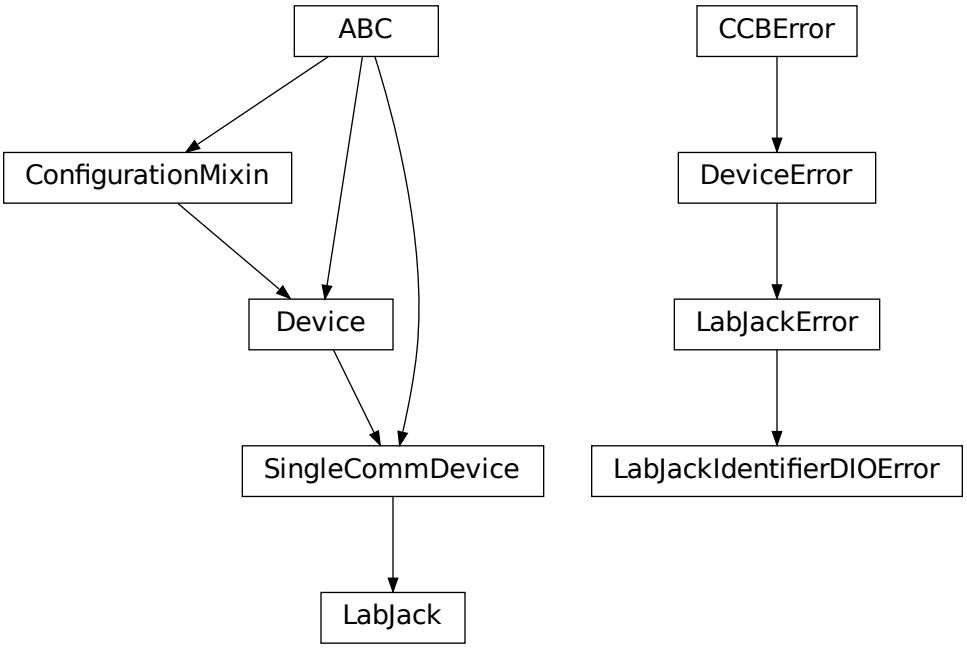
timeout: `Union[int, float] = 3`

use 3 seconds timeout as default

wait_sec_read_text_nonempty: `Union[int, float] = 0.5`

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

hvl_ccb.dev.labjack



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 `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 ambigious 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*) → Union[*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: Union[str, TSeriesDIOChannel]*, *t_start: Union[int, float]*, *t_width: Union[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: Optional[Union[str, TSeriesDIOChannel]]*) → *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*) → Union[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: Union[str,* CalMicroAmpere*]*) → float

This function will return the calibration of the chosen current source, this ist 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, Union[int, float]]

Return clock settings read from LabJack.

get_digital_input(*address: Union[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: Union[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*, *vrange: Union[Real,* AInRange*]*) → *None*

Set the range of an analog input port.

Parameters

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

set_ain_resistance(*channel: int*, *vrange: Union[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
- **vrange** – 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: Union[*None*, str,* ThermocoupleType*]*, *cjc_address: int = 60050*, *cjc_type: Union[str,* CjcType*] = CjcType.internal*, *vrange: Union[Real,* AInRange*] = AInRange.ONE_HUNDREDTH*, *resolution: int = 10*, *unit: Union[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’

- **vrange** – 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: Union[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: Union[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: Union[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*

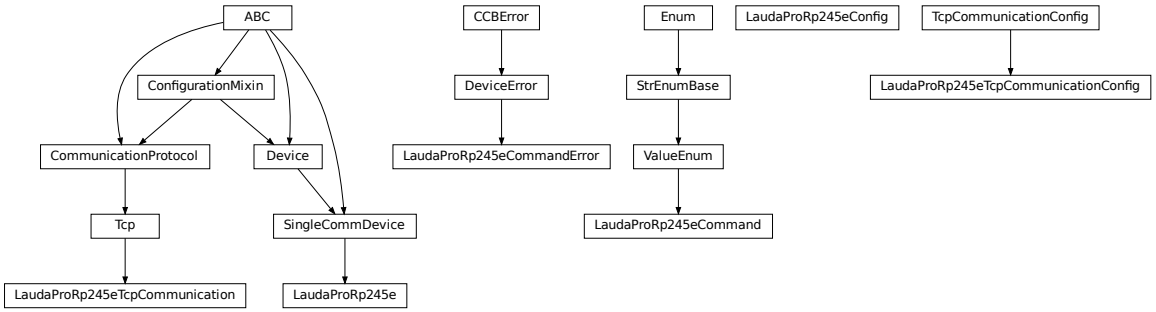
General Error for the LabJack device.

exception LabJackIdentifierDIOError

Bases: *LabJackError*

Error indicating a wrong DIO identifier

hvl_ccb.dev.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: Union[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: Union[int, float] = 20.0*, *pump_init: int = 6*, *upper_temp: Union[int, float] = 80.0*, *lower_temp: Union[int, float] = -55.0*, *com_time_out: Union[int, float] = 0*, *max_pump_level: int = 8*, *max_pr_number: int = 5*, *operation_mode: Union[int,* OperationModeEnum*] = OperationModeEnum.AUTO*, *control_mode: Union[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: Union[int, float] = 0

Communication time out (0 = OFF)

control_mode: Union[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: Union[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: Union[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: Union[int, float] = 20.0

Default temperature set point

upper_temp: Union[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: Union[str, IPv4Address, IPv6Address]*, *port: int = 54321*, *bufsize: int = 1024*, *wait_sec_pre_read_or_write: Union[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.

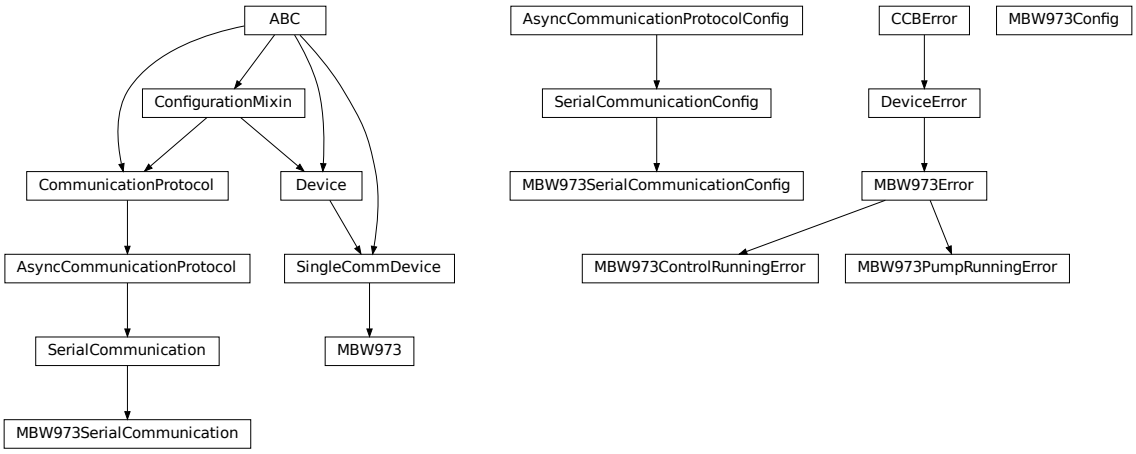
terminator: str = '\r\n'

The terminator character

wait_sec_pre_read_or_write: Union[int, float] = 0.005

Delay time between commands in seconds

hvl_ccb.dev.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: ~typing.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: Union[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: Union[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: Union[str, NoneType] = 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: Union[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: Union[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: Union[int, *SerialCommunicationStopbits*] = 1

MBW973 does use one stop bit

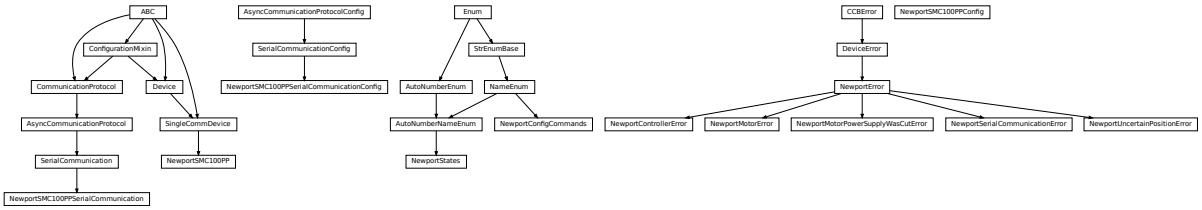
terminator: bytes = b'\r'

The terminator is only CR

timeout: Union[int, float] = 3

use 3 seconds timeout as default

hvl_ccb.dev.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 NewportControllerError

Bases: *NewportError*

Error with the Newport controller.

exception NewportError

Bases: *DeviceError*

General Error for Newport Device

exception NewportMotorError

Bases: *NewportError*

Error with the Newport motor.

exception NewportMotorPowerSupplyWasCutError

Bases: *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: Optional[int] = 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: Optional[int] = None*) → Union[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/s^2), 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: Optional[int] = 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: Optional[int] = 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: Union[int, float]*, *add: Optional[int] = 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: Optional[int] = None*) → Union[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: Optional[int] = 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: Optional[int] = None*) → Union[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*) → *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: Optional[int] = 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: Optional[int] = 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: Optional[int] = 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: Union[int, float]*, *add: Optional[int] = 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: Union[int, float]*, *add: Optional[int] = 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: Optional[int] = 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: Union[int, float]*, *add: Optional[int] = None*) → *None*

Leave the configuration state. The configuration parameters are saved to the device"s memory.

Parameters

- **acc** – acceleration (preset units/s^2), 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: Optional[int] = None*, *config: Optional[dict] = 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: Union[int, float]*, *add: Optional[int] = 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: Union[int, float]*, *add: Optional[int] = 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: Optional[int] = 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: Optional[int] = 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: Union[int, float] = 23.987*, *screw_scaling: Union[int, float] = 1*, *exit_configuration_wait_sec: Union[int, float] = 5*, *move_wait_sec: Union[int, float] = 1*, *acceleration: Union[int, float] = 10*, *backlash_compensation: Union[int, float] = 0*, *hysteresis_compensation: Union[int, float] = 0.015*, *micro_step_per_full_step_factor: int = 100*, *motion_distance_per_full_step: Union[int, float] = 0.01*, *home_search_type: Union[int, HomeSearch] = HomeSearch.HomeSwitch*, *jerk_time: Union[int, float] = 0.04*, *home_search_velocity: Union[int, float] = 4*, *home_search_timeout: Union[int, float] = 27.5*, *home_search_polling_interval: Union[int, float] = 1*, *peak_output_current_limit: Union[int, float] = 0.4*, *rs485_address: int = 2*, *negative_software_limit: Union[int, float] = -23.5*, *positive_software_limit: Union[int, float] = 25*, *velocity: Union[int, float] = 4*, *base_velocity: Union[int, float] = 0*, *stage_configuration: Union[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: Union[int, float] = 10

address: int = 1

backlash_compensation: Union[int, float] = 0

base_velocity: Union[int, float] = 0

clean_values()

exit_configuration_wait_sec: Union[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: Union[int, float] = 1

home_search_timeout: Union[int, float] = 27.5

home_search_type: Union[int, *HomeSearch*] = 2

home_search_velocity: Union[int, float] = 4

hysteresis_compensation: Union[int, float] = 0.015

is_configdataclass = True

jerk_time: Union[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: Union[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: Union[int, float] = 1

negative_software_limit: Union[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: Union[int, float] = 0.4

positive_software_limit: Union[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: Union[int, float] = 1

stage_configuration: Union[int, *EspStageConfig*] = 3

user_position_offset: Union[int, float] = 23.987

velocity: Union[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: Optional[Union[int, float, str]] = 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: Optional[Union[int, float, str]] = 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'\r\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: Union[str, NoneType] = 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: Union[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: Union[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: Union[int, *SerialCommunicationStopbits*] = 1

NewportSMC100 controller uses one stop bit

terminator: bytes = b'\r\n'

The terminator is CR/LF

timeout: Union[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

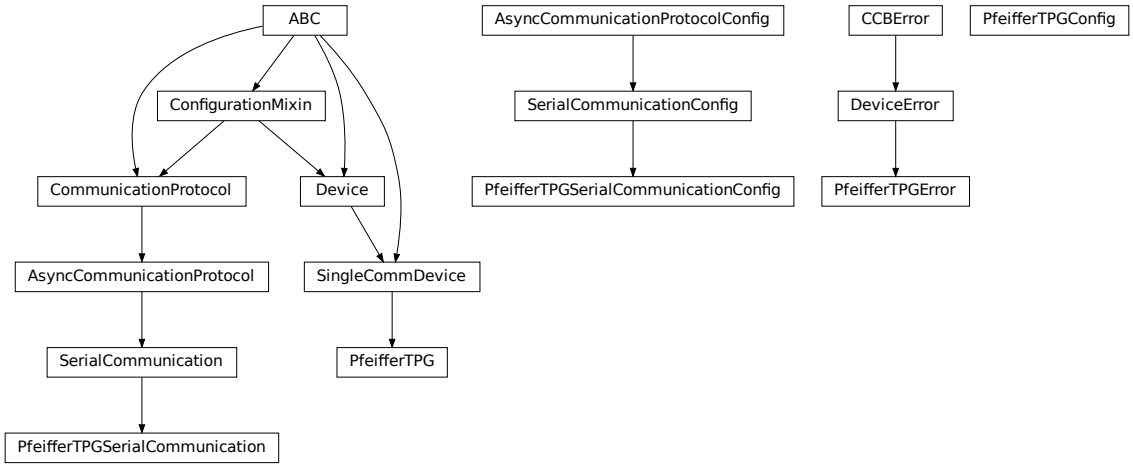
READY = 4

exception NewportUncertainPositionError

Bases: *NewportError*

Error with the position of the Newport motor.

hvl_ccb.dev.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[Union[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 <= channel <= 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[Union[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: Union[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: Union[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: Union[str, NoneType] = 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: Union[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: Union[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: `Union[int, SerialCommunicationStopbits] = 1`

Pfeiffer TPG controllers use one stop bit

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

The terminator is <CR><LF>

timeout: `Union[int, float] = 3`

use 3 seconds timeout as default

hvl_ccb.dev.picotech_pt104

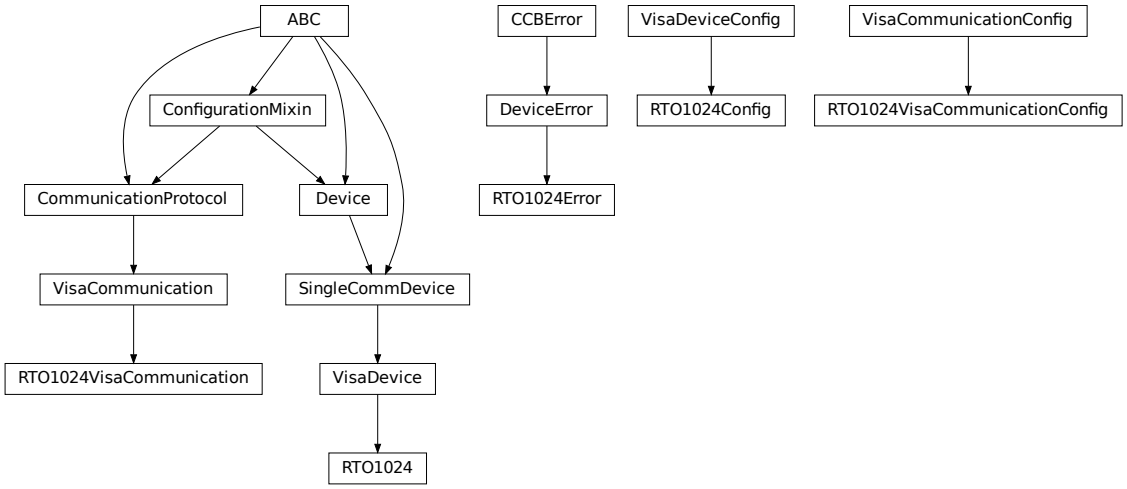
NOTE: PicoSDK Python wrappers already on import attempt to load the PicoSDK library; thus, the API docs can only be generated in a system with the latter installed and are by default disabled.

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.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: Union[RTO1024VisaCommunication, RTO1024VisaCommunicationConfig, dict]*, *dev_config: Union[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
RTO1024Error – 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 '.dfl' 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
RTO1024Error – 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: Union[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
RTO1024Error – 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 RTO1024Config(*waveforms_path: str*, *settings_path: str*, *backup_path: str*, *spoll_interval: Union[int, float] = 0.5*, *spoll_start_delay: Union[int, float] = 2*, *command_timeout_seconds: Union[int, float] = 60*, *wait_sec_short_pause: Union[int, float] = 0.1*, *wait_sec_enable_history: Union[int, float] = 1*, *wait_sec_post_acquisition_start: Union[int, float] = 2*)

Bases: *VisaDeviceConfig*, _RTO1024ConfigDefaultsBase, _RTO1024ConfigBase

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 RTO1024Error

Bases: *DeviceError*

class RTO1024VisaCommunication(*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 RTO1024VisaCommunicationConfig(*host: Union[str, IPv4Address, IPv6Address]*, *interface_type: Union[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: Union[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.

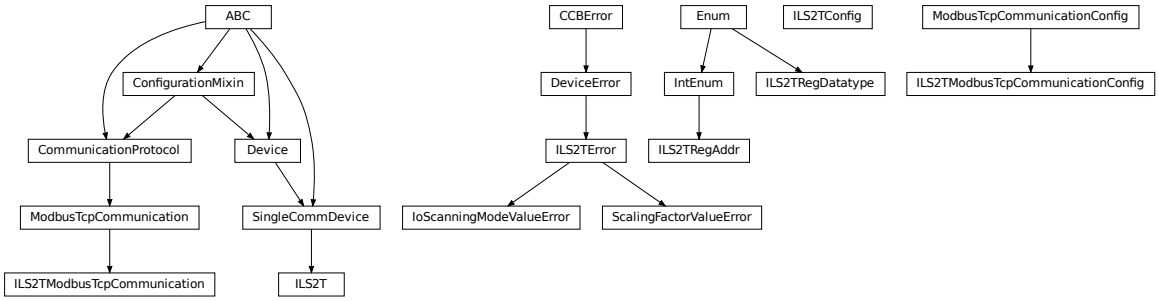
Returns
a list of strings containing all optional keys.

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.

hvl_ccb.dev.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: Optional[int] = 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 occured.

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: Union[int, float] = 1*, *wait_sec_max_disable: Union[int, float] = 10*, *wait_sec_post_cannot_disable: Union[int, float] = 1*, *wait_sec_post_relative_step: Union[int, float] = 2*, *wait_sec_post_absolute_position: Union[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: Union[int, float] = 10

wait_sec_post_absolute_position: Union[int, float] = 2

wait_sec_post_cannot_disable: Union[int, float] = 1

wait_sec_post_enable: Union[int, float] = 1

wait_sec_post_relative_step: Union[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: Union[str, IPv4Address, IPv6Address]*, *unit: int = 255*, *port: int = 502*)

Bases: *ModbusTcpCommunicationConfig*

Configuration dataclass for Modbus/TCP communciation 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*

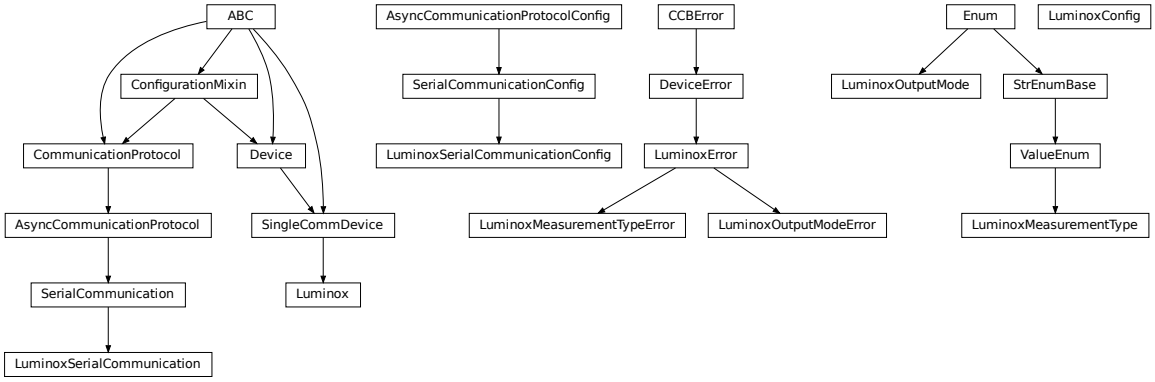
Erorr to indicate that the selected IO scanning mode is invalid.

exception ScalingFactorValueError

Bases: *ILS2TError*

Error to indicate that a scaling factor value is invalid.

hvl_ccb.dev.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 a 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: Union[str,* LuminoxMeasurementType*]*) → Union[Dict[Union[str, *LuminoxMeasurementType*], Union[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[Union[str, *LuminoxMeasurementType*], Union[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: Union[int, float] = 0.5*, *wait_sec_trials_activate: Union[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: Union[int, float] = 0.5

wait_sec_trials_activate: Union[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*) → Union[Dict[Union[str, *LuminoxMeasurementType*], Union[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.

alias of Dict[Union[str, *LuminoxMeasurementType*], Union[float, int, str]]

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'\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: Union[str, NoneType] = 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: Union[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: Union[str, *SerialCommunicationParity*] = 'N'

SST Luminox 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: Union[int, *SerialCommunicationStopbits*] = 1

SST Luminox does use one stop bit

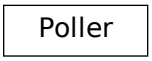
terminator: bytes = b'\r\n'

The terminator is CR LF

timeout: Union[int, float] = 3

use 3 seconds timeout as default

hvl_ccb.dev.utils



class Poller(*spoll_handler: Callable*, *polling_delay_sec: Union[int, float] = 0*, *polling_interval_sec: Union[int, float] = 1*, *polling_timeout_sec: Optional[Union[int, float]] = 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

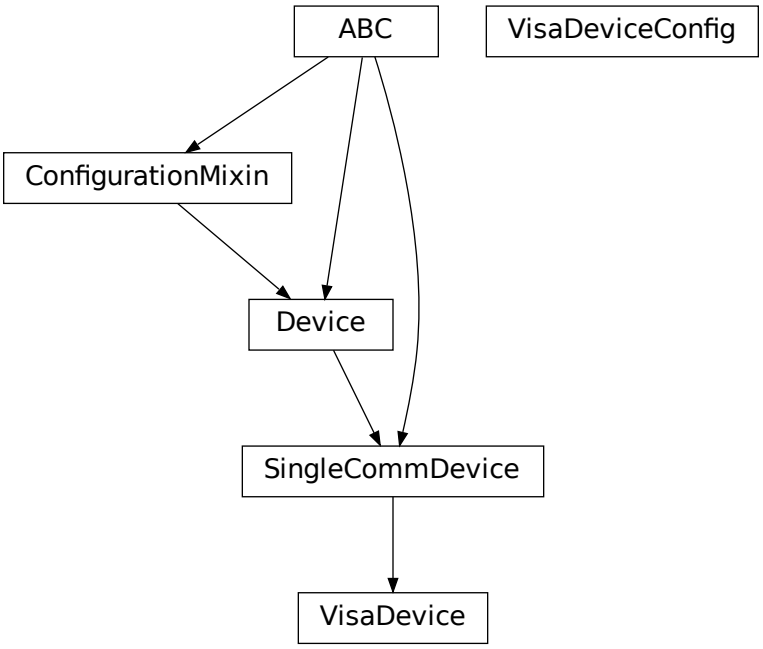
wait_for_polling_result()

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.dev.visa



class VisaDevice(*com: Union[*VisaCommunication*, *VisaCommunicationConfig*, dict]*, *dev_config: Optional[Union[*VisaDeviceConfig*, dict]] = 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: Optional[float] = 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: Union[int, float] = 0.5*, *spoll_start_delay: Union[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

class MapBitAsymRange(*value: ~typing.Union[int, float], bit: int, dtype_1: ~typing.Union[~numpy.dtype, None, type, ~numpy.typing._dtype_like._SupportsDType[~numpy.dtype], str, ~typing.Tuple[~typing.Any, int], ~typing.Tuple[~typing.Any, ~typing.Union[~typing_extensions.SupportsIndex, ~typing.Sequence[~typing_extensions.SupportsIndex]]], ~typing.List[~typing.Any], ~numpy.typing._dtype_like._DTypeDict, ~typing.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: ~typing.Union[int, float], bit: int, dtype_1: ~typing.Union[~numpy.dtype, None, type, ~numpy.typing._dtype_like._SupportsDType[~numpy.dtype], str, ~typing.Tuple[~typing.Any, int], ~typing.Tuple[~typing.Any, ~typing.Union[~typing_extensions.SupportsIndex, ~typing.Sequence[~typing_extensions.SupportsIndex]]], ~typing.List[~typing.Any], ~numpy.typing._dtype_like._DTypeDict, ~typing.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).

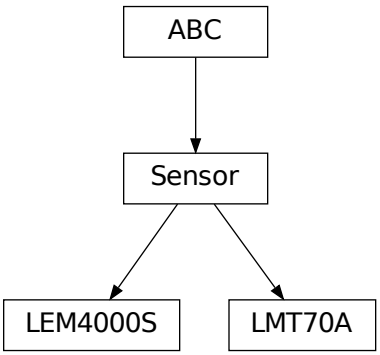
class MapRanges(*range_1: Tuple[Union[int, float], Union[int, float]], range_2: Tuple[Union[int, float], Union[int, float]], dtype_1: Union[dtype, None, type, _SupportsDType[dtype], str, Tuple[Any, int], Tuple[Any, Union[SupportsIndex, Sequence[SupportsIndex]]], List[Any], _DTypeDict, Tuple[Any, Any]], dtype_2: Union[dtype, None, type, _SupportsDType[dtype], str, Tuple[Any, int], Tuple[Any, Union[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*)

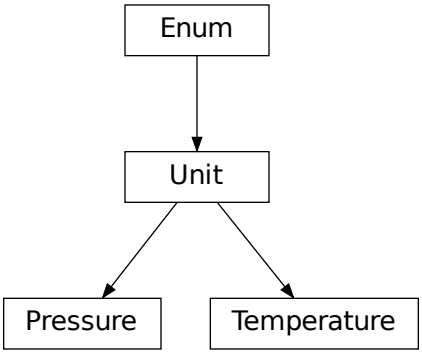
temperature_unit

class Sensor

Bases: ABC

abstract convert(*value*, ***kwargs*)

hvl_ccb.utils.conversion.unit



Unit conversion, within in the same group of units, for 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'

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'

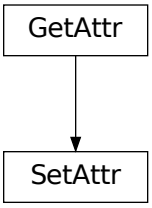
class Unit(*value*)

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]]*) → List[Union[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

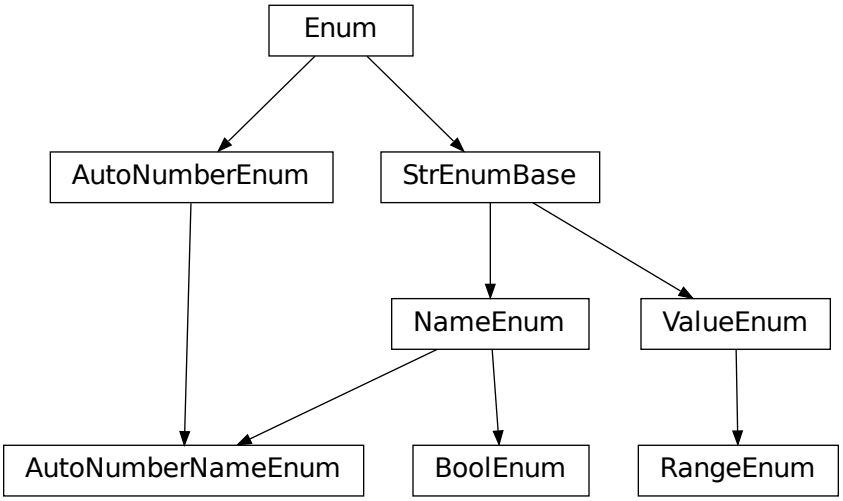
preserve_type(*func*)

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.typing

Additional Python typing module utilities

ConvertableTypes

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]`

Number

Typing hint auxiliary for a Python base number types: *int* or *float*.

alias of `Union[int, float]`

check_generic_type(*value*, *type_*, *name='instance'*)

Check if *value* is of a generic type *type_*. Raises *TypeError* if it's not.

Parameters

- **name** – name to report in case of an error
- **value** – value to check
- **type** – generic type to check against

is_generic_type_hint(*type_*)

Check if class is a generic type, for example *Union[int, float]*, *List[int]*, or *List*.

Parameters

type – type to check

hvl_ccb.utils.validation

validate_and_resolve_host(*host: Union[str, IPv4Address, IPv6Address]*, *logger: Optional[Logger] = None*) → str

validate_bool(*x_name: str*, *x: object*, *logger: Optional[Logger] = 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: ~typing.Optional[~typing.Tuple] = (None, None), number_type: ~typing.Union[~typing.Type[~typing.Union[int, float]], ~typing.Tuple[~typing.Type[~typing.Union[int, float]], ...]] = (<class 'int'>, <class 'float'>), logger: ~typing.Optional[~logging.Logger] = 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

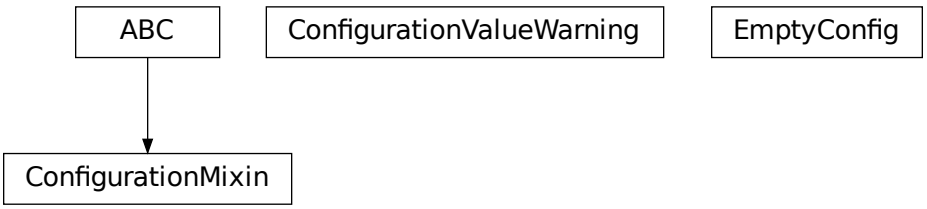
- **TypeError** – when the validated input does not have expected type
- **ValueError** – when the validated input has correct number type but is not within given range

validate_tcp_port(*port: int*, *logger: Optional[Logger] = 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*)

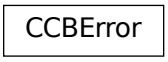
Decorator to make a class a configdataclass. Types in these dataclasses are enforced. Implement a function clean_values(self) to do additional checking on value ranges etc.

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

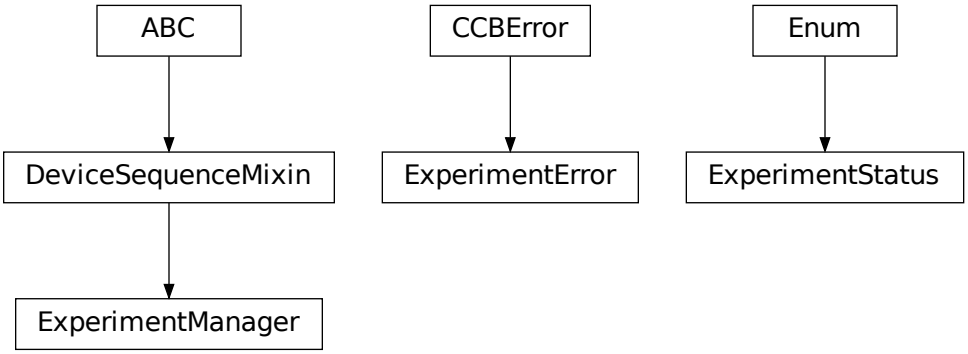


Introduce a common code base error for the CCB

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() → bool

Returns true, if the status of the experiment manager is *error*.

Returns

True if on error, false otherwise

is_finished() → bool

Returns true, if the status of the experiment manager is *finished*.

Returns

True if finished, false otherwise

is_running() → bool

Returns 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.

CHAPTER

FIVE

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. Install your local copy into a virtualenv. Assuming you have virtualenvwrapper installed, this is how you set up your fork for local development:

```
$ mkvirtualenv hvl_ccb
$ cd hvl_ccb/
$ pip install -e .[all]
$ pip install -r requirements_dev.txt
```

3. Create a branch for local development:

```
$ git checkout -b name-of-your-bugfix-or-feature
```

   Now you can make your changes locally.

4. When you're done making changes, check that your changes pass flake8, mypy and the tests, including testing other Python versions with tox:

```
$ 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 style
$ ./make.sh type
$ ./make.sh test
```

5. As we want to maintain a high quality of coding style we use *black*. 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.

6. Commit your changes and push your branch to GitLab:

```
$ git add .
$ git commit -m "Your detailed description of your changes."
$ git push origin name-of-your-bugfix-or-feature
```

7. Submit a 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 3.7 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 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:

```
$ bumpversion 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 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".

CHAPTER

SIX

CREDITS

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CHAPTER

SEVEN

HISTORY

7.1 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

7.2 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

7.3 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

7.4 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

7.5 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

7.6 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)

7.7 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`.

7.8 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.

7.9 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.

7.10 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.

7.11 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.

7.12 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.

7.13 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.

7.14 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.

7.15 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.

7.16 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.

7.17 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>=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`.

7.18 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 poling 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`.

7.19 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 Luminox 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.

7.20 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).

7.21 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.

7.22 0.3.3 (2019-05-08)

- Use PyPI labjack-ljm (no external dependencies)

7.23 0.3.2 (2019-05-08)

- INSTALLATION.rst with LJMPython prerequisite info

7.24 0.3.1 (2019-05-02)

- readthedocs.org support

7.25 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)

7.26 0.2.1 (2019-04-01)

- Fix issue with LJMPython not being installed automatically with setuptools.

7.27 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.

7.28 0.1.0 (2019-02-06)

- Communication protocol base and serial communication implementation.
- Device base and MBW973 implementation.

CHAPTER

EIGHT

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PYTHON MODULE INDEX

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