
HVL Common Code Base Documentation

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CONTENTS:

1	HVL Common Code Base	1
1.1	Features	1
1.2	Documentation	5
1.3	Credits	5
2	Installation	7
2.1	Stable release	7
2.2	From sources	7
2.3	Additional system libraries	8
3	Usage	9
4	API Documentation	11
4.1	hvl_ccb	11
5	Contributing	177
5.1	Types of Contributions	177
5.2	Get Started!	178
5.3	Merge Request Guidelines	179
5.4	Tips	179
5.5	Deploying	180
6	Credits	183
6.1	Active Maintainers	183
6.2	Authors and Contributors	183
7	History	185
7.1	0.13.1 (2023-03-03)	185
7.2	0.13.0 (2023-01-27)	185
7.3	0.12.3 (2022-12-27)	185
7.4	0.12.2 (2022-11-29)	186
7.5	0.12.1 (2022-10-31)	186
7.6	0.12.0 (2022-10-17)	186
7.7	0.11.1 (2022-09-15)	186
7.8	0.11.0 (2022-06-22)	187
7.9	0.10.3 (2022-03-21)	187
7.10	0.10.2 (2022-02-28)	187
7.11	0.10.1 (2022-01-24)	187
7.12	0.10.0 (2022-01-17)	188
7.13	0.9.0 (2022-01-07)	188
7.14	0.8.5 (2021-11-05)	189

7.15	0.8.4 (2021-10-22)	189
7.16	0.8.3 (2021-09-27)	189
7.17	0.8.2 (2021-08-27)	189
7.18	0.8.1 (2021-08-13)	190
7.19	0.8.0 (2021-07-02)	190
7.20	0.7.1 (2021-06-04)	190
7.21	0.7.0 (2021-05-25)	190
7.22	0.6.1 (2021-05-08)	191
7.23	0.6.0 (2021-04-23)	191
7.24	0.5.0 (2020-11-11)	192
7.25	0.4.0 (2020-07-16)	192
7.26	0.3.5 (2020-02-18)	193
7.27	0.3.4 (2019-12-20)	193
7.28	0.3.3 (2019-05-08)	193
7.29	0.3.2 (2019-05-08)	193
7.30	0.3.1 (2019-05-02)	194
7.31	0.3 (2019-05-02)	194
7.32	0.2.1 (2019-04-01)	194
7.33	0.2.0 (2019-03-31)	194
7.34	0.1.0 (2019-02-06)	194
8	Indices and tables	195
	Python Module Index	197
	Index	199

HVL COMMON CODE BASE

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

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

1.1 Features

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

1.1.1 Devices

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

Function/Type	Devices
Bench Multimeter	Fluke 8845A and 8846A 6.5 Digit Precision Multimeter
Data acquisition	LabJack (T4, T7, T7-PRO; requires LJM Library) Pico Technology PT-104 Platinum Resistance Data Logger (requires PicoSDK/libusbpt104)
Digital Delay Generator	Highland T560
Digital IO	LabJack (T4, T7, T7-PRO; requires LJM Library)
Experiment control	HVL Cube with and without Power Inverter
Gas Analyser	MBW 973-SF6 gas dew point mirror analyzer Pfeiffer Vacuum TPG (25x, 26x and 36x) controller for compact pressure gauges SST Luminox oxygen sensor
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	
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	<p>CryLaS pulsed laser and laser attenuator</p> <p>FuG Elektronik power supply (e.g. capacitor charger HCK) using the Probus V protocol</p> <p>Heinzinger PNC power supply using Heinzinger Digital Interface I/II</p> <p>SST Luminox oxygen sensor</p> <p>MBW 973-SF6 gas dew point mirror analyzer</p> <p>Newport SMC100PP single axis driver for 2-phase stepper motors</p> <p>Pfeiffer Vacuum TPG (25x, 26x and 36x) controller for compact pressure gauges</p> <p>Technix capacitor charger</p>
TCP	Lauda PRO RP 245 E circulation thermostat
Telnet	<p>Technix capacitor charger</p> <p>Fluke 8845A and 8846</p>
VISA TCP	<p>Elektro-Automatik PSI9000 DC power supply</p> <p>Rhode & Schwarz RTO 1024 oscilloscope</p>
<i>propriety</i>	<p>LabJack (T4, T7, T7-PRO) devices, which communicate via LJM Library</p> <p>Pico Technology PT-104 Platinum Resistance Data Logger, which communicate via PicoSDK/libusbpt104</p> <p>TiePie (HS5, HS6, WS5) oscilloscopes, generators and I2C hosts, which communicate via LibTiePie SDK</p>

1.1.3 Sensor and Unit Conversion Utility

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

Currently the following sensors are implemented:

- LEM LT 4000S
- LMT 70A

The following unit conversion classes are implemented:

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

1.2 Documentation

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

Do either:

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

or

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

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

and then either on Windows in Git BASH run:

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

or from any other shell with GNU Make installed run:

```
$ make docs
```

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

1.3 Credits

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

INSTALLATION

2.1 Stable release

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

```
$ pip install hvl_ccb
```

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

```
$ pip install "hvl_ccb[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
```


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[`hvl_ccb.comm.base.AsyncCommunicationProtocolConfig`]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

read() → str

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

Returns

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

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

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

Parameters

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

Returns

A multi-line *str* including the terminator internally

abstract read_bytes() → bytes

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

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

Returns

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

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

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

Returns

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

Parameters

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

read_text() → str

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

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

Returns

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

Raises

SerialCommunicationIOError – when communication port is not opened

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

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

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

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

Parameters

- **n_attempts_max** – maximum number of read attempts
- **attempt_interval_sec** – time between the reading attempts

Returns

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

write(*text*: str)

Write text as *str* to the communication.

Parameters

text – text as a *str* to be written

abstract write_bytes(*data*: bytes) → int

Write data as *bytes* to the communication.

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

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

number of bytes written

write_text(*text: str*)

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

NOTE: backward-compatibility proxy for *read* method; to be removed in v1.0**Parameters****text** – Text to send to the port.**Raises*****SerialCommunicationIOError*** – when communication port is not opened

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

Bases: object

Base configuration data class for asynchronous communication protocols

clean_values()**default_n_attempts_read_text_nonempty: int = 10**

default number of attempts to read a non-empty text

encoding: str = 'utf-8'Standard encoding of the connection. Typically this is *utf-8*, but can also be *latin-1* or something from here: <https://docs.python.org/3/library/codecs.html#standard-encodings>**encoding_error_handling: str = 'strict'**Encoding error handling scheme as defined here: <https://docs.python.org/3/library/codecs.html#error-handlers> By default strict error handling that raises *UnicodeError*.**force_value**(*fieldname, value*)

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

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

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

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

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

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

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

Returns

a list of strings containing all required keys.

terminator: bytes = b'\r\n'

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

wait_sec_read_text_nonempty: int | float = 0.5

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

exception **CommunicationError**

Bases: [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[[hvl_ccb.configuration.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[hvl_ccb.comm.base.SyncCommunicationProtocolConfig]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

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

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

Parameters

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

Returns

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

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

Bases: *AsyncCommunicationProtocolConfig*

Base configuration data class for synchronous communication protocols

hvl_ccb.comm.labjack_ljm

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

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

```
class LJMCommunication(configuration)
```

Bases: *CommunicationProtocol*

Communication protocol implementing the LabJack LJM Library Python wrapper.

close() → None

Close the communication port.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

property is_open: bool

Flag indicating if the communication port is open.

Returns

True if the port is open, otherwise False

open() → *None*

Open the communication port.

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

Read one or more input numeric values by name.

Parameters

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

Returns

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

Raises

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

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

Write one value to a named output.

Parameters

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

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

Write more than one value at once to named outputs.

Parameters

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

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

Bases: object

Configuration dataclass for *LJMCommunication*.

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

Bases: *AutoNumberNameEnum*

LabJack connection type.

ANY = 1

ETHERNET = 4

TCP = 3

USB = 2

WIFI = 5

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

Bases: *AutoNumberNameEnum*

LabJack device types.

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

ANY = 1

T4 = 2

T7 = 3

T7_PRO = 4

classmethod `get_by_p_id(p_id: int) → DeviceType | list[hvl_ccb._dev.labjack.DeviceType]`

Get LabJack device type instance via LabJack product ID.

Note: Product ID is not unambiguous for LabJack devices.

Parameters

p_id – Product ID of a LabJack device

Returns

Instance or list of instances of *LabJackDeviceType*

Raises

ValueError – when Product ID is unknown

clean_values() → *None*

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

connection_type: **str** | *ConnectionType* = 'ANY'

Can be either string or of enum *ConnectionType*.

device_type: **str** | *DeviceType* = 'ANY'

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

force_value(fieldname, value)

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

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

Parameters

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

identifier: **str** = 'ANY'

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

is_configdataclass = **True**

classmethod `keys() → Sequence[str]`

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

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

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

Returns

a list of strings containing all optional keys.

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

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

Returns

a list of strings containing all required keys.

exception **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: list[int] | int*)

Write values from the specified address forward.

Parameters

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

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

Bases: object

Configuration dataclass for *ModbusTcpCommunication*.

clean_values()

force_value(*fieldname, value*)

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

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

Parameters

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

host: *str | IPv4Address | IPv6Address*

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

port: *int = 502*

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

unit: *int*

exception ModbusTcpConnectionFailedError(*string=""*)

Bases: *ConnectionException, CommunicationError*

Error raised when the connection failed.

hvl_ccb.comm.opc

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

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

Bases: Client

disconnect()

get_objects_node()

Get Objects node of client. Returns a Node object.

property is_open

send_hello(*args, **kwargs)

class OpcUaCommunication(*config*)

Bases: *CommunicationProtocol*

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

close() → *None*

Close the connection to the OPC UA server.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

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

Initialize monitored nodes.

Parameters

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

Raises

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

property is_open: bool

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

Returns

True if the port is open, otherwise *False*

open() → *None*

Open the communication to the OPC UA server.

Raises

OpcUaCommunicationIOError – when communication port cannot be opened.

read(*node_id, ns_index*)

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

Parameters

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

Returns

the value of the node object.

Raises

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

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

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

Parameters

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

Raises

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

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

Bases: object

Configuration dataclass for OPC UA Communciation.

clean_values()

endpoint_name: str

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

force_value(*fieldname*, *value*)

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

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

Parameters

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

host: str | IPv4Address | IPv6Address

Hostname or IP-Address of the OPC UA server.

is_configdataclass = True

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

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

max_timeout_retry_nr: int = 5

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

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

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

Returns

a list of strings containing all optional keys.

port: int = 4840

Port of the OPC UA server to connect to.

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

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

Returns

a list of strings containing all required keys.

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

object to use for handling subscriptions.

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

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

wait_timeout_retry_sec: int | float = 1

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

exception **OpcUaCommunicationIOError**

Bases: OSError, *CommunicationError*

OPC-UA communication I/O error.

exception **OpcUaCommunicationTimeoutError**

Bases: *OpcUaCommunicationIOError*

OPC-UA communication timeout error.

class **OpcUaSubHandler**

Bases: object

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

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

datachange_notification(*node, val, data*)

event_notification(*event*)

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

Bases: `Server`

get_objects_node()

Get Objects node of server. Returns a Node object.

hvl_ccb.comm.serial

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

class SerialCommunication(*configuration*)

Bases: `AsyncCommunicationProtocol`

Implements the Communication Protocol for serial ports.

close()

Close the serial connection.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

property is_open: bool

Flag indicating if the serial port is open.

Returns

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

open()

Open the serial connection.

Raises

`SerialCommunicationIOError` – when communication port cannot be opened.

read_bytes() → bytes

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

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

Returns

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

Raises

`SerialCommunicationIOError` – when communication port is not opened

read_single_bytes(*size: int = 1*) → bytes

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

Returns

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

write_bytes(*data: bytes*) → int

Write bytes to the serial port.

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

Parameters

data – data to write to the serial port

Returns

number of bytes written

Raises

[*SerialCommunicationIOError*](#) – when communication port is not opened

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

Bases: [*ValueEnum*](#)

Serial communication bytesize.

EIGHTBITS = 8

FIVEBITS = 5

SEVENBITS = 7

SIXBITS = 6

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

Bases: [*AsyncCommunicationProtocolConfig*](#)

Configuration dataclass for [*SerialCommunication*](#).

Bytesize

alias of [*SerialCommunicationBytesize*](#)

Parity

alias of [*SerialCommunicationParity*](#)

Stopbits

alias of [*SerialCommunicationStopbits*](#)

baudrate: int = 9600

Baudrate of the serial port

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

Size of a byte, 5 to 8

clean_values()

create_serial_port() → Serial

Create a serial port instance according to specification in this configuration

Returns

Closed serial port instance

force_value(fieldname, value)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

parity: str | *SerialCommunicationParity* = 'N'

Parity to be used for the connection.

port: str | *None* = None

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

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

stopbits: int | float | *SerialCommunicationStopbits* = 1

Stopbits setting, can be 1, 1.5 or 2.

terminator_str() → str

timeout: int | float = 2

Timeout in seconds for the serial port

exception *SerialCommunicationIOError*

Bases: *OSError*, *CommunicationError*

Serial communication related I/O errors.

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

Bases: *ValueEnum*

Serial communication parity.

EVEN = 'E'

MARK = 'M'

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

NONE = 'N'

ODD = 'O'

SPACE = 'S'

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

Bases: *ValueEnum*

Serial communication stopbits.

ONE = 1

ONE_POINT_FIVE = 1.5

TWO = 2

hvl_ccb.comm.tcp

TCP communication protocol. Makes use of the socket library.

```
class Tcp(configuration)
```

Bases: *CommunicationProtocol*

Tcp Communication Protocol.

close() → *None*

Close TCP connection.

static config_cls() → type[*hvl_ccb.comm.tcp.TcpCommunicationConfig*]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

open() → *None*

Open TCP connection.

read() → str

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

write(command: str = "") → *None*

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

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

Bases: object

Configuration dataclass for TcpCommunication.

```
bufsize:  int = 1024
```

```
clean_values()
```

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

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

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

Parameters

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

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

```
is_configdataclass = True
```

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

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

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

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

Returns

a list of strings containing all optional keys.

```
port:  int = 54321
```

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

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

Returns

a list of strings containing all required keys.

hvl_ccb.comm.telnet

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

```
class TelnetCommunication(configuration)
```

Bases: [AsyncCommunicationProtocol](#)

Implements the Communication Protocol for telnet.

```
close()
```

Close the telnet connection unless it is not closed.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

property is_open: bool

Is the connection open?

Returns

True for an open connection

open()

Open the telnet connection unless it is not yet opened.

read_bytes() → bytes

Read data as *bytes* from the telnet connection.

Returns

data from telnet connection

Raises

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

write_bytes(data: bytes)

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

Parameters

data – Data to be sent.

Raises

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

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

Bases: **AsyncCommunicationProtocolConfig**

Configuration dataclass for **TelnetCommunication**.

clean_values()

create_telnet() → Telnet | *None*

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

force_value(fieldname, value)

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

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

Parameters

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

host: str | IPv4Address | IPv6Address | None = None

Host to connect to can be localhost or

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

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

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

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

Returns

a list of strings containing all optional keys.

port: **int** = **0**

Port at which the host is listening

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

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

Returns

a list of strings containing all required keys.

timeout: **int** | **float** = **0.2**

Timeout for reading a line

exception **TelnetError**

Bases: `OSError`, `CommunicationError`

Telnet communication related errors.

hvl_ccb.comm.visa

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

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

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

class **VisaCommunication**(*configuration*)

Bases: `CommunicationProtocol`

Implements the Communication Protocol for VISA / SCPI.

MULTI_COMMANDS_MAX = **5**

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

MULTI_COMMANDS_SEPARATOR = **' ; '**

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

WAIT_AFTER_WRITE = **0.08**

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

close() → *None*

Close the VISA connection and invalidates the handle.

static config_cls() → type[hvl_ccb.comm.visa.VisaCommunicationConfig]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

open() → *None*

Open the VISA connection and create the resource.

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

A combination of write(message) and read.

Parameters

commands – list of commands

Returns

list of values

Raises

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

spoll() → int

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

Returns

integer representation of the status byte

Raises

VisaCommunicationError – when connection was not started

write(*commands: str) → *None*

Write commands. No answer is read or expected.

Parameters

commands – one or more commands to send

Raises

VisaCommunicationError – when connection was not started

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

Bases: object

VisaCommunication configuration dataclass.

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

Bases: [AutoNumberNameEnum](#)

Supported VISA Interface types.

TCPIP_INSTR = 2

VXI-11 protocol

TCPIP_SOCKET = 1

VISA-RAW protocol

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

Address string specific to the VISA interface type.

Parameters

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

Returns

address string

property address: str

Address string depending on the VISA protocol's configuration.

Returns

address string corresponding to current configuration

board: int = 0

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

chunk_size: int = 204800

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

clean_values()

force_value(*fieldname*, *value*)

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

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

Parameters

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

host: str | IPv4Address | IPv6Address

interface_type: str | *InterfaceType*

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

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

open_timeout: int = 1000

Timeout for opening the connection, in milli seconds.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

port: `int = 5025`

TCP port, standard is 5025.

read_termination: `str = '\n'`

Read termination character.

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

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

Returns

a list of strings containing all required keys.

timeout: `int = 5000`

Timeout for commands in milli seconds.

visa_backend: `str = ''`

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

write_termination: `str = '\n'`

Write termination character.

exception `VisaCommunicationError`

Bases: `OSError`, `CommunicationError`

Base class for VisaCommunication errors.

Module contents

Communication protocols subpackage.

`hvl_ccb.dev`

Subpackages

`hvl_ccb.dev.crylas`

Submodules

`hvl_ccb.dev.crylas.crylas`

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

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

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

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

class CryLasAttenuator(*com, dev_config=None*)

Bases: *SingleCommDevice*

Device class for the CryLas laser attenuator.

property attenuation: *int | float*

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

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

Returns

the type of the standard communication protocol for this device

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

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

set_init_attenuation()

Sets the attenuation to its configured initial/default value

Raises

SerialCommunicationIOError – when communication port is not opened

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

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

start() → *None*

Open the com, apply the config value 'init_attenuation'

Raises

SerialCommunicationIOError – when communication port cannot be opened

property transmission: *int | float*

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

Bases: *object*

Device configuration dataclass for CryLas attenuator.

clean_values()

force_value(*fieldname, value*)

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

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

Parameters

- **fieldname** – name of the field

- **value** – value to assign

init_attenuation: `int | float = 0`

is_configdataclass = `True`

classmethod keys() → `Sequence[str]`

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

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

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

Returns

a list of strings containing all optional keys.

classmethod required_keys() → `Sequence[str]`

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

Returns

a list of strings containing all required keys.

response_sleep_time: `int | float = 1`

exception CryLasAttenuatorError

Bases: *DeviceError*

General error with the CryLas Attenuator.

class CryLasAttenuatorSerialCommunication(*configuration*)

Bases: *SerialCommunication*

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

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

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

Bases: *SerialCommunicationConfig*

baudrate: `int = 9600`

Baudrate for CryLas attenuator is 9600 baud

bytesize: `int | SerialCommunicationBytesize = 8`

One byte is eight bits long

force_value(*fieldname*, *value*)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

parity: `str | SerialCommunicationParity = 'N'`

CryLas attenuator does not use parity

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

stopbits: `int | SerialCommunicationStopbits = 1`

CryLas attenuator uses one stop bit

terminator: `bytes = b''`

No terminator

timeout: `int | float = 3`

use 3 seconds timeout as default

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

Bases: *SingleCommDevice*

CryLas laser controller device class.

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

Bases: Enum

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

CLOSED = 'Shutter inaktiv'

OPENED = 'Shutter aktiv'

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

Bases: Enum

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

ACTIVE = 'STATUS: Laser active'

HEAD = 'STATUS: Head ok'

INACTIVE = 'STATUS: Laser inactive'

READY = 'STATUS: System ready'

TEC1 = 'STATUS: TEC1 Regulation ok'

TEC2 = 'STATUS: TEC2 Regulation ok'

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

Bases: Enum

Status of the CryLas laser

READY_ACTIVE = 2

READY_INACTIVE = 1

UNREADY_INACTIVE = 0

property is_inactive

property is_ready

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

Bases: IntEnum

Repetition rates for the internal software trigger in Hz

HARDWARE = 0

SOFTWARE_INTERNAL_SIXTY = 60

SOFTWARE_INTERNAL_TEN = 10

SOFTWARE_INTERNAL_TWENTY = 20

ShutterStatus

alias of [CryLasLaserShutterStatus](#)

close_shutter() → *None*

Close the laser shutter.

Raises

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

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

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

Returns

the type of the standard communication protocol for this device

get_pulse_energy_and_rate() → tuple[int, int]

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

Returns

(energy in micro joule, rate in Hz)

Raises

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

laser_off() → *None*

Turn the laser off.

Raises

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

laser_on() → *None*

Turn the laser on.

Raises

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

open_shutter() → *None*

Open the laser shutter.

Raises

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

set_init_shutter_status() → *None*

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

Raises

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

set_pulse_energy(energy: int) → *None*

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

Parameters

energy – energy in micro joule

Raises

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

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

Sets the repetition rate of the internal software trigger.

Parameters

rate – frequency (Hz) as an integer

Raises

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

start() → *None*

Opens the communication protocol and configures the device.

Raises

SerialCommunicationIOError – when communication port cannot be opened

stop() → *None*

Stops the device and closes the communication protocol.

Raises

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

property target_pulse_energy

update_laser_status() → *None*

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

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

Raises

SerialCommunicationIOError – when communication port is not opened

update_repetition_rate() → *None*

Query the laser repetition rate.

Raises

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

update_shutter_status() → *None*

Update the shutter status (OPENED or CLOSED)

Raises

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

update_target_pulse_energy() → *None*

Query the laser pulse energy.

Raises

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

wait_until_ready() → *None*

Block execution until the laser is ready

Raises

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

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

Bases: object

Device configuration dataclass for the CryLas laser controller.

ShutterStatus

alias of ***CryLasLaserShutterStatus***

auto_laser_on: bool = True

calibration_factor: int | float = 4.35

clean_values()

force_value(fieldname, value)

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

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

Parameters

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

init_shutter_status: int | ***CryLasLaserShutterStatus*** = 0

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

polling_period: int | float = 12

polling_timeout: int | float = 300

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

exception CryLasLaserError

Bases: *DeviceError*

General error with the CryLas Laser.

exception CryLasLaserNotReadyError

Bases: *CryLasLaserError*

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

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

Bases: *Poller*

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

Raises

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

class CryLasLaserSerialCommunication(*configuration*)

Bases: *SerialCommunication*

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

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

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

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

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

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

Parameters

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

Returns

line in question as a string

Raises

SerialCommunicationIOError – when communication port is not opened

query_all(cmd: str, prefix: str)

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

Parameters

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

Returns

line in question as a string

Raises

SerialCommunicationIOError – when communication port is not opened

read() → str

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

Returns

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

Raises

SerialCommunicationIOError – when communication port is not opened

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

Bases: *SerialCommunicationConfig*

baudrate: `int = 19200`

Baudrate for CryLas laser is 19200 baud

bytesize: `int | SerialCommunicationBytesize = 8`

One byte is eight bits long

force_value(*fieldname*, *value*)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

parity: `str | SerialCommunicationParity = 'N'`

CryLas laser does not use parity

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

stopbits: `int | SerialCommunicationStopbits = 1`

CryLas laser uses one stop bit

terminator: `bytes = b'\n'`

The terminator is LF

timeout: `int | float = 10`

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

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

Bases: Enum

Status of the CryLas laser shutter

CLOSED = 0

OPENED = 1

Module contents

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

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

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

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

hvl_ccb.dev.cube

Submodules

hvl_ccb.dev.cube.alarms

Alarms of the different “Cubes”.

hvl_ccb.dev.cube.base

Classes for the BaseCube device.

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

Bases: *SingleCommDevice*

Base class for Cube variants.

OPC_MAX_YEAR = 2089

OPC_MIN_YEAR = 1990

active_alarms(*human_readable: bool = True*) → list[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: `bool` | *None*

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

Returns

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

quit_error() → *None*

Quits errors that are active on the Cube.

read(node_id: str)

Local wrapper for the OPC UA communication protocol read method.

Parameters

node_id – the id of the node to read.

Returns

the value of the variable

property ready: `bool` | *None*

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

Returns

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

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

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

Parameters

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

Raises

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

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

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

Parameters

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

Raises

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

start() → *None*

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

property status: *SafetyStatus*

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

Returns

the safety status of the Cube's state machine.

stop() → *None*

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

Raises

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

t13_socket_1

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

t13_socket_2

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

t13_socket_3

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

write(node_id, value) → *None*

Local wrapper for the OPC UA communication protocol write method.

Parameters

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

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

Bases: object

Configuration dataclass for the BaseCube devices.

clean_values()

force_value(fieldname, value)

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

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

Parameters

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

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

namespace_index: `int = 3`

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

noise_level_measurement_channel_1: `int | float = 100`

noise_level_measurement_channel_2: `int | float = 100`

noise_level_measurement_channel_3: `int | float = 100`

noise_level_measurement_channel_4: `int | float = 100`

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

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

Returns

a list of strings containing all optional keys.

polling_delay_sec: `int | float = 5.0`

polling_interval_sec: `int | float = 1.0`

classmethod required_keys() `→ Sequence[str]`

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

Returns

a list of strings containing all required keys.

timeout_interval: `int | float = 0.1`

timeout_status_change: `int | float = 6`

class BaseCubeOpcUaCommunication(*config*)

Bases: *OpcUaCommunication*

Communication protocol specification for BaseCube devices.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

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

Bases: *OpcUaCommunicationConfig*

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

endpoint_name: `_CubeOpcEndpoint = 'BaseCube'`

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

force_value(*fieldname*, *value*)

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

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

Parameters

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

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

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

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

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

Returns

a list of strings containing all optional keys.

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

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

Returns

a list of strings containing all required keys.

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

Subscription handler for data change events

hvl_ccb.dev.cube.constants

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

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

Bases: IntEnum

Possible status values for doors.

CLOSED = 2

Door is closed, but not locked.

ERROR = 4

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

INACTIVE = 0

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

LOCKED = 3

Door is closed and locked (safe state).

OPEN = 1

Door is open.

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

Bases: IntEnum

Possible status values for earthing rods.

EXPERIMENT_BLOCKED = 0

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

EXPERIMENT_READY = 1

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

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

Bases: _LineEnumBase

Variable NodeID strings for message board lines.

LINE_1 = "DB_OPC_Connection"."Is_status_Line_1"

LINE_10 = "DB_OPC_Connection"."Is_status_Line_10"

LINE_11 = "DB_OPC_Connection"."Is_status_Line_11"

LINE_12 = "DB_OPC_Connection"."Is_status_Line_12"

LINE_13 = "DB_OPC_Connection"."Is_status_Line_13"

LINE_14 = "DB_OPC_Connection"."Is_status_Line_14"

LINE_15 = "DB_OPC_Connection"."Is_status_Line_15"

LINE_2 = "DB_OPC_Connection"."Is_status_Line_2"

LINE_3 = "DB_OPC_Connection"."Is_status_Line_3"

LINE_4 = "DB_OPC_Connection"."Is_status_Line_4"

LINE_5 = "DB_OPC_Connection"."Is_status_Line_5"

LINE_6 = "DB_OPC_Connection"."Is_status_Line_6"

LINE_7 = "DB_OPC_Connection"."Is_status_Line_7"

LINE_8 = "DB_OPC_Connection"."Is_status_Line_8"

LINE_9 = "DB_OPC_Connection"."Is_status_Line_9"

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

Bases: IntEnum

An enumeration.

NEGATIVE = 0

POSITIVE = 1

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

Bases: IntEnum

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

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

AC_100KV = 3

AC_150KV = 4

AC_200KV = 5

AC_50KV = 2

DC_140KV = 7

DC_280KV = 8

EXTERNAL_SOURCE = 1

IMPULSE_140KV = 9

NO_SOURCE = 0

POWER_INVERTER_220V = 6

```
STOP_SAFETY_STATUSES: tuple[hvl_ccb.dev.cube.constants.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.earthing_stick`

EarthingStick of the different “Cubes”.

```
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 or 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
```

`hvl_ccb.dev.cube.errors`

Errors of the different “Cubes”.

```
exception CubeEarthingStickOperationError
```

Bases: `CubeError`

```
exception CubeError
```

Bases: `DeviceError`

```
exception CubeRemoteControlError
```

Bases: `CubeError`

exception `CubeStatusChangeError`

Bases: `CubeError`

exception `CubeStopError`

Bases: `CubeError`

exception `PICubeTestParameterError`

Bases: `CubeError`

`hvl_ccb.dev.cube.picube`

A PICube is a BaseCube with build in Power Inverter

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

Bases: `BaseCube`

Variant of the BaseCube with build in Power Inverter

static `config_cls()`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

property `current_primary: float`

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

Returns

primary current in A

static `default_com_cls()`

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

Returns

the type of the standard communication protocol for this device

property `frequency: float`

Read the electrical frequency of the current PICube setup.

Returns

the frequency in Hz

property `operate: bool | None`

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

Returns

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

property `polarity: Polarity | None`

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

property `power_setup: PowerSetup`

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

Returns

the power setup

property voltage_actual: float

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

Returns

the actual voltage of the setup in V.

property voltage_max: float

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

Returns

the maximum voltage of the setup in V.

property voltage_primary: float

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

Returns

primary voltage in V

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

Bases: [BaseCubeConfiguration](#)

clean_values()

force_value(fieldname, value)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

```
timeout_test_parameters: int | float = 2.0
```

```
class PICubeOpcUaCommunication(config)
```

Bases: [BaseCubeOpcUaCommunication](#)

```
static config_cls()
```

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class PICubeOpcUaCommunicationConfig(host: Union[str, ipaddress.IPv4Address, ipaddress.IPv6Address],
                                     endpoint_name: '_CubeOpcEndpoint' =
                                     <_CubeOpcEndpoint.PI_CUBE: 'PICube'>, port: int = 4840,
                                     sub_handler: hvl_ccb.comm.opc.OpcUaSubHandler =
                                     <hvl_ccb.dev.cube.base._BaseCubeSubscriptionHandler object at
                                     0x7f4249c2b430>, update_parameter:
                                     asyncua.ua.uaproto.protocol_auto.CreateSubscriptionParameters =
                                     CreateSubscriptionParameters(RequestedPublishingInterval=1000,
                                     RequestedLifetimeCount=300, RequestedMaxKeepAliveCount=22,
                                     MaxNotificationsPerPublish=10000, PublishingEnabled=True,
                                     Priority=0), wait_timeout_retry_sec: Union[int, float] = 1,
                                     max_timeout_retry_nr: int = 5)
```

Bases: [BaseCubeOpcUaCommunicationConfig](#)

```
endpoint_name: _CubeOpcEndpoint = 'PICube'
```

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

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

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

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

Parameters

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

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

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

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

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

Returns

a list of strings containing all optional keys.

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

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

Returns

a list of strings containing all required keys.

hvl_ccb.dev.cube.support

Supports of the different “Cubes”.

Module contents

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

hvl_ccb.dev.ea_psi9000

Submodules

hvl_ccb.dev.ea_psi9000.ea_psi9000

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

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

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

Bases: [VisaDevice](#)

Elektro Automatik PSI 9000 power supply.

MS_NOMINAL_CURRENT = 2040

MS_NOMINAL_VOLTAGE = 80

SHUTDOWN_CURRENT_LIMIT = 0.1

SHUTDOWN_VOLTAGE_LIMIT = 0.1

check_master_slave_config() → *None*

Checks if the master / slave configuration and initializes if successful

Raises

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

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

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

Returns

the VisaCommunication class

get_output() → bool

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

Returns

the state of the DC output

get_system_lock() → bool

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

Returns

the current lock state of the device

get_ui_lower_limits() → tuple[float, float]

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

Returns

Umin in V, Imin in A

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

Get the upper voltage, current and power limits.

Returns

Umax in V, Imax in A, Pmax in W

get_voltage_current_setpoint() → tuple[float, float]

Get the voltage and current setpoint of the current source.

Returns

Uset in V, Iset in A

measure_voltage_current() → tuple[float, float]

Measure the DC output voltage and current

Returns

Umeas in V, Imeas in A

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

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

Parameters

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

Raises

PSI9000Error – if the limits are out of range

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

Enables / disables the DC output.

Parameters

target_onstate – enable or disable the output power

Raises

PSI9000Error – if operation was not successful

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

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

Parameters

lock – True: locking, False: unlocking

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

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

Parameters

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

Raises

PSI9000Error – if limits are out of range

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

Set voltage and current setpoints.

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

Parameters

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

Raises

PSI9000Error – if the desired setpoint is out of limits

start() → *None*

Start this device.

stop() → *None*

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

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

Bases: *VisaDeviceConfig*

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

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

clean_values() → *None*

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

current_lower_limit: int | float = 0.0

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

current_upper_limit: int | float = 2040.0

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

force_value(*fieldname*, *value*)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

power_limit: int | float = 43500

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

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

voltage_lower_limit: int | float = 0.0

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

voltage_upper_limit: int | float = 10.0

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

wait_sec_initialisation: int | float = 2

wait_sec_settings_effect: int | float = 1

wait_sec_system_lock: int | float = 0.5

exception PSI9000Error

Bases: *DeviceError*

Base error class regarding problems with the PSI 9000 supply.

class PSI9000VisaCommunication(*configuration*)

Bases: *VisaCommunication*

Communication protocol used with the PSI 9000 power supply.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

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

Bases: *VisaCommunicationConfig*

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

force_value(fieldname, value)

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

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

Parameters

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

interface_type: str | *InterfaceType* = 1

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

Module contents

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)

`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[hvl_ccb.dev.fluke884x.base.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[hvl_ccb.dev.fluke884x.base.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*, *n_attempts_max: int* | *None* = *None*, *attempt_interval_sec: int* | *float* | *None* = *None*)
→ *str*

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

Parameters

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

Raises

Fluke8845aError – if the connection is broken

Returns

Answer from the interface

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

Bases: *TelnetCommunicationConfig*

force_value(*fieldname*, *value*)

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

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

Parameters

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

classmethod keys() → *Sequence[str]*

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

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

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

Returns

a list of strings containing all optional keys.

port: `int = 3490`

Port at which Fluke 8845a is listening

classmethod `required_keys()` → Sequence[str]

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

Returns

a list of strings containing all required keys.

terminator: `bytes = b'\r'`

The terminator is CR

hvl_ccb.dev.fluke884x.constants

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

exception `Fluke8845aCheckError`

Bases: *Fluke8845aError*

exception `Fluke8845aError`

Bases: *DeviceError*

exception `Fluke8845aUnknownCommandError`

Bases: *Fluke8845aError*

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

Bases: *ValueEnum*

Page 40

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

`CURRENT_AC = 'CURR:AC'`

`CURRENT_DC = 'CURR'`

`DIODE = 'DIOD'`

`FOUR_WIRE_RESISTANCE = 'FRES'`

`FREQUENCY = 'FREQ'`

`PERIOD = 'PER'`

`TWO_WIRE_RESISTANCE = 'RES'`

`VOLTAGE_AC = 'VOLT:AC'`

`VOLTAGE_DC = 'VOLT'`

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

Bases: [ValueEnum](#)

Page 57

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

```
BUS = 'BUS'
```

```
EXTERNAL = 'EXT'
```

```
IMMEDIATE = 'IMM'
```

[hvl_ccb.dev.fluke884x.ranges](#)

Ranges, RangeEnum for Fluke8845a device

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

Bases: [RangeEnum](#)

possible measurement ranges for AC current with unit Ampere

```
FOUR_HUNDRED_MILLI_AMPERE = 0.4
```

```
ONE_AMPERE = 1.0
```

```
ONE_HUNDRED_MILLI_AMPERE = 0.1
```

```
TEN_AMPERE = 10.0
```

```
TEN_MILLI_AMPERE = 0.01
```

```
THREE_AMPERE = 3.0
```

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

Bases: [RangeEnum](#)

possible measurement ranges for AC voltage with unit volt

```
HUNDRED_VOLT = 100.0
```

```
ONE_HUNDRED_MILLI_VOLT = 0.1
```

```
ONE_VOLT = 1.0
```

```
SEVEN_HUNDRED_FIFTY_VOLT = 750.0
```

```
TEN_VOLT = 10.0
```

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

Bases: [RangeEnum](#)

Page 46

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

10ms = 4 1/2 digits

100ms = 5 1/2 digits

1s = 6 1/2 digits

ONE_HUNDRED_MILLI_SECOND = 0.1

ONE_SECOND = 1.0

TEN_MILLI_SECOND = 0.01

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

Bases: [RangeEnum](#)

possible measurement ranges for DC current with unit Ampere

FOUR_HUNDRED_MILLI_AMPERE = 0.4

ONE_AMPERE = 1.0

ONE_HUNDRED_MICRO_AMPERE = 0.0001

ONE_HUNDRED_MILLI_AMPERE = 0.1

ONE_MILLI_AMPERE = 0.001

TEN_AMPERE = 10.0

TEN_MILLI_AMPERE = 0.01

THREE_AMPERE = 3.0

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

Bases: [RangeEnum](#)

possible measurement ranges for DC voltage with unit volt

HUNDRED_VOLT = 100.0

ONE_HUNDRED_MILLI_VOLT = 0.1

ONE_THOUSAND_VOLT = 1000.0

ONE_VOLT = 1.0

TEN_VOLT = 10.0

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

Bases: [RangeEnum](#)

Page 47

```

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

```

```
FAST_FILTER = 200.0
```

```
MEDIUM_FILTER = 20.0
```

```
SLOW_FILTER = 3.0
```

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

Bases: *RangeEnum*

possible measurement ranges for resistance with unit Ohm

```
ONE_HUNDRED_MILLION_OHM = 100000000.0
```

```
ONE_HUNDRED_OHM = 100.0
```

```
ONE_HUNDRED_THOUSAND_OHM = 100000.0
```

```
ONE_MILLION_OHM = 1000000.0
```

```
ONE_THOUSAND_OHM = 1000.0
```

```
TEN_MILLION_OHM = 10000000.0
```

```
TEN_THOUSAND_OHM = 10000.0
```

Module contents

Fluke 8845A multimeter implementation using Telnet communication

hvl_ccb.dev.fug

Submodules

hvl_ccb.dev.fug.fug

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

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

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

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

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

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 typical 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`: `int` | `float`

Returns the maximal current which could be provided within the test setup

Returns

property `max_current_hardware`: `int` | `float`

Returns the maximal current which could be provided with the power supply

Returns

property `max_voltage`: `int` | `float`

Returns the maximal voltage which could be provided within the test setup

Returns

property `max_voltage_hardware`: `int` | `float`

Returns the maximal voltage which could be provided with the power supply

Returns

property on: *FuGProbusVDORegisters*

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

Returns

FuGProbusVDORegisters

property outX0: *FuGProbusVDORegisters*

Returns the registers for the digital output X0

Returns

FuGProbusVDORegisters

property outX1: *FuGProbusVDORegisters*

Returns the registers for the digital output X1

Returns

FuGProbusVDORegisters

property outX2: *FuGProbusVDORegisters*

Returns the registers for the digital output X2

Returns

FuGProbusVDORegisters

property outXCMD: *FuGProbusVDORegisters*

Returns the registers for the digital outputX-CMD

Returns

FuGProbusVDORegisters

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

Opens the communication protocol and configures the device.

Parameters

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

property voltage: *FuGProbusVSetRegisters*

Returns the registers for the voltage output

Returns

property voltage_monitor: *FuGProbusVMonitorRegisters*

Returns the registers for the voltage monitor.

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

Returns

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

Bases: object

Device configuration dataclass for FuG power supplies.

clean_values()

force_value(*fieldname*, *value*)

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

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

Parameters

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

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

wait_sec_stop_commands: int | float = 0.5

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

class FuGDigitalVal(*value*)

Bases: IntEnum

An enumeration.

NO = 0

OFF = 0

ON = 1

YES = 1

exception FuGError(**args*, ***kwargs*)

Bases: *DeviceError*

Error with the FuG voltage source.

errorcode: str

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

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

Bases: *NameEnum*

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

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

```
raise_()
```

```
class FuGMonitorModes(value)
```

```
    Bases: IntEnum
```

```
    An enumeration.
```

```
    T1MS = 1
```

```
        15 bit + sign, 1 ms integration time
```

```
    T200MS = 6
```

```
        typ. 19 bit + sign, 200 ms integration time
```

```
    T20MS = 3
```

```
        17 bit + sign, 20 ms integration time
```

```
    T256US = 0
```

```
        14 bit + sign, 256 us integration time
```

```
    T40MS = 4
```

```
        17 bit + sign, 40 ms integration time
```

```
    T4MS = 2
```

```
        15 bit + sign, 4 ms integration time
```

```
    T800MS = 7
```

```
        typ. 20 bit + sign, 800 ms integration time
```

```
    T80MS = 5
```

```
        typ. 18 bit + sign, 80 ms integration time
```

```
class FuGPolarities(value)
```

Bases: `IntEnum`

An enumeration.

NEGATIVE = 1

POSITIVE = 0

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

Bases: `SingleCommDevice`, `ABC`

FuG Probus IV device class

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

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

Parameters

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

Returns

a String if a query was performed

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

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

Returns

the type of the standard communication protocol for this device

output_off() → *None*

Switch DC voltage output off.

reset() → *None*

Reset of the interface: All setvalues are set to zero

abstract start()

Open the associated communication protocol.

stop() → *None*

Close the associated communication protocol.

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

Bases: `NameEnum`

An enumeration.

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

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

EXECUTE = ('X', None)

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

Wait for “X” to execute pending commands

ID = ('*IDN?', None)

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

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

QUERY = ('?', None)

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

RESET = ('=', None)

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

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

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

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

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

Bases: [FuGProbusIV](#)

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

get_register(*register: str*) → str

get the value from a register

Parameters

register – the register from which the value is requested

Returns

the value of the register as a String

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

generic method to set value to register

Parameters

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

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

Bases: object

Configuration and Status values, acc. 4.2.5

property execute_on_x: [FuGDigitalVal](#)

status of Execute-on-X

Returns

FuGDigitalVal of the status

property most_recent_error: *FuErrorcodes*

Reads the Error-Code of the most recent command

Return *FuGError*

Raises

FuGError – if code is not “E0”

property readback_data: *FuGReadbackChannels*

Preselection of readout data for Trigger-on-Talk

Returns

index for the readback channel

property srq_mask: *int*

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

Returns

representative integer value

property srq_status: *str*

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

Returns

representative string

property status: *str*

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

Returns

string of 0/1

property terminator: *FuGTerminators*

Terminator character for answer strings from ADDA

Returns

FuGTerminators

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

Bases: object

Digital Inputs acc. 4.2.4

property analog_control: *FuGDigitalVal*

Returns

shows 1 if power supply is controlled by the analog interface

property calibration_mode: *FuGDigitalVal*

Returns

shows 1 if power supply is in calibration mode

property cc_mode: *FuGDigitalVal*

Returns

shows 1 if power supply is in CC mode

property `cv_mode`: *FuGDigitalVal*

Returns

shows 1 if power supply is in CV mode

property `digital_control`: *FuGDigitalVal*

Returns

shows 1 if power supply is digitally controlled

property `on`: *FuGDigitalVal*

Returns

shows 1 if power supply ON

property `reg_3`: *FuGDigitalVal*

For special applications.

Returns

input from bit 3-REG

property `x_stat`: *FuGPolarities*

Returns

polarity of HVPS with polarity reversal

class `FuGProbusVDORegisters`(*fug*, *super_register*: *FuGProbusVRegisterGroups*)

Bases: object

Digital outputs acc. 4.2.2

property `out`: `int` | *FuGDigitalVal*

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

Returns

FuGDigitalVal

property `status`: *FuGDigitalVal*

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

Returns

FuGDigitalVal

class `FuGProbusVMonitorRegisters`(*fug*, *super_register*: *FuGProbusVRegisterGroups*)

Bases: object

Analog monitors acc. 4.2.3

property `adc_mode`: *FuGMonitorModes*

The programmed resolution and integration time of the AD converter

Returns

FuGMonitorModes

property `value`: `float`

Value from the monitor.

Returns

a float value in V or A

property value_raw: float

uncalibrated raw value from AD converter

Returns

float value from ADC

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

Bases: [NameEnum](#)

An enumeration.

CONFIG = 'K'

INPUT = 'D'

MONITOR_I = 'M1'

MONITOR_V = 'M0'

OUTPUTONCMD = 'BON'

OUTPUTX0 = 'B0'

OUTPUTX1 = 'B1'

OUTPUTX2 = 'B2'

OUTPUTXCMD = 'BX'

SETCURRENT = 'S1'

SETVOLTAGE = 'S0'

class FuGProbusVSetRegisters(fug, super_register: [FuGProbusVRegisterGroups](#))

Bases: [object](#)

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

property actualsetvalue: float

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

Returns

actual valid set value

property high_resolution: [FuGDigitalVal](#)

Status of the high resolution mode of the output.

Return 0

normal operation

Return 1

High Res. Mode

property rampmode: [FuGRampModes](#)

The set ramp mode to control the setvalue.

Returns

the mode of the ramp as instance of [FuGRampModes](#)

property ramprate: float

The set ramp rate in V/s.

Returns

ramp rate in V/s

property rampstate: *FuGDigitalVal*

Status of ramp function.

Return 0

if final setvalue is reached

Return 1

if still ramping up

property setvalue: float

For the voltage or current output this setvalue was programmed.

Returns

the programmed setvalue

class FuGRampModes(*value*)

Bases: IntEnum

An enumeration.

FOLLOWRAMP = 1

Follow the ramp up- and downwards

IMMEDIATELY = 0

Standard mode: no ramp

ONLYUPWARDSOFFTOZERO = 4

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

RAMPUPWARDS = 2

Follow the ramp only upwards, downwards immediately

SPECIALRAMPUPWARDS = 3

Follow a special ramp function only upwards

class FuGReadbackChannels(*value*)

Bases: IntEnum

An enumeration.

CURRENT = 1

FIRMWARE = 5

RATEDCURRENT = 4

RATEDVOLTAGE = 3

SN = 6

STATUSBYTE = 2

VOLTAGE = 0

class `FuGSerialCommunication(configuration)`

Bases: `SerialCommunication`

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

static `config_cls()`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

query(*command: str*) → str

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

Parameters

command – Command to send

Raises

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

Returns

Answer from the interface or empty string

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

Bases: `SerialCommunicationConfig`

baudrate: int = 9600

Baudrate for FuG power supplies is 9600 baud

bytesize: int | `SerialCommunicationBytesize` = 8

One byte is eight bits long

default_n_attempts_read_text_nonempty: int = 10

default number of attempts to read a non-empty text

force_value(fieldname, value)

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

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

Parameters

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

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

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

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

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

Returns

a list of strings containing all optional keys.

parity: str | *SerialCommunicationParity* = 'N'

FuG does not use parity

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

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

Returns

a list of strings containing all required keys.

stopbits: int | *SerialCommunicationStopbits* = 1

FuG uses one stop bit

terminator: bytes = b'\n'

The terminator is LF

timeout: int | float = 3

use 3 seconds timeout as default

wait_sec_read_text_nonempty: int | float = 0.5

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

class **FuGTerminators**(value)

Bases: IntEnum

An enumeration.

CR = 3

CRLF = 0

LF = 2

LFCR = 1

Module contents

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

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

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

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

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

hvl_ccb.dev.heinzinger

Submodules

hvl_ccb.dev.heinzinger.base

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

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

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

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

Bases: object

Device configuration dataclass for Heinzinger power supplies.

```
class RecordingsEnum(value)
```

Bases: IntEnum

An enumeration.

EIGHT = 8

FOUR = 4

ONE = 1

SIXTEEN = 16

TWO = 2

```
clean_values()
```

```
default_number_of_recordings: int | RecordingsEnum = 1
```

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

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

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

Parameters

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

```
is_configdataclass = True
```

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

number_of_decimals: int = 6

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

wait_sec_stop_commands: int | float = 0.5

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

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: 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: 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: 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: int | float
```

```
property max_current_hardware: int | float
```

```
property max_voltage: int | float
```

```
property max_voltage_hardware: int | float
```

```
set_current(value: 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: 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
```

```
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:
                                          Optional[str] = None, baudrate: int = 9600, parity:
                                          Union[str, hvl_ccb.comm.serial.SerialCommunicationParity]
                                          = <SerialCommunicationParity.NONE: 'N'>, stopbits:
                                          Union[int,
                                          hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                          <SerialCommunicationStopbits.ONE: 1>, bytesize:
                                          Union[int,
                                          hvl_ccb.comm.serial.SerialCommunicationBytesize] =
                                          <SerialCommunicationBytesize.EIGHTBITS: 8>, timeout:
                                          Union[int, float] = 3)
```

Bases: `SerialCommunicationConfig`

baudrate: `int = 9600`

Baudrate for Heinzinger power supplies is 9600 baud

bytesize: `int | SerialCommunicationBytesize = 8`

One byte is eight bits long

default_n_attempts_read_text_nonempty: `int = 40`

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

force_value(*fieldname*, *value*)

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

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

Parameters

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

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

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

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

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

Returns

a list of strings containing all optional keys.

parity: `str | SerialCommunicationParity = 'N'`

Heinzinger does not use parity

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

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

Returns

a list of strings containing all required keys.

stopbits: `int` | *SerialCommunicationStopbits* = 1

Heinzinger uses one stop bit

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

The terminator is LF

timeout: `int` | `float` = 3

use 3 seconds timeout as default

wait_sec_read_text_nonempty: `int` | `float` = 0.5

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

hvl_ccb.dev.heinzinger.constants

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

exception 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'.

Module contents

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

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

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

hvl_ccb.dev.highland_t560

Submodules

hvl_ccb.dev.highland_t560.base

Module containing base device and communication classes and enums.

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

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

Bases: *ValueEnum*

Modes for installing configuration settings to the device.

INSTALL = 1

OFF = 0

QUEUE = 2

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

Bases: *ValueEnum*

Available T560 gate modes

INPUT = 'INP'

OFF = 'OFF'

OUTPUT = 'OUT'

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

Bases: *ValueEnum*

Possible channel polarity states

ACTIVE_HIGH = 'POS'

ACTIVE_LOW = 'NEG'

```
class T560Communication(configuration)
```

Bases: *SyncCommunicationProtocol*, *TelnetCommunication*

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

```
static config_cls()
```

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

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

Send a command to the device and handle the response.

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

Parameters

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

Raises

T560Error – if no response is received, or if the device responds with an error message.

Returns

Response from the device.

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

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

force_value(*fieldname, value*)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

port: int = 2000

Port at which the host is listening

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

terminator: `bytes = b'\r'`

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

exception T560Error

Bases: *DeviceError*

T560 related errors.

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

Bases: *ValueEnum*

Available T560 trigger modes

COMMAND = 'REM'

EXT_FALLING_EDGE = 'NEG'

EXT_RISING_EDGE = 'POS'

INT_SYNTHESIZER = 'SYN'

OFF = 'OFF'

hvl_ccb.dev.highland_t560.channel

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

hvl_ccb.dev.highland_t560.device

Module for controlling device, including TRIG, CLOCK and GATE I/Os.

class T560(*com, dev_config=None*)

Bases: *SingleCommDevice*

activate_clock_output()

Outputs 10 MHz clock signal

property auto_install_mode: *AutoInstallMode*

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

property ch_a: *_Channel*

Channel A of T560

property ch_b: *_Channel*

Channel B of T560

property ch_c: *_Channel*

Channel C of T560

property ch_d: *_Channel*

Channel D of T560

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

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

Returns

the type of the standard communication protocol for this device

disarm_trigger()

Disarm DDG by disabling all trigger sources.

fire_trigger()

Fire a software trigger.

property frequency: float

The frequency of the timing cycle in Hz.

property gate_mode: *GateMode*

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

property gate_polarity: *Polarity*

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

load_device_configuration()

Load the settings saved in nonvolatile memory.

property period: float

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

save_device_configuration()

Save the current settings to nonvolatile memory.

property trigger_level

Get external trigger level.

property trigger_mode

Get device trigger source.

use_external_clock()

Finds and accepts an external clock signal to the CLOCK input

class T560Config

Bases: object

auto_install_mode = 1

clean_values()

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

force_value(*fieldname*, *value*)

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

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

Parameters

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

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

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

Module contents

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

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

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

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

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

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

Extra installation

To use this LabJack T-series devices wrapper:

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

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

this will install the Python bindings for the library.

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

class LabJack(*com, dev_config=None*)

Bases: *SingleCommDevice*

LabJack Device.

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

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

Bases: *StrEnumBase*

An enumeration.

ONE = 1.0

ONE_HUNDREDTH = 0.01

ONE_TENTH = 0.1

TEN = 10.0

property value: float

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

Bases: *IntEnum*

Maximum integer values for clock settings

THIRTY_TWO_BIT = 4294967295

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

Bases: *Enum*

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

TEN = '10uA'

TWO_HUNDRED = '200uA'

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

Bases: *NameEnum*

CJC slope and offset

```
internal = (1, 0)
```

```
lm34 = (55.56, 255.37)
```

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

Bases: `IntEnum`

Available clock frequencies, in Hz

```
FIVE_MHZ = 5000000
```

```
FORTY_MHZ = 40000000
```

```
MAXIMUM = 80000000
```

```
MINIMUM = 312500
```

```
TEN_MHZ = 10000000
```

```
TWELVE_HUNDRED_FIFTY_KHZ = 1250000
```

```
TWENTY_FIVE_HUNDRED_KHZ = 2500000
```

```
TWENTY_MHZ = 20000000
```

DIOChannel

alias of `TSeriesDIOChannel`

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

Bases: `IntEnum`

State of a digital I/O channel.

```
HIGH = 1
```

```
LOW = 0
```

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

Bases: `AutoNumberNameEnum`

LabJack device types.

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

```
ANY = 1
```

```
T4 = 2
```

```
T7 = 3
```

```
T7_PRO = 4
```

```
classmethod get_by_p_id(p_id: int) → DeviceType | list[hvl_ccb._dev.labjack.DeviceType]
```

Get LabJack device type instance via LabJack product ID.

Note: Product ID is not unambiguous for LabJack devices.

Parameters**p_id** – Product ID of a LabJack device**Returns**Instance or list of instances of *LabJackDeviceType***Raises****ValueError** – when Product ID is unknown

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

Bases: *NameEnum*

Temperature unit (to be returned)

C = 1**F** = 2**K** = 0

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

Bases: *NameEnum*

Thermocouple type; NONE means disable thermocouple mode.

C = 30**E** = 20**J** = 21**K** = 22**NONE** = 0**PT100** = 40**PT1000** = 42**PT500** = 41**R** = 23**S** = 25**T** = 24

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

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

static default_com_cls()

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

Returns

the type of the standard communication protocol for this device

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

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

enable_clock(clock_enabled: bool) → None

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

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

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

Parameters

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

Returns

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

get_cal_current_source(name: str | CalMicroAmpere) → float

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

The value was stored during fabrication.

Parameters

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

Returns

calibration of the chosen current source in ampere

get_clock() → dict[str, Union[int, float]]

Return clock settings read from LabJack.

get_digital_input(address: str | TSeriesDIOChannel) → DIOStatus

Get the value of a digital input.

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

get_product_id() → int

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

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

Returns

integer product ID of the device

get_product_name(force_query_id=False) → str

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

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

Parameters

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

Returns

device name string, compatible with *LabJack.DeviceType*

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

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

Parameters

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

Returns

DeviceType instance

Raises

LabJackIdentifierDIOError – when read Product ID is unknown

get_sbus_rh(*number: int*) → float

Read the relative humidity value from a serial SBUS sensor.

Parameters

number – port number (0..22)

Returns

relative humidity in %RH

get_sbus_temp(*number: int*) → float

Read the temperature value from a serial SBUS sensor.

Parameters

number – port number (0..22)

Returns

temperature in Kelvin

get_serial_number() → int

Returns the serial number of the connected LabJack.

Returns

Serial number.

read_resistance(*channel: int*) → float

Read resistance from specified channel.

Parameters

channel – channel with resistor

Returns

resistance value with 2 decimal places

read_thermocouple(*pos_channel: int*) → float

Read the temperature of a connected thermocouple.

Parameters

pos_channel – is the AIN number of the positive pin

Returns

temperature in specified unit

send_pulses(*addresses: str | TSeriesDIOChannel) → None

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

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

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

Parameters

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

Raises

LabJackError – if parameters are unsupported

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

Set the range of an analog input port.

Parameters

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

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

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

Parameters

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

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

Set the resolution index of an analog input port.

Parameters

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

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

Set the analog input channel to thermocouple mode.

Parameters

- **pos_channel** – is the analog input channel of the positive part of the differential pair
- **thermocouple** – None to disable thermocouple mode, or string specifying the thermocouple type
- **cjc_address** – modbus register address to read the CJC temperature
- **cjc_type** – determines cjc slope and offset, 'internal' or 'lm34'

- **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: int | float*) → *None*

Set the voltage of a analog output port

Parameters

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

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

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

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

Set the value of a digital output.

Parameters

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

start() → *None*

Start the Device.

stop() → *None*

Stop the Device.

exception LabJackError

Bases: *DeviceError*

General Error for the LabJack device.

exception LabJackIdentifierDIOError

Bases: *LabJackError*

Error indicating a wrong DIO identifier

Module contents

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

Extra installation

To use this LabJack T-series devices wrapper:

1. install the `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> .

`hvl_ccb.dev.lauda`

Submodules

`hvl_ccb.dev.lauda.lauda`

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

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

Bases: *SingleCommDevice*

Lauda RP245E circulation chiller class.

static config_cls() → type[*hvl_ccb.dev.lauda.lauda.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[*hvl_ccb.dev.lauda.lauda.LaudaProRp245eTcpCommunication*]

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

Returns

the type of the standard communication protocol for this device

get_bath_temp() → float

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

get_device_type() → str

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

pause() → str

Stop temperature control and pump.

Returns

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

pause_ramp() → str

Pause current ramp program.

Returns

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

reset_ramp() → str

Delete all segments from current ramp program.

Returns

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

run() → str

Start temperature control & pump.

Returns

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

set_control_mode(*mod: int* | `ExtControlModeEnum` = `ExtControlModeEnum.INTERNAL`) → str

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

Parameters

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

Returns

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

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

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

Parameters

external_temp – current value of external temperature to be controlled.

Returns

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

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

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

Parameters

pump_level – pump level.

Returns

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

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

Define number of ramp program cycles.

Parameters

num – number of program cycles to be performed.

Returns

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

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

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

Parameters

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

Returns

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

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

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

Parameters

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

Returns

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

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

Define temperature set point

Parameters

temp_set_point – temperature set point.

Returns

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

start() → *None*

Start this device.

start_ramp() → str

Start current ramp program.

Returns

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

stop() → *None*

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

stop_ramp() → str

Stop current ramp program.

Returns

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

validate_pump_level(*level: int*)

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

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

Bases: *ValueEnum*

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

BATH_TEMP = 'IN_PV_00'

Request internal bath temperature

COM_TIME_OUT = 'OUT_SP_08_'

Define communication time out

CONT_MODE = 'OUT_MODE_01_'

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

DEVICE_TYPE = 'TYPE'

Request device type

EXTERNAL_TEMP = 'OUT_PV_05_'

Pass on external controlled temperature

LOWER_TEMP = 'OUT_SP_05_'

Define lower temp limit

OPERATION_MODE = 'OUT_SP_02_'

Define operation mode

PUMP_LEVEL = 'OUT_SP_01_'

Define pump level 1-8

RAMP_CONTINUE = 'RMP_CONT'

Continue a paused ramp program

RAMP_DELETE = 'RMP_RESET'

Reset a selected ramp program

RAMP_ITERATIONS = 'RMP_OUT_02_'

Define how often a ramp program should be iterated

RAMP_PAUSE = 'RMP_PAUSE'

Pause a selected ramp program

RAMP_SELECT = 'RMP_SELECT_'

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

RAMP_SET = 'RMP_OUT_00_'

Define parameters of a selected ramp program

RAMP_START = 'RMP_START'

Start a selected ramp program

RAMP_STOP = 'RMP_STOP'

Stop a running ramp program

START = 'START'

Start temp control (pump and heating/cooling)

STOP = 'STOP'

Stop temp control (pump and heating/cooling)

TEMP_SET_POINT = 'OUT_SP_00_'

Define temperature set point

```
UPPER_TEMP = 'OUT_SP_04_'
```

Define upper temp limit

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

Build a command string for sending to the device

Parameters

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

Returns

Command's string with a parameter and terminator

```
exception LaudaProRp245eCommandError
```

Bases: [DeviceError](#)

Error raised when an error is returned upon a command.

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

Bases: object

Configuration for the Lauda RP245E circulation chiller.

```
class ExtControlModeEnum(value)
```

Bases: IntEnum

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

```
ANALOG = 2
```

```
ETH = 5
```

```
EXPT100 = 1
```

```
INTERNAL = 0
```

```
SERIAL = 3
```

```
USB = 4
```

```
class OperationModeEnum(value)
```

Bases: IntEnum

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

```
AUTO = 2
```

Automatically select heating/cooling

```
COOLOFF = 0
```

```
COOLON = 1
```

```
clean_values() → None
```

com_time_out: int | float = 0

Communication time out (0 = OFF)

control_mode: int | *ExtControlModeEnum* = 0

force_value(*fieldname*, *value*)

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

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

Parameters

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

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

lower_temp: int | float = -55.0

Lower temperature limit (safe for Galden HT135 cooling liquid)

max_pr_number: int = 5

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

max_pump_level: int = 8

Highest pump level of the chiller

operation_mode: int | *OperationModeEnum* = 2

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

pump_init: int = 6

Default pump Level

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

temp_set_point_init: int | float = 20.0

Default temperature set point

upper_temp: int | float = 80.0

Upper temperature limit (safe for Galden HT135 cooling liquid)

class `LaudaProRp245eTcpCommunication(configuration)`

Bases: `Tcp`

Implements the Communication Protocol for Lauda PRO RP245E TCP connection.

close() → `None`

Close the Lauda PRO RP245E TCP connection.

static config_cls() → type[`hvl_ccb.dev.lauda.lauda.LaudaProRp245eTcpCommunicationConfig`]

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

open() → `None`

Open the Lauda PRO RP245E TCP connection.

Raises

`LaudaProRp245eCommandError` – if the connection fails.

query_command(command: LaudaProRp245eCommand, param: str = "") → str

Send and receive function. E.g. to be used when setting/changing device setting. :param command: first part of command string, defined in `LaudaProRp245eCommand` :param param: second part of command string, parameter (by default '') :return: None

read() → str

Receive value function. :return: reply from device as a string, the terminator, as well as the 'OK' stripped from the reply to make it directly useful as a value (e.g. in case the internal bath temperature is requested)

write_command(command: LaudaProRp245eCommand, param: str = "") → `None`

Send command function. :param command: first part of command string, defined in `LaudaProRp245eCommand` :param param: second part of command string, parameter (by default '') :return: None

class `LaudaProRp245eTcpCommunicationConfig(host: str | IPv4Address | IPv6Address, port: int = 54321, bufsize: int = 1024, wait_sec_pre_read_or_write: int | float = 0.005, terminator: str = '\r\n')`

Bases: `TcpCommunicationConfig`

Configuration dataclass for `LaudaProRp245eTcpCommunication`.

clean_values() → `None`

force_value(fieldname, value)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

terminator: str = '\r\n'

The terminator character

wait_sec_pre_read_or_write: int | float = 0.005

Delay time between commands in seconds

Module contents

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

hvl_ccb.dev.mbw973

Submodules

hvl_ccb.dev.mbw973.mbw973

Device class for controlling a MBW 973 SF6 Analyzer over a serial connection.

The MBW 973 is a gas analyzer designed for gas insulated switchgear and measures humidity, SF6 purity and SO2 contamination in one go. Manufacturer homepage: <https://www.mbw.ch/products/sf6-gas-analysis/973-sf6-analyzer/>

class MBW973(com, dev_config=None)

Bases: *SingleCommDevice*

MBW 973 dew point mirror device class.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

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

Returns

the type of the standard communication protocol for this device

is_done() → bool

Poll status of the dew point mirror and return True, if all measurements are done.

Returns

True, if all measurements are done; False otherwise.

Raises

SerialCommunicationIOError – when communication port is not opened

read(*cast_type*: type = <class 'str'>)

Read value from *self.com* and cast to *cast_type*. Raises *ValueError* if read text (*str*) is not convertible to *cast_type*, e.g. to *float* or to *int*.

Returns

Read value of *cast_type* type.

read_float() → float

Convenience wrapper for *self.read()*, with typing hint for return value.

Returns

Read *float* value.

read_int() → int

Convenience wrapper for *self.read()*, with typing hint for return value.

Returns

Read *int* value.

read_measurements() → dict[str, float]

Read out measurement values and return them as a dictionary.

Returns

Dictionary with values.

Raises

SerialCommunicationIOError – when communication port is not opened

set_measuring_options(*humidity*: bool = True, *sf6_purity*: bool = False) → None

Send measuring options to the dew point mirror.

Parameters

- **humidity** – Perform humidity test or not?
- **sf6_purity** – Perform SF6 purity test or not?

Raises

SerialCommunicationIOError – when communication port is not opened

start() → None

Start this device. Opens the communication protocol and retrieves the set measurement options from the device.

Raises

SerialCommunicationIOError – when communication port cannot be opened.

start_control() → None

Start dew point control to acquire a new value set.

Raises

SerialCommunicationIOError – when communication port is not opened

stop() → *None*

Stop the device. Closes also the communication protocol.

write(value) → *None*

Send *value* to *self.com*.

Parameters

value – Value to send, converted to *str*.

Raises

SerialCommunicationIOError – when communication port is not opened

class MBW973Config(*polling_interval: int | float = 2*)

Bases: object

Device configuration dataclass for MBW973.

clean_values()

force_value(fieldname, value)

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

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

Parameters

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

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

polling_interval: int | float = 2

Polling period for *is_done* status queries [in seconds].

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

exception MBW973ControlRunningError

Bases: *MBW973Error*

Error indicating there is still a measurement running, and a new one cannot be started.

exception MBW973Error

Bases: [DeviceError](#)

General error with the MBW973 dew point mirror device.

exception MBW973PumpRunningError

Bases: [MBW973Error](#)

Error indicating the pump of the dew point mirror is still recovering gas, unable to start a new measurement.

class MBW973SerialCommunication(configuration)

Bases: [SerialCommunication](#)

Specific communication protocol implementation for the MBW973 dew point mirror. Already predefines device-specific protocol parameters in config.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class MBW973SerialCommunicationConfig(terminator: bytes = b'\r', encoding: str = 'utf-8',
                                     encoding_error_handling: str = 'strict',
                                     wait_sec_read_text_nonempty: Union[int, float] = 0.5,
                                     default_n_attempts_read_text_nonempty: int = 10, port:
                                     Optional[str] = None, baudrate: int = 9600, parity: Union[str,
                                     hvl_ccb.comm.serial.SerialCommunicationParity] =
                                     <SerialCommunicationParity.NONE: 'N'>, stopbits: Union[int,
                                     hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                     <SerialCommunicationStopbits.ONE: 1>, bytesize: Union[int,
                                     hvl_ccb.comm.serial.SerialCommunicationBytesize] =
                                     <SerialCommunicationBytesize.EIGHTBITS: 8>, timeout:
                                     Union[int, float] = 3)
```

Bases: [SerialCommunicationConfig](#)

baudrate: int = 9600

Baudrate for MBW973 is 9600 baud

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

One byte is eight bits long

force_value(fieldname, value)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

parity: str | *SerialCommunicationParity* = 'N'

MBW973 does not use parity

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

stopbits: int | *SerialCommunicationStopbits* = 1

MBW973 does use one stop bit

terminator: bytes = b'\r'

The terminator is only CR

timeout: int | float = 3

use 3 seconds timeout as default

Module contents

Device class for controlling a MBW 973 SF6 Analyzer over a serial connection.

The MBW 973 is a gas analyzer designed for gas insulated switchgear and measures humidity, SF6 purity and SO2 contamination in one go. Manufacturer homepage: <https://www.mbw.ch/products/sf6-gas-analysis/973-sf6-analyzer/>

hvl_ccb.dev.newport

Submodules

hvl_ccb.dev.newport.newport

Device class for Newport SMC100PP stepper motor controller with serial communication.

The SMC100PP is a single axis motion controller/driver for stepper motors up to 48 VDC at 1.5 A rms. Up to 31 controllers can be networked through the internal RS-485 communication link.

Manufacturer homepage: <https://www.newport.com/f/smc100-single-axis-dc-or-stepper-motion-controller>

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

Bases: *NameEnum*

Commands predefined by the communication protocol of the SMC100PP

AC = 'acceleration'

BA = 'backlash_compensation'

```
BH = 'hysteresis_compensation'
FRM = 'micro_step_per_full_step_factor'
FRS = 'motion_distance_per_full_step'
HT = 'home_search_type'
JR = 'jerk_time'
OH = 'home_search_velocity'
OT = 'home_search_timeout'
QIL = 'peak_output_current_limit'
SA = 'rs485_address'
SL = 'negative_software_limit'
SR = 'positive_software_limit'
VA = 'velocity'
VB = 'base_velocity'
ZX = 'stage_configuration'
```

exception 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: int | None = None) → None

Exit the CONFIGURATION state and go back to the NOT REFERENCED state. All configuration parameters are saved to the device's memory.

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

get_acceleration(add: int | None = None) → int | float

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

Parameters

add – controller address (1 to 31)

Returns

acceleration (preset units/s²), value between 1e-6 and 1e12

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

get_controller_information(add: int | None = None) → str

Get information on the controller name and driver version

Parameters

add – controller address (1 to 31)

Returns

controller information

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained

- ***NewportControllerError*** – if the controller reports an error

get_motor_configuration(*add*: int | None = None) → dict[str, float]

Query the motor configuration and returns it in a dictionary.

Parameters

add – controller address (1 to 31)

Returns

dictionary containing the motor's configuration

Raises

- ***SerialCommunicationIOError*** – if the com is closed
- ***NewportSerialCommunicationError*** – if an unexpected answer is obtained
- ***NewportControllerError*** – if the controller reports an error

get_move_duration(*dist*: int | float, *add*: int | None = None) → float

Estimate the time necessary to move the motor of the specified distance.

Parameters

- **dist** – distance to travel
- **add** – controller address (1 to 31), defaults to self.address

Raises

- ***SerialCommunicationIOError*** – if the com is closed
- ***NewportSerialCommunicationError*** – if an unexpected answer is obtained
- ***NewportControllerError*** – if the controller reports an error

get_negative_software_limit(*add*: int | None = None) → int | float

Get the negative software limit (the maximum position that the motor is allowed to travel to towards the left).

Parameters

add – controller address (1 to 31)

Returns

negative software limit (preset units), value between -1e12 and 0

Raises

- ***SerialCommunicationIOError*** – if the com is closed
- ***NewportSerialCommunicationError*** – if an unexpected answer is obtained
- ***NewportControllerError*** – if the controller reports an error

get_position(*add*: int | None = None) → float

Returns the value of the current position.

Parameters

add – controller address (1 to 31)

Raises

- ***SerialCommunicationIOError*** – if the com is closed
- ***NewportSerialCommunicationError*** – if an unexpected answer is obtained
- ***NewportControllerError*** – if the controller reports an error

- *NewportUncertainPositionError* – if the position is ambiguous

get_positive_software_limit(*add*: int | None = None) → int | float

Get the positive software limit (the maximum position that the motor is allowed to travel to towards the right).

Parameters

add – controller address (1 to 31)

Returns

positive software limit (preset units), value between 0 and 1e12

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

get_state(*add*: int | None = None) → *StateMessages*

Check on the motor errors and the controller state

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error
- *NewportMotorError* – if the motor reports an error

Returns

state message from the device (member of *StateMessages*)

go_home(*add*: int | None = None) → None

Move the motor to its home position.

Parameters

add – controller address (1 to 31), defaults to self.address

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

go_to_configuration(*add*: int | None = None) → None

This method is executed during start(). It can also be executed after a reset(). The controller is put in CONFIG state, where configuration parameters can be changed.

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained

- ***NewportControllerError*** – if the controller reports an error

initialize(*add*: int | *None* = *None*) → *None*

Puts the controller from the NOT_REF state to the READY state. Sends the motor to its “home” position.

Parameters

add – controller address (1 to 31)

Raises

- ***SerialCommunicationIOError*** – if the com is closed
- ***NewportSerialCommunicationError*** – if an unexpected answer is obtained
- ***NewportControllerError*** – if the controller reports an error

move_to_absolute_position(*pos*: int | float, *add*: int | *None* = *None*) → *None*

Move the motor to the specified position.

Parameters

- **pos** – target absolute position (affected by the configured offset)
- **add** – controller address (1 to 31), defaults to self.address

Raises

- ***SerialCommunicationIOError*** – if the com is closed
- ***NewportSerialCommunicationError*** – if an unexpected answer is obtained
- ***NewportControllerError*** – if the controller reports an error

move_to_relative_position(*pos*: int | float, *add*: int | *None* = *None*) → *None*

Move the motor of the specified distance.

Parameters

- **pos** – distance to travel (the sign gives the direction)
- **add** – controller address (1 to 31), defaults to self.address

Raises

- ***SerialCommunicationIOError*** – if the com is closed
- ***NewportSerialCommunicationError*** – if an unexpected answer is obtained
- ***NewportControllerError*** – if the controller reports an error

reset(*add*: int | *None* = *None*) → *None*

Resets the controller, equivalent to a power-up. This puts the controller back to NOT REFERENCED state, which is necessary for configuring the controller.

Parameters

add – controller address (1 to 31)

Raises

- ***SerialCommunicationIOError*** – if the com is closed
- ***NewportSerialCommunicationError*** – if an unexpected answer is obtained
- ***NewportControllerError*** – if the controller reports an error

set_acceleration(*acc*: int | float, *add*: int | None = None) → None

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

Parameters

- **acc** – acceleration (preset units/s²), value between 1e-6 and 1e12
- **add** – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

set_motor_configuration(*add*: int | None = None, *config*: dict | None = None) → None

Set the motor configuration. The motor must be in CONFIG state.

Parameters

- **add** – controller address (1 to 31)
- **config** – dictionary containing the motor's configuration

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

set_negative_software_limit(*lim*: int | float, *add*: int | None = None) → None

Set the negative software limit (the maximum position that the motor is allowed to travel to towards the left).

Parameters

- **lim** – negative software limit (preset units), value between -1e12 and 0
- **add** – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

set_positive_software_limit(*lim*: int | float, *add*: int | None = None) → None

Set the positive software limit (the maximum position that the motor is allowed to travel to towards the right).

Parameters

- **lim** – positive software limit (preset units), value between 0 and 1e12
- **add** – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained

- **NewportControllerError** – if the controller reports an error

start()

Opens the communication protocol and applies the config.

Raises

SerialCommunicationIOError – when communication port cannot be opened

stop() → *None*

Stop the device. Close the communication protocol.

stop_motion(add: int | None = None) → *None*

Stop a move in progress by decelerating the positioner immediately with the configured acceleration until it stops. If a controller address is provided, stops a move in progress on this controller, else stops the moves on all controllers.

Parameters

add – controller address (1 to 31)

Raises

- **SerialCommunicationIOError** – if the com is closed
- **NewportSerialCommunicationError** – if an unexpected answer is obtained
- **NewportControllerError** – if the controller reports an error

wait_until_motor_initialized(add: int | None = None) → *None*

Wait until the motor leaves the HOMING state (at which point it should have arrived to the home position).

Parameters

add – controller address (1 to 31)

Raises

- **SerialCommunicationIOError** – if the com is closed
- **NewportSerialCommunicationError** – if an unexpected answer is obtained
- **NewportControllerError** – if the controller reports an error

```
class NewportSMC100PPConfig(address: int = 1, user_position_offset: int | float = 23.987, screw_scaling: int | float = 1, exit_configuration_wait_sec: int | float = 5, move_wait_sec: int | float = 1, acceleration: int | float = 10, backlash_compensation: int | float = 0, hysteresis_compensation: int | float = 0.015, micro_step_per_full_step_factor: int = 100, motion_distance_per_full_step: int | float = 0.01, home_search_type: int | HomeSearch = HomeSearch.HomeSwitch, jerk_time: int | float = 0.04, home_search_velocity: int | float = 4, home_search_timeout: int | float = 27.5, home_search_polling_interval: int | float = 1, peak_output_current_limit: int | float = 0.4, rs485_address: int = 2, negative_software_limit: int | float = -23.5, positive_software_limit: int | float = 25, velocity: int | float = 4, base_velocity: int | float = 0, stage_configuration: int | EspStageConfig = EspStageConfig.EnableEspStageCheck)
```

Bases: object

Configuration dataclass for the Newport motor controller SMC100PP.

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

Bases: IntEnum

Different configurations to check or not the motor configuration upon power-up.

```
DisableEspStageCheck = 1
EnableEspStageCheck = 3
UpdateEspStageInfo = 2
```

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

Bases: IntEnum

Different methods for the motor to search its home position during initialization.

```
CurrentPosition = 1
EndOfRunSwitch = 4
EndOfRunSwitch_and_Index = 3
HomeSwitch = 2
HomeSwitch_and_Index = 0
```

acceleration: int | float = 10

address: int = 1

backlash_compensation: int | float = 0

base_velocity: int | float = 0

clean_values()

exit_configuration_wait_sec: int | float = 5

force_value(*fieldname, value*)

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

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

Parameters

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

```
home_search_polling_interval: int | float = 1
home_search_timeout: int | float = 27.5
home_search_type: int | HomeSearch = 2
home_search_velocity: int | float = 4
hysteresis_compensation: int | float = 0.015
is_configdataclass = True
jerk_time: int | float = 0.04
```

classmethod `keys()` → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

micro_step_per_full_step_factor: int = 100

motion_distance_per_full_step: int | float = 0.01

property `motor_config:` dict[str, float]

Gather the configuration parameters of the motor into a dictionary.

Returns

dict containing the configuration parameters of the motor

move_wait_sec: int | float = 1

negative_software_limit: int | float = -23.5

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

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

Returns

a list of strings containing all optional keys.

peak_output_current_limit: int | float = 0.4

positive_software_limit: int | float = 25

post_force_value(*fieldname*, *value*)

classmethod `required_keys()` → Sequence[str]

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

Returns

a list of strings containing all required keys.

rs485_address: int = 2

screw_scaling: int | float = 1

stage_configuration: int | *EspStageConfig* = 3

user_position_offset: int | float = 23.987

velocity: int | float = 4

class `NewportSMC100PPSerialCommunication`(*configuration*)

Bases: *SerialCommunication*

Specific communication protocol implementation for NewportSMC100 controller. Already predefines device-specific protocol parameters in config.

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

Bases: Enum

Possible controller errors with values as returned by the device in response to sent commands.

```
ADDR_INCORRECT = 'B'
CMD_EXEC_ERROR = 'V'
CMD_NOT_ALLOWED = 'D'
CMD_NOT_ALLOWED_CC = 'X'
CMD_NOT_ALLOWED_CONFIGURATION = 'I'
CMD_NOT_ALLOWED_DISABLE = 'J'
CMD_NOT_ALLOWED_HOMING = 'L'
CMD_NOT_ALLOWED_MOVING = 'M'
CMD_NOT_ALLOWED_NOT_REFERENCED = 'H'
CMD_NOT_ALLOWED_PP = 'W'
CMD_NOT_ALLOWED_READY = 'K'
CODE_OR_ADDR_INVALID = 'A'
COM_TIMEOUT = 'S'
DISPLACEMENT_OUT_OF_LIMIT = 'G'
EEPROM_ACCESS_ERROR = 'U'
ESP_STAGE_NAME_INVALID = 'F'
HOME_STARTED = 'E'
NO_ERROR = '@'
PARAM_MISSING_OR_INVALID = 'C'
POSITION_OUT_OF_LIMIT = 'N'
```

check_for_error(*add: int*) → *None*

Ask the Newport controller for the last error it recorded.

This method is called after every command or query.

Parameters

add – controller address (1 to 31)

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

query(*add: int, cmd: str, param: int | float | str | None = None*) → str

Send a query to the controller, read the answer, and check for errors. The prefix `add+cmd` is removed from the answer.

Parameters

- **add** – the controller address (1 to 31)
- **cmd** – the command to be sent
- **param** – optional parameter (int/float/str) appended to the command

Returns

the answer from the device without the prefix

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

query_multiple(*add: int, cmd: str, prefixes: list[str]*) → list[str]

Send a query to the controller, read the answers, and check for errors. The prefixes are removed from the answers.

Parameters

- **add** – the controller address (1 to 31)
- **cmd** – the command to be sent
- **prefixes** – prefixes of each line expected in the answer

Returns

list of answers from the device without prefix

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

read_text() → str

Read one line of text from the serial port, and check for presence of a null char which indicates that the motor power supply was cut and then restored. The input buffer may hold additional data afterwards, since only one line is read.

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

Returns

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

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *NewportMotorPowerSupplyWasCutError* – if a null char is read

send_command(*add: int, cmd: str, param: int | float | str | None = None*) → None

Send a command to the controller, and check for errors.

Parameters

- **add** – the controller address (1 to 31)
- **cmd** – the command to be sent
- **param** – optional parameter (int/float/str) appended to the command

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained
- *NewportControllerError* – if the controller reports an error

send_stop(*add: int*) → *None*

Send the general stop ST command to the controller, and check for errors.

Parameters

add – the controller address (1 to 31)

Returns

ControllerErrors reported by Newport Controller

Raises

- *SerialCommunicationIOError* – if the com is closed
- *NewportSerialCommunicationError* – if an unexpected answer is obtained

```
class NewportSMC100PPPSerialCommunicationConfig(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: Optional[str] = None, baudrate: int = 57600,
                                                  parity: Union[str,
                                                                hvl_ccb.comm.serial.SerialCommunicationParity] =
                                                                <SerialCommunicationParity.NONE: 'N'>, stopbits:
                                                                Union[int,
                                                                hvl_ccb.comm.serial.SerialCommunicationStopbits] =
                                                                <SerialCommunicationStopbits.ONE: 1>, bytesize:
                                                                Union[int,
                                                                hvl_ccb.comm.serial.SerialCommunicationBytesize] =
                                                                <SerialCommunicationBytesize.EIGHTBITS: 8>,
                                                  timeout: Union[int, float] = 10)
```

Bases: *SerialCommunicationConfig*

baudrate: **int** = 57600

Baudrate for NewportSMC100 controller is 57600 baud

bytesize: **int** | *SerialCommunicationBytesize* = 8

NewportSMC100 controller uses 8 bits for one data byte

encoding: **str** = 'ascii'

use ASCII as de-/encoding, cf. the manual

encoding_error_handling: **str** = 'replace'

replace bytes with instead of raising utf-8 exception when decoding fails

force_value(*fieldname, value*)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

parity: str | *SerialCommunicationParity* = 'N'

NewportSMC100 controller does not use parity

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

stopbits: int | *SerialCommunicationStopbits* = 1

NewportSMC100 controller uses one stop bit

terminator: bytes = b'\r\n'

The terminator is CR/LF

timeout: int | float = 10

use 10 seconds timeout as default

exception NewportSerialCommunicationError

Bases: *NewportError*

Communication error with the Newport controller.

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

Bases: *AutoNumberNameEnum*

States of the Newport controller. Certain commands are allowed only in certain states.

CONFIG = 3

DISABLE = 6

HOMING = 2

JOGGING = 7

MOVING = 5

NO_REF = 1

READY = 4

exception NewportUncertainPositionError

Bases: *NewportError*

Error with the position of the Newport motor.

Module contents

Device class for Newport SMC100PP stepper motor controller with serial communication.

The SMC100PP is a single axis motion controller/driver for stepper motors up to 48 VDC at 1.5 A rms. Up to 31 controllers can be networked through the internal RS-485 communication link.

Manufacturer homepage: <https://www.newport.com/f/smc100-single-axis-dc-or-stepper-motion-controller>

hvl_ccb.dev.pfeiffer_tpg

Submodules

hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg

Device class for Pfeiffer TPG controllers.

The Pfeiffer TPG control units are used to control Pfeiffer Compact Gauges. Models: TPG 251 A, TPG 252 A, TPG 256A, TPG 261, TPG 262, TPG 361, TPG 362 and TPG 366.

Manufacturer homepage: <https://www.pfeiffer-vacuum.com/en/products/measurement-analysis/> measurement/activeline/controllers/

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

Bases: *SingleCommDevice*

Pfeiffer TPG control unit device class

class SensorStatus(*value*)

Bases: *IntEnum*

An enumeration.

Identification_error = 6

No_sensor = 5

Ok = 0

Overrange = 2

Sensor_error = 3

Sensor_off = 4

Underrange = 1

```
class SensorTypes(value)
```

Bases: Enum

An enumeration.

CMR = 4

IKR = 2

IKR11 = 2

IKR9 = 2

IMR = 5

None = 7

PBR = 6

PKR = 3

TPR = 1

noSENSOR = 7

noSen = 7

```
static config_cls()
```

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
static default_com_cls()
```

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

Returns

the type of the standard communication protocol for this device

```
get_full_scale_mbar() → list[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 $1 \leq \text{channel} \leq \text{number_of_sensors}$

Returns

measured value as float if measurement successful, sensor status as string if not

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *PfeifferTPGError* – if command fails

measure_all() → list[tuple[str, float]]

Get the status and measurement of all sensors (this command is not available on all models)

Returns

list of measured values as float if measurements successful, and or sensor status as strings if not

Raises

- *SerialCommunicationIOError* – when communication port is not opened
- *PfeifferTPGError* – if command fails

property number_of_sensors

set_full_scale_mbar(fsr: list[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: str* | *Model* = *Model.TPG25xA*)

Bases: *object*

Device configuration dataclass for Pfeiffer TPG controllers.

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

Bases: *NameEnum*

An enumeration.

TPG25xA = {**0.1**: 8, **1**: 0, **10**: 1, **100**: 2, **1000**: 3, **2000**: 4, **5000**: 5, **10000**: 6, **50000**: 7}

TPGx6x = {**0.01**: 0, **0.1**: 1, **1**: 2, **10**: 3, **100**: 4, **1000**: 5, **2000**: 6, **5000**: 7, **10000**: 8, **50000**: 9}

is_valid_scale_range_reversed_str(*v: str*) → *bool*

Check if given string represents a valid reversed scale range of a model.

Parameters

v – Reversed scale range string.

Returns

True if valid, *False* otherwise.

clean_values()

force_value(*fieldname, value*)

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

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

Parameters

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

is_configdataclass = *True*

classmethod keys() → *Sequence[str]*

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

model: str | *Model* = {**0.1**: 8, **1**: 0, **10**: 1, **100**: 2, **1000**: 3, **2000**: 4, **5000**: 5, **10000**: 6, **50000**: 7}

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

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

Returns

a list of strings containing all optional keys.

classmethod `required_keys()` → Sequence[str]

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

Returns

a list of strings containing all required keys.

exception `PfeifferTPGError`

Bases: `DeviceError`

Error with the Pfeiffer TPG Controller.

class `PfeifferTPGSerialCommunication(configuration)`

Bases: `SerialCommunication`

Specific communication protocol implementation for Pfeiffer TPG controllers. Already predefines device-specific protocol parameters in config.

static `config_cls()`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

query(*cmd: str*) → str

Send a query, then read and returns the first line from the com port.

Parameters

cmd – query message to send to the device

Returns

first line read on the com

Raises

- `SerialCommunicationIOError` – when communication port is not opened
- `PfeifferTPGError` – if the device does not acknowledge the command or if the answer from the device is empty

send_command(*cmd: str*) → *None*

Send a command to the device and check for acknowledgement.

Parameters

cmd – command to send to the device

Raises

- `SerialCommunicationIOError` – when communication port is not opened
- `PfeifferTPGError` – if the answer from the device differs from the expected acknowledgement character 'chr(6)'.

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

Bases: `SerialCommunicationConfig`

baudrate: `int = 9600`

Baudrate for Pfeiffer TPG controllers is 9600 baud

bytesize: `int | SerialCommunicationBytesize = 8`

One byte is eight bits long

force_value(*fieldname*, *value*)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

parity: `str | SerialCommunicationParity = 'N'`

Pfeiffer TPG controllers do not use parity

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

stopbits: `int` | `SerialCommunicationStopbits` = 1

Pfeiffer TPG controllers use one stop bit

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

The terminator is <CR><LF>

timeout: `int` | `float` = 3

use 3 seconds timeout as default

Module contents

Device class for Pfeiffer TPG controllers.

The Pfeiffer TPG control units are used to control Pfeiffer Compact Gauges. Models: TPG 251 A, TPG 252 A, TPG 256A, TPG 261, TPG 262, TPG 361, TPG 362 and TPG 366.

Manufacturer homepage: <https://www.pfeiffer-vacuum.com/en/products/measurement-analysis/> measurement/activeline/controllers/

`hvl_ccb.dev.picotech_pt104`

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

To build the API docs for this submodule locally edit the `docs/hvl_ccb.dev.picotech_pt104.rst` file to remove the `.. code-block::` directive preceding the following directives:

```
.. inheritance-diagram:: hvl_ccb.dev.picotech_pt104
   :parts: 1

.. automodule:: hvl_ccb.dev.picotech_pt104
   :members:
   :undoc-members:
   :show-inheritance:
```

`hvl_ccb.dev.rs_rto1024`

Submodules

`hvl_ccb.dev.rs_rto1024.rs_rto1024`

Python module for the Rhode & Schwarz RTO 1024 oscilloscope. The communication to the device is through VISA, type TCPIP / INSTR.

class `RT01024`(*com*: `RTO1024VisaCommunication` | `RTO1024VisaCommunicationConfig` | *dict*, *dev_config*: `RTO1024Config` | *dict*)

Bases: `VisaDevice`

Device class for the Rhode & Schwarz RTO 1024 oscilloscope.


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

Bases: [AutoNumberNameEnum](#)

Enumeration for the three available trigger modes.

AUTO = 1

FREERUN = 3

NORMAL = 2

classmethod names()

Returns a list of the available trigger modes. :return: list of strings

```
activate_measurements(meas_n: int, source: str, measurements: list[str], category: str = 'AMPTIME')
```

Activate the list of 'measurements' of the waveform 'source' in the measurement box number 'meas_n'. The list 'measurements' starts with the main measurement and continues with additional measurements of the same 'category'.

Parameters

- **meas_n** – measurement number 1..8
- **source** – measurement source, for example C1W1
- **measurements** – list of measurements, the first one will be the main measurement.
- **category** – the category of measurements, by default AMPTIME

```
backup_waveform(filename: str) → None
```

Backup a waveform file from the standard directory specified in the device configuration to the standard backup destination specified in the device configuration. The filename has to be specified without .bin or path.

Parameters

filename – The waveform filename without extension and path

```
static config_cls()
```

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
static default_com_cls()
```

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

Returns

the VisaCommunication class

```
file_copy(source: str, destination: str) → None
```

Copy a file from one destination to another on the oscilloscope drive. If the destination file already exists, it is overwritten without notice.

Parameters

- **source** – absolute path to the source file on the DSO filesystem
- **destination** – absolute path to the destination file on the DSO filesystem

Raises

[RT01024Error](#) – if the operation did not complete

get_acquire_length() → float

Gets the time of one acquisition, that is the time across the 10 divisions of the diagram.

- Range: 250E-12 ... 500 [s]
- Increment: 1E-12 [s]

Returns

the time for one acquisition. Range: 250e-12 ... 500 [s]

get_channel_offset(channel: int) → float

Gets the voltage offset of the indicated channel.

Parameters

channel – is the channel number (1..4)

Returns

channel offset voltage in V (value between -1 and 1)

get_channel_position(channel: int) → float

Gets the vertical position of the indicated channel.

Parameters

channel – is the channel number (1..4)

Returns

channel position in div (value between -5 and 5)

get_channel_range(channel: int) → float

Queries the channel range in V.

Parameters

channel – is the input channel (1..4)

Returns

channel range in V

get_channel_scale(channel: int) → float

Queries the channel scale in V/div.

Parameters

channel – is the input channel (1..4)

Returns

channel scale in V/div

get_channel_state(channel: int) → bool

Queries if the channel is active or not.

Parameters

channel – is the input channel (1..4)

Returns

True if active, else False

get_reference_point() → int

Gets the reference point of the time scale in % of the display. If the “Trigger offset” is zero, the trigger point matches the reference point. ReferencePoint = zero pint of the time scale

- Range: 0 ... 100 [%]
- Increment: 1 [%]

Returns

the reference in %

get_repetitions() → int

Get the number of acquired waveforms with RUN Nx SINGLE. Also defines the number of waveforms used to calculate the average waveform.

- Range: 1 ... 16777215
- Increment: 10
- *RST = 1

Returns

the number of waveforms to acquire

get_timestamps() → list[float]

Gets the timestamps of all recorded frames in the history and returns them as a list of floats.

Returns

list of timestamps in [s]

Raises

RT01024Error – 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 *ReCaLI* calls up the instrument settings from an intermediate memory identified by the specified number. The instrument settings can be stored to this memory using the command *SAV with the associated number. It also activates the instrument settings which are stored in a file and loaded using *MMEMory:LOAD:STATe* .

Parameters

filename – is the name of the settings file without path and extension

local_display(state: bool) → *None*

Enable or disable local display of the scope.

Parameters

state – is the desired local display state

prepare_ultra_segmentation() → *None*

Make ready for a new acquisition in ultra segmentation mode. This function does one acquisition without ultra segmentation to clear the history and prepare for a new measurement.

read_measurement(meas_n: int, name: str) → float

Parameters

- **meas_n** – measurement number 1..8

- **name** – measurement name, for example “MAX”

Returns

measured value

run_continuous_acquisition() → *None*

Start acquiring continuously.

run_single_acquisition() → *None*

Start a single or Nx acquisition.

save_configuration(filename: str) → *None*

Save the current oscilloscope settings to a file. The filename has to be specified without path and ‘.dff’ extension, the file will be saved to the configured settings directory.

Information from the manual *SAVE* stores the current instrument settings under the specified number in an intermediate memory. The settings can be recalled using the command **RCL* with the associated number. To transfer the stored instrument settings to a file, use *MMEMory:STORe:STATe* .

Parameters

filename – is the name of the settings file without path and extension

save_waveform_history(filename: str, channel: int, waveform: int = 1) → *None*

Save the history of one channel and one waveform to a .bin file. This function is used after an acquisition using sequence trigger mode (with or without ultra segmentation) was performed.

Parameters

- **filename** – is the name (without extension) of the file
- **channel** – is the channel number
- **waveform** – is the waveform number (typically 1)

Raises

RT01024Error – if storing waveform times out

set_acquire_length(timerange: float) → *None*

Defines the time of one acquisition, that is the time across the 10 divisions of the diagram.

- Range: 250E-12 ... 500 [s]
- Increment: 1E-12 [s]
- *RST = 0.5 [s]

Parameters

timerange – is the time for one acquisition. Range: 250e-12 ... 500 [s]

set_channel_offset(channel: int, offset: float) → *None*

Sets the voltage offset of the indicated channel.

- Range: Dependent on the channel scale and coupling [V]
- Increment: Minimum 0.001 [V], may be higher depending on the channel scale and coupling
- *RST = 0

Parameters

- **channel** – is the channel number (1..4)

- **offset** – Offset voltage. Positive values move the waveform down, negative values move it up.

set_channel_position(*channel: int, position: float*) → *None*

Sets the vertical position of the indicated channel as a graphical value.

- Range: -5.0 ... 5.0 [div]
- Increment: 0.02
- *RST = 0

Parameters

- **channel** – is the channel number (1..4)
- **position** – is the position. Positive values move the waveform up, negative values move it down.

set_channel_range(*channel: int, v_range: float*) → *None*

Sets the voltage range across the 10 vertical divisions of the diagram. Use the command alternatively instead of set_channel_scale.

- Range for range: Depends on attenuation factors and coupling. With 1:1 probe and external attenuations and 50 input coupling, the range is 10 mV to 10 V. For 1 M input coupling, it is 10 mV to 100 V. If the probe and/or external attenuation is changed, multiply the range values by the attenuation factors.
- Increment: 0.01
- *RST = 0.5

Parameters

- **channel** – is the channel number (1..4)
- **v_range** – is the vertical range [V]

set_channel_scale(*channel: int, scale: float*) → *None*

Sets the vertical scale for the indicated channel. The scale value is given in volts per division.

- Range for scale: depends on attenuation factor and coupling. With 1:1 probe and external attenuations and 50 input coupling, the vertical scale (input sensitivity) is 1 mV/div to 1 V/div. For 1 M input coupling, it is 1 mV/div to 10 V/div. If the probe and/or external attenuation is changed, multiply the values by the attenuation factors to get the actual scale range.
- Increment: 1e-3
- *RST = 0.05

See also: set_channel_range

Parameters

- **channel** – is the channel number (1..4)
- **scale** – is the vertical scaling [V/div]

set_channel_state(*channel: int, state: bool*) → *None*

Switches the channel signal on or off.

Parameters

- **channel** – is the input channel (1..4)
- **state** – is True for on, False for off

set_reference_point(*percentage: int*) → *None*

Sets the reference point of the time scale in % of the display. If the “Trigger offset” is zero, the trigger point matches the reference point. ReferencePoint = zero pint of the time scale

- Range: 0 ... 100 [%]
- Increment: 1 [%]
- *RST = 50 [%]

Parameters

percentage – is the reference in %

set_repetitions(*number: int*) → *None*

Set the number of acquired waveforms with RUN Nx SINGLE. Also defines the number of waveforms used to calculate the average waveform.

- Range: 1 ... 16777215
- Increment: 10
- *RST = 1

Parameters

number – is the number of waveforms to acquire

set_trigger_level(*channel: int, level: float, event_type: int = 1*) → *None*

Sets the trigger level for the specified event and source.

- Range: -10 to 10 V
- Increment: 1e-3 V
- *RST = 0 V

Parameters

- **channel** – indicates the trigger source.
 - 1..4 = channel 1 to 4, available for all event types 1..3
 - 5 = external trigger input on the rear panel for analog signals, available for A-event type = 1
 - 6..9 = not available
- **level** – is the voltage for the trigger level in [V].
- **event_type** – is the event type. 1: A-Event, 2: B-Event, 3: R-Event

set_trigger_mode(*mode: str | TriggerModes*) → *None*

Sets the trigger mode which determines the behavior of the instrument if no trigger occurs.

Parameters

mode – is either auto, normal, or freerun.

Raises

RT01024Error – if an invalid triggermode is selected

set_trigger_source(*channel: int, event_type: int = 1*) → *None*

Set the trigger (Event A) source channel.

Parameters

- **channel** – is the channel number (1..4)
- **event_type** – is the event type. 1: A-Event, 2: B-Event, 3: R-Event

start() → *None*

Start the RTO1024 oscilloscope and bring it into a defined state and remote mode.

stop() → *None*

Stop the RTO1024 oscilloscope, reset events and close communication. Brings back the device to a state where local operation is possible.

stop_acquisition() → *None*

Stop any acquisition.

```
class RT01024Config(waveforms_path: str, settings_path: str, backup_path: str, spoll_interval: int | float = 0.5,
                    spoll_start_delay: int | float = 2, command_timeout_seconds: int | float = 60,
                    wait_sec_short_pause: int | float = 0.1, wait_sec_enable_history: int | float = 1,
                    wait_sec_post_acquisition_start: int | float = 2)
```

Bases: *VisaDeviceConfig*, *_RT01024ConfigDefaultsBase*, *_RT01024ConfigBase*

Configdataclass for the RTO1024 device.

force_value(*fieldname, value*)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

exception RT01024Error

Bases: *DeviceError*

class `RT01024VisaCommunication(configuration)`

Bases: `VisaCommunication`

Specialization of `VisaCommunication` for the RT01024 oscilloscope

static `config_cls()`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

class `RT01024VisaCommunicationConfig(host: str | IPv4Address | IPv6Address, interface_type: str | InterfaceType = InterfaceType.TCPIP_INSTR, board: int = 0, port: int = 5025, timeout: int = 5000, chunk_size: int = 204800, open_timeout: int = 1000, write_termination: str = '\n', read_termination: str = '\n', visa_backend: str = '')`

Bases: `VisaCommunicationConfig`

Configuration dataclass for `VisaCommunication` with specifications for the RT01024 device class.

force_value(fieldname, value)

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

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

Parameters

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

interface_type: str | InterfaceType = 2

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

classmethod `keys()` → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

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

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

Returns

a list of strings containing all optional keys.

classmethod `required_keys()` → Sequence[str]

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

Returns

a list of strings containing all required keys.

Module contents

Python module for the Rhode & Schwarz RTO 1024 oscilloscope. The communication to the device is through VISA, type TCPIP / INSTR.

hvl_ccb.dev.se_ils2t

Submodules

hvl_ccb.dev.se_ils2t.se_ils2t

Device class for controlling a Schneider Electric ILS2T stepper drive over modbus TCP.

class `ILS2T`(*com*, *dev_config=None*)

Bases: `SingleCommDevice`

Schneider Electric ILS2T stepper drive class.

ACTION_JOG_VALUE = 0

The single action value for `ILS2T.Mode.JOG`

class `ActionsPtp`(*value*)

Bases: `IntEnum`

Allowed actions in the point to point mode (`ILS2T.Mode.PTP`).

ABSOLUTE_POSITION = 0

RELATIVE_POSITION_MOTOR = 2

RELATIVE_POSITION_TARGET = 1

DEFAULT_IO_SCANNING_CONTROL_VALUES = {'action': 2, 'continue_after_stop_cu': 0, 'disable_driver_di': 0, 'enable_driver_en': 0, 'execute_stop_sh': 0, 'fault_reset_fr': 0, 'mode': 3, 'quick_stop_qs': 0, 'ref_16': 1500, 'ref_32': 0, 'reset_stop_ch': 0}

Default IO Scanning control mode values

class `Mode`(*value*)

Bases: `IntEnum`

ILS2T device modes

JOG = 1

PTP = 3

class `Ref16Jog`(*value*)

Bases: `Flag`

Allowed values for ILS2T ref_16 register (the shown values are the integer representation of the bits), all in Jog mode = 1

FAST = 4

NEG = 2

NEG_FAST = 6

NONE = 0

POS = 1

POS_FAST = 5

RegAddr

Modbus Register Addresses

alias of [*ILS2TRegAddr*](#)

RegDatatype

Modbus Register Datatypes

alias of [*ILS2TRegDatatype*](#)

class State(*value*)

Bases: `IntEnum`

State machine status values

ON = 6

QUICKSTOP = 7

READY = 4

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

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

Returns

the type of the standard communication protocol for this device

disable(*log_warn*: *bool* = *True*, *wait_sec_max*: *int* | *None* = *None*) → *bool*

Disable the driver of the stepper motor and enable the brake.

Note: the driver cannot be disabled if the motor is still running.

Parameters

- **log_warn** – if log a warning in case the motor cannot be disabled.
- **wait_sec_max** – maximal wait time for the motor to stop running and to disable it; by default, with *None*, use a config value

Returns

True if disable request could and was sent, *False* otherwise.

do_ioscanning_write(***kwargs*: *int*) → *None*

Perform a write operation using IO Scanning mode.

Parameters

kwargs – Keyword-argument list with options to send, remaining are taken from the defaults.

enable() → *None*

Enable the driver of the stepper motor and disable the brake.

execute_absolute_position(*position: int*) → bool

Execute a absolute position change, i.e. enable motor, perform absolute position change, wait until done and disable motor afterwards.

Check position at the end if wrong do not raise error; instead just log and return check result.

Parameters

position – absolute position of motor in user defined steps.

Returns

True if actual position is as expected, *False* otherwise.

execute_relative_step(*steps: int*) → bool

Execute a relative step, i.e. enable motor, perform relative steps, wait until done and disable motor afterwards.

Check position at the end if wrong do not raise error; instead just log and return check result.

Parameters

steps – Number of steps.

Returns

True if actual position is as expected, *False* otherwise.

get_dc_volt() → float

Read the DC supply voltage of the motor.

Returns

DC input voltage.

get_error_code() → dict[int, dict[str, Any]]

Read all messages in fault memory. Will read the full error message and return the decoded values. At the end the fault memory of the motor will be deleted. In addition, `reset_error` is called to re-enable the motor for operation.

Returns

Dictionary with all information

get_position() → int

Read the position of the drive and store into status.

Returns

Position step value

get_status() → dict[str, int]

Perform an IO Scanning read and return the status of the motor.

Returns

dict with status information.

get_temperature() → int

Read the temperature of the motor.

Returns

Temperature in degrees Celsius.

jog_run(*direction: bool = True, fast: bool = False*) → *None*

Slowly turn the motor in positive direction.

jog_stop() → *None*

Stop turning the motor in Jog mode.

quickstop() → *None*

Stops the motor with high deceleration rate and falls into error state. Reset with *reset_error* to recover into normal state.

reset_error() → *None*

Resets the motor into normal state after quick stop or another error occurred.

set_jog_speed(slow: int = 60, fast: int = 180) → *None*

Set the speed for jog mode. Default values correspond to startup values of the motor.

Parameters

- **slow** – RPM for slow jog mode.
- **fast** – RPM for fast jog mode.

set_max_acceleration(rpm_minute: int) → *None*

Set the maximum acceleration of the motor.

Parameters

rpm_minute – revolution per minute per minute

set_max_deceleration(rpm_minute: int) → *None*

Set the maximum deceleration of the motor.

Parameters

rpm_minute – revolution per minute per minute

set_max_rpm(rpm: int) → *None*

Set the maximum RPM.

Parameters

rpm – revolution per minute (0 < rpm <= RPM_MAX)

Raises

ILS2TError – if RPM is out of range

set_ramp_type(ramp_type: int = -1) → *None*

Set the ramp type. There are two options available:

0: linear ramp -1: motor optimized ramp

Parameters

ramp_type – 0: linear ramp | -1: motor optimized ramp

start() → *None*

Start this device.

stop() → *None*

Stop this device. Disables the motor (applies brake), disables access and closes the communication protocol.

user_steps(steps: int = 16384, revolutions: int = 1) → *None*

Define steps per revolution. Default is 16384 steps per revolution. Maximum precision is 32768 steps per revolution.

Parameters

- **steps** – number of steps in *revolutions*.
- **revolutions** – number of revolutions corresponding to *steps*.

write_absolute_position(*position: int*) → *None*

Write instruction to turn the motor until it reaches the absolute position. This function does not enable or disable the motor automatically.

Parameters

position – absolute position of motor in user defined steps.

write_relative_step(*steps: int*) → *None*

Write instruction to turn the motor the relative amount of steps. This function does not enable or disable the motor automatically.

Parameters

steps – Number of steps to turn the motor.

```
class ILS2TConfig(rpm_max_init: Integral = 1500, wait_sec_post_enable: int | float = 1,
                  wait_sec_max_disable: int | float = 10, wait_sec_post_cannot_disable: int | float = 1,
                  wait_sec_post_relative_step: int | float = 2, wait_sec_post_absolute_position: int | float = 2)
```

Bases: object

Configuration for the ILS2T stepper motor device.

clean_values()

force_value(*fieldname, value*)

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

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

Parameters

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

is_configdataclass = **True**

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

rpm_max_init: `Integral = 1500`

initial maximum RPM for the motor, can be set up to 3000 RPM. The user is allowed to set a new max RPM at runtime using `ILS2T.set_max_rpm()`, but the value must never exceed this configuration setting.

wait_sec_max_disable: `int | float = 10`

wait_sec_post_absolute_position: `int | float = 2`

wait_sec_post_cannot_disable: `int | float = 1`

wait_sec_post_enable: `int | float = 1`

wait_sec_post_relative_step: `int | float = 2`

exception ILS2TError

Bases: `DeviceError`

Error to indicate problems with the SE ILS2T stepper motor.

class ILS2TModbusTcpCommunication(configuration)

Bases: `ModbusTcpCommunication`

Specific implementation of Modbus/TCP for the Schneider Electric ILS2T stepper motor.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

class ILS2TModbusTcpCommunicationConfig(host: str | IPv4Address | IPv6Address, unit: int = 255, port: int = 502)

Bases: `ModbusTcpCommunicationConfig`

Configuration dataclass for Modbus/TCP communication specific for the Schneider Electric ILS2T stepper motor.

force_value(fieldname, value)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

classmethod `required_keys()` → Sequence[str]

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

Returns

a list of strings containing all required keys.

unit: `int = 255`

The unit has to be 255 such that IO scanning mode works.

class `ILS2TRegAddr(value)`

Bases: IntEnum

Modbus Register Addresses for for Schneider Electric ILS2T stepper drive.

ACCESS_ENABLE = 282

FLT_INFO = 15362

FLT_MEM_DEL = 15112

FLT_MEM_RESET = 15114

IO_SCANNING = 6922

JOGN_FAST = 10506

JOGN_SLOW = 10504

POSITION = 7706

RAMP_ACC = 1556

RAMP_DECEL = 1558

RAMP_N_MAX = 1554

RAMP_TYPE = 1574

SCALE = 1550

TEMP = 7200

VOLT = 7198

class `ILS2TRegDatatype(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1, boundary=None)`

Bases: Enum

Modbus Register Datatypes for Schneider Electric ILS2T stepper drive.

From the manual of the drive:

datatype	byte	min	max
INT8	1 Byte	-128	127
UINT8	1 Byte	0	255
INT16	2 Byte	-32_768	32_767
UINT16	2 Byte	0	65_535
INT32	4 Byte	-2_147_483_648	2_147_483_647
UINT32	4 Byte	0	4_294_967_295
BITS	just 32bits	N/A	N/A

INT32 = (-2147483648, 2147483647)

is_in_range(value: int) → bool

exception IoScanningModeValueError

Bases: *ILS2TError*

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

exception ScalingFactorValueError

Bases: *ILS2TError*

Error to indicate that a scaling factor value is invalid.

Module contents

Device class for controlling a Schneider Electric ILS2T stepper drive over modbus TCP.

hvl_ccb.dev.sst_luminox

Submodules

hvl_ccb.dev.sst_luminox.sst_luminox

Device class for a SST Luminox Oxygen sensor. This device can measure the oxygen concentration between 0 % and 25 %.

Furthermore, it measures the barometric pressure and internal temperature. The device supports two operating modes: in streaming mode the device measures all parameters every second, in polling mode the device measures only after a query.

Technical specification and documentation for the device can be found at the manufacturer's page: <https://www.sstsensing.com/product/luminox-optical-oxygen-sensors-2/>

class Luminox(com, dev_config=None)

Bases: *SingleCommDevice*

Luminox oxygen sensor device class.

activate_output(mode: *LuminoxOutputMode*) → None

activate the selected output mode of the Luminox Sensor. :param mode: polling or streaming

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls()

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

Returns

the type of the standard communication protocol for this device


```
query_polling(measurement: str | LuminoxMeasurementType) → dict[Union[str,  
    hvl_ccb.dev.sst_luminox.sst_luminox.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, hvl_ccb.dev.sst_luminox.sst_luminox.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: int | float = 0.5, wait_sec_trials_activate: int | float = 0.1,  
    nr_trials_activate: int = 5)
```

Bases: object

Configuration for the SST Luminox oxygen sensor.

```
clean_values()
```

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

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

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

Parameters

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

```
is_configdataclass = True
```

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

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

nr_trials_activate: int = 5

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

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

Returns

a list of strings containing all optional keys.

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

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

Returns

a list of strings containing all required keys.

wait_sec_post_activate: int | float = 0.5

wait_sec_trials_activate: int | float = 0.1

exception **LuminoxError**

Bases: [DeviceError](#)

General Error for Luminox Device.

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

Bases: [ValueEnum](#)

Measurement types for *LuminoxOutputMode.polling*.

The *all_measurements* type will read values for the actual measurement types as given in *LuminoxOutputMode.all_measurements_types()*; it parses multiple single values using regexp's for other measurement types, therefore, no regexp is defined for this measurement type.

all_measurements = 'A'

classmethod **all_measurements_types()** → tuple['LuminoxMeasurementType', ...]

A tuple of *LuminoxMeasurementType* enum instances which are actual measurements, i.e. not date of manufacture or software revision.

barometric_pressure = 'P'

property **command:** str

date_of_manufacture = '# 0'

parse_read_measurement_value(read_txt: str) → dict[Union[str, [hvl_ccb.dev.sst_luminox.sst_luminox.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.

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

Bases: [SerialCommunicationConfig](#)

baudrate: `int = 9600`

Baudrate for SST Luminos is 9600 baud

bytesize: `int | SerialCommunicationBytesize = 8`

One byte is eight bits long

force_value(*fieldname*, *value*)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

parity: `str | SerialCommunicationParity = 'N'`

SST Luminos does not use parity

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

stopbits: `int | SerialCommunicationStopbits = 1`

SST Luminos does use one stop bit

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

The terminator is CR LF

```
timeout: int | float = 3
```

use 3 seconds timeout as default

Module contents

Device class for a SST Luminox Oxygen sensor. This device can measure the oxygen concentration between 0 % and 25 %.

Furthermore, it measures the barometric pressure and internal temperature. The device supports two operating modes: in streaming mode the device measures all parameters every second, in polling mode the device measures only after a query.

Technical specification and documentation for the device can be found at the manufacturer's page: <https://www.sstsensing.com/product/luminox-optical-oxygen-sensors-2/>

hvl_ccb.dev.technix

Submodules

hvl_ccb.dev.technix.base

Communication and auxiliary classes for Technix

exception `TechnixError`

Bases: `DeviceError`

Technix related errors.

exception `TechnixFaultError`

Bases: `TechnixError`

Raised when the fault flag was detected while the interlock is closed

class `TechnixSerialCommunication(configuration)`

Bases: `_TechnixCommunication`, `SerialCommunication`

Serial communication for Technix

static `config_cls()`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

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

Bases: `_TechnixCommunicationConfig`, `SerialCommunicationConfig`

Configuration for the serial communication for Technix

force_value(*fieldname*, *value*)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

```
class TechnixTelnetCommunication(configuration)
```

Bases: `TelnetCommunication`, `_TechnixCommunication`

Telnet communication for Technix

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

```
class TechnixTelnetCommunicationConfig(terminator: bytes = b'\r', encoding: str = 'utf-8',
                                       encoding_error_handling: str = 'strict',
                                       wait_sec_read_text_nonempty: int | float = 0.5,
                                       default_n_attempts_read_text_nonempty: int = 10, host: str |
                                       IPv4Address | IPv6Address | None = None, port: int = 4660,
                                       timeout: int | float = 0.2)
```

Bases: `_TechnixCommunicationConfig`, `TelnetCommunicationConfig`

Configuration for the telnet communication for Technix

force_value(fieldname, value)

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

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

Parameters

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

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

port: int = 4660

Port at which Technix is listening

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

hvl_ccb.dev.technix.device

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: `int | float | None`

Actual current of the output in A

default_com_cls() → `type[hvl_ccb.dev.technix.base.TechnixSerialCommunication] | type[hvl_ccb.dev.technix.base.TechnixTelnetCommunication]`

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

Returns

the type of the standard communication protocol for this device

property inhibit: `bool | None`

Is the output of the voltage inhibited? The output stage can still be active.

property is_started: `bool`

Is the device started?

property max_current: `int | float`

Maximal output current of the hardware in A

property max_voltage: `int | float`

Maximal output voltage of the hardware in V

property open_interlock: `bool | None`

Is the interlock open? (in safe mode)

property output: `bool | None`

State of the high voltage output

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

Query the status of the device.

Returns

This function returns nothing

property remote: `bool | None`

Is the device in remote control mode?

start()

Start the device and set it into the remote controllable mode. The high voltage is turn off, and the status poller is started.

property status: `_Status | None`

The status of the device with the different states as sub-fields

stop()

Stop the device. The status poller is stopped and the high voltage output is turn off.

property voltage: `int | float | None`

Actual voltage at the output in V

property voltage_regulation: `bool | None`

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

class TechnixConfig(*communication_channel: type[hvl_ccb.dev.technix.base.TechnixSerialCommunication] | type[hvl_ccb.dev.technix.base.TechnixTelnetCommunication], max_voltage: int | float, max_current: int | float, polling_interval_sec: int | float = 4, post_stop_pause_sec: int | float = 1, register_pulse_time: int | float = 0.1, read_output_while_polling: bool = False*)

Bases: `object`

clean_values()

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

communication_channel: `type[hvl_ccb.dev.technix.base.TechnixSerialCommunication] | type[hvl_ccb.dev.technix.base.TechnixTelnetCommunication]`

communication channel between computer and Technix

force_value(fieldname, value)

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

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

Parameters

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

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

max_current: int | float

Maximal Output current

max_voltage: int | float

Maximal Output voltage

classmethod optional_defaults() → dict[str, object]

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

Returns

a list of strings containing all optional keys.

polling_interval_sec: int | float = 4

Polling interval in s to maintain to watchdog of the device

post_stop_pause_sec: int | float = 1

Time to wait after stopping the device

read_output_while_polling: bool = False

Read output voltage and current within the polling event

register_pulse_time: int | float = 0.1

Time for pulsing a register

classmethod required_keys() → Sequence[str]

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

Returns

a list of strings containing all required keys.

Module contents

Device classes for “RS 232” and “Ethernet” interfaces, which are used to control power supplies from Technix. Manufacturer homepage: <https://www.technix-hv.com>

The regulated power supplies series and capacitor chargers series from Technix are series of low and high voltage direct current power supplies as well as capacitor chargers. The class *Technix* is tested with a CCR10KV-7,5KJ via an ethernet connection as well as a CCR15-P-2500-OP via a serial connection. Check the code carefully before using it with other devices or device series

This Python package may support the following interfaces from Technix:

- Remote Interface RS232
- Ethernet Remote Interface
- Optic Fiber Remote Interface

hvl_ccb.dev.tiepie

Submodules

hvl_ccb.dev.tiepie.base

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:
```

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```
: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
```

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```
.. 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, hvl_ccb.dev.base.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, [hvl_ccb.dev.base.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, *hvl_ccb.dev.base.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, *hvl_ccb.dev.base.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[hvl_ccb.comm.base.CommunicationProtocol]

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

Returns

the type of the standard communication protocol for this device

start() → None

Open the associated communication protocol.

stop() → None

Close the associated communication protocol.

hvl_ccb.dev.utils

hvl_ccb.dev.visa

class VisaDevice(com: VisaCommunication | VisaCommunicationConfig | dict, dev_config: VisaDeviceConfig | dict | None = None)

Bases: *SingleCommDevice*

Device communicating over the VISA protocol using VisaCommunication.

static config_cls()

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

static default_com_cls() → type[hvl_ccb.comm.visa.VisaCommunication]

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

Returns

the VisaCommunication class

get_error_queue() → str

Read out error queue and logs the error.

Returns

Error string

get_identification() → str

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

Returns

the identification string of the connected device

reset() → None

Send “*RST” and “*CLS” to the device. Typically sets a defined state.

spoll_handler()

Reads the status byte and decodes it. The status byte STB is defined in IEEE 488.2. It provides a rough overview of the instrument status.

Returns

start() → None

Start the VisaDevice. Sets up the status poller and starts it.

Returns

stop() → None

Stop the VisaDevice. Stops the polling thread and closes the communication protocol.

Returns

wait_operation_complete(timeout: float | None = None) → bool

Waits for a operation complete event. Returns after timeout [s] has expired or the operation complete event has been caught.

Parameters

timeout – Time in seconds to wait for the event; None for no timeout.

Returns

True, if OPC event is caught, False if timeout expired

class VisaDeviceConfig(spoll_interval: int | float = 0.5, spoll_start_delay: int | float = 2)

Bases: _VisaDeviceConfigDefaultsBase, _VisaDeviceConfigBase

Configdataclass for a VISA device.

force_value(*fieldname*, *value*)

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

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

Parameters

- **fieldname** – name of the field
- **value** – value to assign

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

Module contents

Devices subpackage.

hvl_ccb.utils

Subpackages

hvl_ccb.utils.conversion

Submodules

hvl_ccb.utils.conversion.map_range

```
class MapBitAsymRange(value: int | float, bit: int, dtype_1: ~numpy.dtype[~typing.Any] | None |
    ~typing.Type[~typing.Any] |
    ~numpy._typing._dtype_like._SupportsDType[~numpy.dtype[~typing.Any]] | str |
    ~typing.Tuple[~typing.Any, int] | ~typing.Tuple[~typing.Any, ~typing.SupportsIndex |
    ~typing.Sequence[~typing.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: int | float, bit: int, dtype_1: ~numpy.dtype[~typing.Any] | None |
    ~typing.Type[~typing.Any] |
    ~numpy._typing._dtype_like._SupportsDType[~numpy.dtype[~typing.Any]] | str |
    ~typing.Tuple[~typing.Any, int] | ~typing.Tuple[~typing.Any, ~typing.SupportsIndex |
    ~typing.Sequence[~typing.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: dtype[Any] | None | Type[Any] | _SupportsDType[dtype[Any]] | str |
    Tuple[Any, int] | Tuple[Any, SupportsIndex | Sequence[SupportsIndex]] | List[Any] |
    _DTypeDict | Tuple[Any, Any], dtype_2: dtype[Any] | None | Type[Any] |
    _SupportsDType[dtype[Any]] | str | Tuple[Any, int] | Tuple[Any, SupportsIndex |
    Sequence[SupportsIndex]] | List[Any] | _DTypeDict | Tuple[Any, Any], logger=None)
```

Bases: `object`

convert_to_range1(value, **kwargs)

convert_to_range2(value, **kwargs)

hvl_ccb.utils.conversion.sensor

Sensors that are used by the devices implemented in the CCB

class **LEM4000S**

Bases: `Sensor`

CONVERSION

calibration_factor

convert(value, **kwargs)

shunt

class **LMT70A**

Bases: `Sensor`

Converts the output voltage (V) to the measured temperature (default °C) when using a TI Precision Analog Temperature Sensor LMT70(A)

LUT

convert(value, **kwargs)

temperature_unit

class **Sensor**

Bases: `ABC`

abstract convert(value, **kwargs)

hvl_ccb.utils.conversion.unit

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"
```

(continues on next page)

(continued from previous page)

```
E.a != 2
E.a != "2"
```

The access would be normally with `E["a"]`, but `E("a")` works also. Therefore, `E["a"] == E("a")`

Attention: to avoid errors, best use together with *unique* enum decorator.

```
class RangeEnum(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                 boundary=None)
```

Bases: float, [ValueEnum](#)

Range enumeration inherit from ValueEnum, find suitable voltage/current/resistance input range for devices such as multimeter and oscilloscope

```
abstract classmethod unit() → str
```

Returns the Unit of the values in the enumeration. :return: the unit of the values in the enumeration in string format

```
class StrEnumBase(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                 boundary=None)
```

Bases: Enum

String representation-based equality and lookup.

```
class ValueEnum(value=<no_arg>, names=None, module=None, qualname=None, type=None, start=1,
                 boundary=None)
```

Bases: [StrEnumBase](#)

Enum with string representation of values used as string representation, and with lookup and equality based on this representation. Values do not need to be of type 'str', but they need to have a str-representation to enable this feature. The lookup is implemented in StrEnumBase with the `_missing_value_` method. The equality is also defined at this place (`__eq__`).

Use-case:

```
class E(ValueEnum):
    ONE = 1

E.ONE == "1"
E.ONE != 1
E.ONE != "ONE"
```

The access would be normally with `E(1)`, but `E("1")` works also. Therefore, `E(1) == E("1")`

Attention: to avoid errors, best use together with *unique* enum decorator.

hvl_ccb.utils.poller

```
class Poller(spoll_handler: Callable, polling_delay_sec: int | float = 0, polling_interval_sec: int | float = 1,
             polling_timeout_sec: int | float | None = None)
```

Bases: object

Poller class wrapping `concurrent.futures.ThreadPoolExecutor` which enables passing of results and errors out of the polling thread.

is_polling() → bool

Check if device status is being polled.

Returns

True when polling thread is set and alive

start_polling() → bool

Start polling.

Returns

True if was not polling before, *False* otherwise

stop_polling() → bool

Stop polling.

Wait for until polling function returns a result as well as any exception / error that might have been raised within a thread.

Returns

True if was polling before, *False* otherwise, and last result of the polling function call.

Raises

polling function exceptions

wait_for_polling_result()

Wait for until polling function returns a result as well as any exception / error that might have been raised within a thread.

Returns

polling function result

Raises

polling function errors

hvl_ccb.utils.typing

Additional Python typing module utilities

ConvertibleTypes

Typing hint for data type that can be used in conversion

alias of Union[int, float, list[Union[int, float]], tuple[Union[int, float], ...], dict[str, Union[int, float]], ndarray[Any, dtype[ScalarType]]]

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: str | IPv4Address | IPv6Address, logger: Logger | None = None*) → *str*

validate_bool(*x_name: str, x: object, logger: Logger | None = None*) → *None*

Validate if given input *x* is a *bool*.

Parameters

- **x_name** – string name of the validate input, use for the error message
- **x** – an input object to validate as boolean
- **logger** – logger of the calling submodule

Raises

TypeError – when the validated input does not have boolean type

validate_number(*x_name: str, x: object, limits: tuple | None = (None, None), number_type: type[typing.Union[int, float]] | tuple[type[typing.Union[int, float]], ...] = (<class 'int'>, <class 'float'>), logger: ~logging.Logger | None = None*) → *None*

Validate if given input *x* is a number of given *number_type* type, with value between given *limits[0]* and *limits[1]* (inclusive), if not *None*. For array-like objects (npt.NDArray, list, tuple, dict) it is checked if all elements are within the limits and have the correct type.

Parameters

- **x_name** – string name of the validate input, use for the error message
- **x** – an input object to validate as number of given type within given range
- **logger** – logger of the calling submodule
- **limits** – [lower, upper] limit, with *None* denoting no limit: [-inf, +inf]
- **number_type** – expected type or tuple of types of a number, by default (*int*, *float*)

Raises

- **TypeError** – when the validated input does not have expected type
- **ValueError** – when the validated input has correct number type but is not within given range or has wrong input limits

validate_tcp_port(*port: int, logger: Logger | None = None*)

Module contents

4.1.2 Submodules

`hvl_ccb.configuration`

Facilities providing classes for handling configuration for communication protocols and devices.

class `ConfigurationMixin(configuration)`

Bases: `ABC`

Mixin providing configuration to a class.

property `config`

ConfigDataclass property.

Returns

the configuration

abstract static `config_cls()`

Return the default configdataclass class.

Returns

a reference to the default configdataclass class

configuration_save_json(path: str) → None

Save current configuration as JSON file.

Parameters

path – path to the JSON file.

classmethod `from_json(filename: str)`

Instantiate communication protocol using configuration from a JSON file.

Parameters

filename – Path and filename to the JSON configuration

exception `ConfigurationValueWarning`

Bases: `UserWarning`

User warnings category for values of `@configdataclass` fields.

class `EmptyConfig`

Bases: `object`

Empty configuration dataclass.

clean_values()

Cleans and enforces configuration values. Does nothing by default, but may be overridden to add custom configuration value checks.

force_value(fieldname, value)

Forces a value to a dataclass field despite the class being frozen.

NOTE: you can define `post_force_value` method with same signature as this method to do extra processing after `value` has been forced on `fieldname`.

Parameters

- **fieldname** – name of the field

- **value** – value to assign

is_configdataclass = True

classmethod keys() → Sequence[str]

Returns a list of all configdataclass fields key-names.

Returns

a list of strings containing all keys.

classmethod optional_defaults() → dict[str, object]

Returns a list of all configdataclass fields, that have a default value assigned and may be optionally specified on instantiation.

Returns

a list of strings containing all optional keys.

classmethod required_keys() → Sequence[str]

Returns a list of all configdataclass fields, that have no default value assigned and need to be specified on instantiation.

Returns

a list of strings containing all required keys.

configdataclass(*direct_decoration=None, frozen=True*)

Decorator to make a class a configdataclass. Types in these dataclasses are enforced. Implement a function `clean_values(self)` to do additional checking on value ranges etc.

It is possible to inherit from a configdataclass and re-decorate it with `@configdataclass`. In a subclass, default values can be added to existing fields. Note: adding additional non-default fields is prone to errors, since the order has to be respected through the whole chain (first non-default fields, only then default-fields).

Parameters

frozen – defaults to True. False allows to later change configuration values. Attention: if configdataclass is not frozen and a value is changed, typing is not enforced anymore!

hvl_ccb.error

Introduce a common code base error for the CCB

exception CCBError

Bases: Exception

hvl_ccb.experiment_manager

Main module containing the top level ExperimentManager class. Inherit from this class to implement your own experiment functionality in another project and it will help you start, stop and manage your devices.

exception ExperimentError

Bases: [CCBError](#)

Error to indicate that the current status of the experiment manager is on ERROR and thus no operations can be made until reset.

class ExperimentManager(*args, **kwargs)

Bases: [DeviceSequenceMixin](#)

Experiment Manager can start and stop communication protocols and devices. It provides methods to queue commands to devices and collect results.

add_device(*name: str, device: Device*) → *None*

Add a new device to the manager. If the experiment is running, automatically start the device. If a device with this name already exists, raise an error.

Parameters

- **name** – is the name of the device.
- **device** – is the instantiated Device object.

Raises

ExperimentError –

devices_failed_start: dict[str, *hvl_ccb.dev.base.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, *hvl_ccb.dev.base.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.

CONTRIBUTING

Contributions are welcome, and they are greatly appreciated! Every little bit helps, and credit will always be given. You can contribute in many ways:

5.1 Types of Contributions

5.1.1 Report Bugs

Report bugs at https://gitlab.com/ethz_hvl/hvl_ccb/issues.

If you are reporting a bug, please include:

- Your operating system name and version.
- Any details about your local setup that might be helpful in troubleshooting.
- Detailed steps to reproduce the bug.

5.1.2 Fix Bugs

Look through the GitLab issues for bugs. Anything tagged with “bug” and “help wanted” is open to whoever wants to implement it.

5.1.3 Implement Features

Look through the GitLab issues for features. Anything tagged with “enhancement” and “help wanted” is open to whoever wants to implement it.

5.1.4 Write Documentation

HVL Common Code Base could always use more documentation, whether as part of the official HVL Common Code Base docs, in docstrings, or even on the web in blog posts, articles, and such.

5.1.5 Submit Feedback

The best way to send feedback is to file an issue at https://gitlab.com/ethz_hvl/hvl_ccb/issues.

If you are proposing a feature:

- Explain in detail how it would work.
- Keep the scope as narrow as possible, to make it easier to implement.
- Remember that this is a volunteer-driven project, and that contributions are welcome :)

5.2 Get Started!

Ready to contribute? Here's how to set up *hvl_ccb* for local development.

1. Clone *hvl_ccb* repo from GitLab:

```
$ git clone git@gitlab.com:ethz_hvl/hvl_ccb.git
```

2. Go into the cloned folder. Then install your virtual environment and activate it:

```
$ cd hvl_ccb
$ python -m venv .venv
$ . .venv/Scripts/activate # <-- for Windows
$ . .venv_22/bin/activate  # <-- for Linux
```

3. Install the HVL-CommonCodeBase with its dependencies as well as the dependencies for development:

```
$ pip install -e .[all]
$ pip install -r requirements_dev.txt
```

4. Furthermore, it is recommended to install the git hook script shipped within the repository:

```
$ pre-commit install
```

5. After creating an Issue and Merge Request on GitLab, you can switch to you created development branch:

```
$ git switch name-of-your-bugfix-or-feature
```

Now you can make your changes locally.

6. When you're done making changes, check that your changes pass flake8, mypy, black, isort and the tests, including testing other Python versions with tox:

```
$ isort .
$ black --preview hvl_ccb/ tests/ examples/
$ flake8 hvl_ccb tests
$ mypy --show-error-codes hvl_ccb
$ python setup.py test or py.test
$ tox
```

You can also use the provided make-like shell script to run flake8 and tests:

```
$ ./make.sh black
$ ./make.sh isort
$ ./make.sh style
$ ./make.sh type
$ ./make.sh test
```

7. As we want to maintain a high quality of coding style we use *black* and *isort*. This style is checked with the pipelines on gitlab.com. Ensure that your commits include only properly formatted code. One way to comply is to install and use *pre-commit*. This package includes the necessary configuration.
8. Commit your changes and push your branch to GitLab:

```
$ git add .
$ git commit -m "Your detailed description of your changes."
$ git push
```

9. Request a review of your merge request through the GitLab website.

5.3 Merge Request Guidelines

Before you submit a merge request, check that it meets these guidelines:

1. The merge request should include tests.
2. If the merge request adds functionality, the docs should be updated. Put your new functionality into a function with a docstring, and add the feature to the list in README.rst.
3. The merge request should work for Python 3.9 to 3.10. Check https://gitlab.com/ethz_hvl/hvl_ccb/merge_requests and make sure that the tests pass for all supported Python versions.

5.4 Tips

- To run tests from a single file:

```
$ py.test tests/test_hvl_ccb.py
```

or a single test function:

```
$ py.test tests/test_hvl_ccb.py::test_command_line_interface
```

- If your tests are slow, profile them using the pytest-profiling plugin:

```
$ py.test tests/test_hvl_ccb.py --profile
```

or for a graphical overview (you need a SVG image viewer):

```
$ py.test tests/test_hvl_ccb.py --profile-svg
$ open prof/combined.svg
```

- To add dependency, edit appropriate **requirements* variable in the *setup.py* file and re-run:

```
$ python setup.py develop
```

- To generate a PDF version of the Sphinx documentation instead of HTML use:

```
$ rm -rf docs/hvl_ccb.rst docs/modules.rst docs/_build && sphinx-apidoc -o docs/hvl_
→ccb && python -msphinx -M latexpdf docs/ docs/_build
```

This command can also be run through the make-like shell script:

```
$ ./make.sh docs-pdf
```

This requires a local installation of a LaTeX distribution, e.g. MikTeX.

5.5 Deploying

A reminder for the maintainers on how to deploy.

Make sure all your changes are committed and that all relevant MR are merged. Then switch to `devel`, update it and create `release-N.M.K` branch:

```
$ git switch devel
$ git pull
$ git checkout -b release-N.M.K
```

- Update copyright information (if necessary) in `docs/conf.py` and `README.rst`
- Update or create entry in `HISTORY.rst` (commit message: Update HISTORY.rst: release N.M.K).
- Update, if applicable, `AUTHORS.rst` (commit message: Update AUTHORS.rst: release N.M.K)
- Update features tables in `README.rst` file (commit message: Update README.rst: release N.M.K)
- Update API docs (commit message: Update API-docs: release N.M.K)

```
$ ./make.sh docs # windows
$ make docs # unix-based-os
```

Commit all of the above, except for

- `docs/hvl_ccb.dev.picotech_pt104.rst`
- `docs/hvl_ccb.dev.tiepie.base.rst`
- `docs/hvl_ccb.dev.tiepie.channel.rst`
- `docs/hvl_ccb.dev.tiepie.device.rst`
- `docs/hvl_ccb.dev.tiepie.generator.rst`
- `docs/hvl_ccb.dev.tiepie.i2c.rst`
- `docs/hvl_ccb.dev.tiepie.oscilloscope.rst`
- `docs/hvl_ccb.dev.tiepie.utils.rst`.

Before you continue revert the changes in this file.

Then run:

```
$ 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 pull 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”.

6.1 Active Maintainers

- Chi-Ching Hsu <hsu@eeh.ee.ethz.ch>
- Henning Janssen <janssen@eeh.ee.ethz.ch>

6.2 Authors and Contributors

- Alise Chachereau (Author)
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- Ruben Stadler (Contributor)
- David Taylor (Author)
- Hanut Vemulapalli (Contributor)

HISTORY

7.1 0.13.1 (2023-03-03)

- **Repository maintenance**
 - add the option to manually set `n_attempts_max` and `attempt_interval_sec` in query of the `SyncCommunicationProtocol`
 - fix links in description for `Heinzinger` digital interface and universal high voltage power supplies
 - keep copyright year information only in `docs/conf.py` and `README.rst`
 - remove copyright year information from the files
 - fix `readthedocs` build failed issue
 - update code style to `black 23.1.0`

7.2 0.13.0 (2023-01-27)

- **Drop support for Python 3.7 and 3.8:**
 - remove version dependent implementations
 - changed typing acc. to PEP 585
- Un-freeze version number of dependencies and upgrade to most recent versions

7.3 0.12.3 (2022-12-27)

- **Code improvements for device cube:**
 - split alarms from constants
 - split errors from constants
 - split earthing_stick from constants
 - split support from constants
- Update code style to `black 22.12.0`
- **Smaller change of device tiepie:**
 - change hard coded trigger time out value for no time out/infinite (-1) to `ltp.const.TO_INFINITY`

7.4 0.12.2 (2022-11-29)

- Move the device modules into packages
- Bugfix in `validate_number` to check the order of the limits
- **Repository maintenance:**
 - imports are sorted with `isort`
 - some mypy fixing and additional typing

7.5 0.12.1 (2022-10-31)

- **Fix numpy version requirement problem**
 - for Python 3.7: 1.21.6
 - for Python 3.8 and onwards: 1.23.4

7.6 0.12.0 (2022-10-17)

- Last release for Python 3.7 and 3.8
- **Repository maintenance**
 - update Labjack LJM software installer link in the pipeline
 - fix dependencies to the fixed version
 - fix `asyncua` to 0.9.95 and `pymodbus` to 2.5.3 (newer versions break the code)
 - fix PICube checker for slope as it is always positive

7.7 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

7.8 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

7.9 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

7.10 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`

7.11 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

7.12 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)

7.13 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`.

7.14 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.

7.15 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.

7.16 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.

7.17 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.

7.18 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.

7.19 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.

7.20 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.

7.21 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.

7.22 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.

7.23 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`.

7.24 0.5.0 (2020-11-11)

- TiePie USB oscilloscope, generator and I2C host devices, as a wrapper of the Python bindings for the LibTiePie SDK.
- a FuG Elektronik Power Supply (e.g. Capacitor Charger HCK) using the built-in ADDAT controller with the Probus V protocol over a serial connection
- All devices polling status or measurements use now a `dev.utils.Poller` utility class.
- **Extensions and improvements in existing devices:**
 - In `dev.rs_rto1024.RTO1024`: added Channel state, scale, range, position and offset accessors, and measurements activation and read methods.
 - In `dev.sst_luminox.Luminox`: added querying for all measurements in polling mode, and made output mode activation more robust.
 - In `dev.newport.NewportSMC100PP`: an error-prone `wait_until_move_finished` method of replaced by a fixed waiting time, device operations are now robust to a power supply cut, and device restart is not required to apply a start configuration.
- **Other minor improvements:**
 - Single failure-safe starting and stopping of devices sequenced via `dev.base.DeviceSequenceMixin`.
 - Moved `read_text_nonempty` up to `comm.serial.SerialCommunication`.
 - Added development Dockerfile.
 - Updated package and development dependencies: `pymodbus`, `pytest-mock`.

7.25 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.

7.26 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).

7.27 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.

7.28 0.3.3 (2019-05-08)

- Use PyPI labjack-ljm (no external dependencies)

7.29 0.3.2 (2019-05-08)

- INSTALLATION.rst with LJMPython prerequisite info

7.30 0.3.1 (2019-05-02)

- readthedocs.org support

7.31 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)

7.32 0.2.1 (2019-04-01)

- Fix issue with LJMPython not being installed automatically with setuptools.

7.33 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.

7.34 0.1.0 (2019-02-06)

- Communication protocol base and serial communication implementation.
- Device base and MBW973 implementation.

INDICES AND TABLES

- `genindex`
- `modindex`
- `search`

PYTHON MODULE INDEX

h

- [hvl_ccb](#), 175
- [hvl_ccb.comm](#), 32
 - [hvl_ccb.comm.base](#), 11
 - [hvl_ccb.comm.labjack_ljm](#), 15
 - [hvl_ccb.comm.modbus_tcp](#), 18
 - [hvl_ccb.comm.opc](#), 20
 - [hvl_ccb.comm.serial](#), 23
 - [hvl_ccb.comm.tcp](#), 26
 - [hvl_ccb.comm.telnet](#), 27
 - [hvl_ccb.comm.visa](#), 29
- [hvl_ccb.configuration](#), 172
- [hvl_ccb.dev](#), 165
 - [hvl_ccb.dev.base](#), 160
 - [hvl_ccb.dev.crylas](#), 43
 - [hvl_ccb.dev.crylas.crylas](#), 32
 - [hvl_ccb.dev.cube](#), 55
 - [hvl_ccb.dev.cube.alarms](#), 43
 - [hvl_ccb.dev.cube.base](#), 43
 - [hvl_ccb.dev.cube.constants](#), 48
 - [hvl_ccb.dev.cube.earthing_stick](#), 51
 - [hvl_ccb.dev.cube.errors](#), 51
 - [hvl_ccb.dev.cube.picube](#), 52
 - [hvl_ccb.dev.cube.support](#), 55
 - [hvl_ccb.dev.ea_psi9000](#), 59
 - [hvl_ccb.dev.ea_psi9000.ea_psi9000](#), 55
 - [hvl_ccb.dev.fluke884x](#), 67
 - [hvl_ccb.dev.fluke884x.base](#), 60
 - [hvl_ccb.dev.fluke884x.constants](#), 64
 - [hvl_ccb.dev.fluke884x.ranges](#), 65
 - [hvl_ccb.dev.fug](#), 80
 - [hvl_ccb.dev.fug.fug](#), 67
 - [hvl_ccb.dev.heinzinger](#), 87
 - [hvl_ccb.dev.heinzinger.base](#), 81
 - [hvl_ccb.dev.heinzinger.constants](#), 87
 - [hvl_ccb.dev.highland_t560](#), 92
 - [hvl_ccb.dev.highland_t560.base](#), 88
 - [hvl_ccb.dev.highland_t560.channel](#), 90
 - [hvl_ccb.dev.highland_t560.device](#), 90
 - [hvl_ccb.dev.labjack](#), 99
 - [hvl_ccb.dev.labjack.labjack](#), 92
 - [hvl_ccb.dev.lauda](#), 107
 - [hvl_ccb.dev.lauda.lauda](#), 100
 - [hvl_ccb.dev.mbw973](#), 111
 - [hvl_ccb.dev.mbw973.mbw973](#), 107
 - [hvl_ccb.dev.newport](#), 126
 - [hvl_ccb.dev.newport.newport](#), 111
 - [hvl_ccb.dev.pfeiffer_tpg](#), 132
 - [hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg](#), 126
 - [hvl_ccb.dev.rs_rto1024](#), 141
 - [hvl_ccb.dev.rs_rto1024.rs_rto1024](#), 132
 - [hvl_ccb.dev.se_ils2t](#), 148
 - [hvl_ccb.dev.se_ils2t.se_ils2t](#), 141
 - [hvl_ccb.dev.sst_luminox](#), 153
 - [hvl_ccb.dev.sst_luminox.sst_luminox](#), 148
 - [hvl_ccb.dev.technix](#), 158
 - [hvl_ccb.dev.technix.base](#), 153
 - [hvl_ccb.dev.technix.device](#), 155
 - [hvl_ccb.dev.utils](#), 163
 - [hvl_ccb.dev.visa](#), 163
 - [hvl_ccb.error](#), 173
 - [hvl_ccb.experiment_manager](#), 173
 - [hvl_ccb.utils](#), 172
 - [hvl_ccb.utils.conversion](#), 168
 - [hvl_ccb.utils.conversion.map_range](#), 165
 - [hvl_ccb.utils.conversion.sensor](#), 166
 - [hvl_ccb.utils.conversion.unit](#), 167
 - [hvl_ccb.utils.conversion.utils](#), 168
 - [hvl_ccb.utils.enum](#), 168
 - [hvl_ccb.utils.poller](#), 169
 - [hvl_ccb.utils.typing](#), 170
 - [hvl_ccb.utils.validation](#), 171

A

- A (*HeinzingerPNC.UnitCurrent* attribute), 84
 - ABSOLUTE_POSITION (*ILS2T.ActionsPtp* attribute), 141
 - AC (*NewportConfigCommands* attribute), 111
 - AC_100KV (*PowerSetup* attribute), 50
 - AC_150KV (*PowerSetup* attribute), 50
 - AC_200KV (*PowerSetup* attribute), 50
 - AC_50KV (*PowerSetup* attribute), 50
 - ac_current_range (*Fluke8845a* attribute), 60
 - ac_voltage_range (*Fluke8845a* attribute), 60
 - acceleration (*NewportSMC100PPConfig* attribute), 120
 - ACCESS_ENABLE (*ILS2TRegAddr* attribute), 147
 - access_lock (*CommunicationProtocol* attribute), 14
 - ACCurrentRange (class in *hvl_ccb.dev.fluke884x.ranges*), 65
 - ACTION_JOG_VALUE (*ILS2T* attribute), 141
 - activate_clock_output() (*T560* method), 90
 - activate_measurements() (*RTO1024* method), 133
 - activate_output() (*Luminox* method), 148
 - activate_remote_mode() (*Fluke8845a* method), 60
 - ACTIVE (*CryLasLaser.AnswersStatus* attribute), 36
 - active_alarms() (*BaseCube* method), 43
 - ACTIVE_HIGH (*Polarity* attribute), 88
 - ACTIVE_LOW (*Polarity* attribute), 88
 - actualsetvalue (*FuGProbusVSetRegisters* property), 77
 - ACVoltageRange (class in *hvl_ccb.dev.fluke884x.ranges*), 65
 - adc_mode (*FuGProbusVMonitorRegisters* property), 76
 - add_device() (*DeviceSequenceMixin* method), 161
 - add_device() (*ExperimentManager* method), 173
 - ADDR_INCORRECT (NewportSMC100PPSerialCommunication.ControllerBase attribute), 121
 - address (*NewportSMC100PPConfig* attribute), 120
 - address (*VisaCommunicationConfig* property), 31
 - address() (*VisaCommunicationConfig.InterfaceType* method), 30
 - ADMODE (*FuGProbusIVCommands* attribute), 73
 - all_measurements (*LuminoxMeasurementType* attribute), 150
 - all_measurements_types() (*LuminoxMeasurementType* class method), 150
 - ANALOG (*LaudaProRp245eConfig.ExtControlModeEnum* attribute), 104
 - analog_control (*FuGProbusVDIRegisters* property), 75
 - ANY (*LabJack.DeviceType* attribute), 94
 - ANY (*LJMCommunicationConfig.ConnectionType* attribute), 16
 - ANY (*LJMCommunicationConfig.DeviceType* attribute), 17
 - ApertureRange (class in *hvl_ccb.dev.fluke884x.ranges*), 65
 - AsyncCommunicationProtocol (class in *hvl_ccb.comm.base*), 11
 - AsyncCommunicationProtocolConfig (class in *hvl_ccb.comm.base*), 13
 - ATM (*Pressure* attribute), 167
 - ATMOSPHERE (*Pressure* attribute), 167
 - attenuation (*CryLasAttenuator* property), 33
 - AUTO (*EarthingStickOperatingStatus* attribute), 51
 - AUTO (*LaudaProRp245eConfig.OperationModeEnum* attribute), 104
 - AUTO (*RTO1024.TriggerModes* attribute), 133
 - auto_install_mode (*T560* property), 90
 - auto_install_mode (*T560Config* attribute), 91
 - auto_laser_on (*CryLasLaserConfig* attribute), 39
 - AutoInstallMode (class in *hvl_ccb.dev.highland_t560.base*), 88
 - AutoNumberNameEnum (class in *hvl_ccb.utils.enum*), 168
- ## B
- BA (*NewportConfigCommands* attribute), 111
 - BacklashCompensation (*NewportSMC100PPConfig* attribute), 120
 - backup_waveform() (*RTO1024* method), 133
 - BAR (*Pressure* attribute), 167
 - barometric_pressure (*LuminoxMeasurementType* attribute), 150
 - base_velocity (*NewportSMC100PPConfig* attribute), 120
 - BaseCube (class in *hvl_ccb.dev.cube.base*), 43

BaseCubeConfiguration (class in **C**
hvl_ccb.dev.cube.base), 46

BaseCubeOpcUaCommunication (class in
hvl_ccb.dev.cube.base), 47

BaseCubeOpcUaCommunicationConfig (class in
hvl_ccb.dev.cube.base), 47

BATH_TEMP (*LaudaProRp245eCommand* attribute), 102

baudrate (*CryLasAttenuatorSerialCommunicationConfig* attribute), 35

baudrate (*CryLasLaserSerialCommunicationConfig* attribute), 42

baudrate (*FuGSerialCommunicationConfig* attribute), 79

baudrate (*HeinzingerSerialCommunicationConfig* attribute), 86

baudrate (*LuminosSerialCommunicationConfig* attribute), 152

baudrate (*MBW973SerialCommunicationConfig* attribute), 110

baudrate (*NewportSMC100PPSerialCommunicationConfig* attribute), 124

baudrate (*PfeifferTPGSerialCommunicationConfig* attribute), 131

baudrate (*SerialCommunicationConfig* attribute), 24

BH (*NewportConfigCommands* attribute), 111

board (*VisaCommunicationConfig* attribute), 31

BoolEnum (class in *hvl_ccb.utils.enum*), 168

breakdown_detection_active (*BaseCube* property), 43

breakdown_detection_reset() (*BaseCube* method), 43

breakdown_detection_triggered (*BaseCube* property), 43

bufsize (*TcpCommunicationConfig* attribute), 27

build_str() (*LaudaProRp245eCommand* method), 104

BUS (*TriggerSource* attribute), 65

bytesize (*CryLasAttenuatorSerialCommunicationConfig* attribute), 35

bytesize (*CryLasLaserSerialCommunicationConfig* attribute), 42

bytesize (*FuGSerialCommunicationConfig* attribute), 79

bytesize (*HeinzingerSerialCommunicationConfig* attribute), 86

bytesize (*LuminosSerialCommunicationConfig* attribute), 152

bytesize (*MBW973SerialCommunicationConfig* attribute), 110

bytesize (*NewportSMC100PPSerialCommunicationConfig* attribute), 124

bytesize (*PfeifferTPGSerialCommunicationConfig* attribute), 131

Bytesize (*SerialCommunicationConfig* attribute), 24

bytesize (*SerialCommunicationConfig* attribute), 24

C (*LabJack.TemperatureUnit* attribute), 95

C (*LabJack.ThermocoupleType* attribute), 95

C (*Temperature* attribute), 167

calibration_factor (*CryLasLaserConfig* attribute), 39

calibration_factor (*LEM4000S* attribute), 166

calibration_mode (*FuGProbusVDIRegisters* property), 75

cc_mode (*FuGProbusVDIRegisters* property), 75

CCBError, 173

cee16_socket (*BaseCube* property), 43

CELSIUS (*Temperature* attribute), 167

ch_a (*T560* property), 90

ch_b (*T560* property), 90

ch_c (*T560* property), 90

ch_d (*T560* property), 90

check_for_error() (*NewportSMC100PPSerialCommunication* method), 122

check_generic_type() (in module *hvl_ccb.utils.typing*), 170

check_master_slave_config() (*PSI9000* method), 55

chunk_size (*VisaCommunicationConfig* attribute), 31

clean_values() (*AsyncCommunicationProtocolConfig* method), 13

clean_values() (*BaseCubeConfiguration* method), 46

clean_values() (*CryLasAttenuatorConfig* method), 33

clean_values() (*CryLasLaserConfig* method), 39

clean_values() (*EmptyConfig* method), 162, 172

clean_values() (*Fluke8845aConfig* method), 62

clean_values() (*FuGConfig* method), 69

clean_values() (*HeinzingerConfig* method), 81

clean_values() (*ILS2TConfig* method), 145

clean_values() (*LaudaProRp245eConfig* method), 104

clean_values() (*LaudaProRp245eTcpCommunicationConfig* method), 106

clean_values() (*LJMCommunicationConfig* method), 17

clean_values() (*LuminosConfig* method), 149

clean_values() (*MBW973Config* method), 109

clean_values() (*ModbusTcpCommunicationConfig* method), 19

clean_values() (*NewportSMC100PPConfig* method), 120

clean_values() (*OpcUaCommunicationConfig* method), 21

clean_values() (*PfeifferTPGConfig* method), 129

clean_values() (*PICubeConfiguration* method), 53

clean_values() (*PSI9000Config* method), 57

`clean_values()` (*SerialCommunicationConfig method*), 24
`clean_values()` (*T560Config method*), 91
`clean_values()` (*TcpCommunicationConfig method*), 27
`clean_values()` (*TechnixConfig method*), 156
`clean_values()` (*TelnetCommunicationConfig method*), 28
`clean_values()` (*VisaCommunicationConfig method*), 31
`clear_display_message()` (*Fluke8845a method*), 60
`clear_error_queue()` (*Fluke8845a method*), 60
`Client` (*class in hvl_ccb.comm.opc*), 20
`CLOSE` (*EarthingStickOperation attribute*), 51
`close()` (*CommunicationProtocol method*), 14
`close()` (*LaudaProRp245eTcpCommunication method*), 106
`close()` (*LJMCommunication method*), 15
`close()` (*ModbusTcpCommunication method*), 18
`close()` (*NullCommunicationProtocol method*), 14
`close()` (*OpcUaCommunication method*), 20
`close()` (*SerialCommunication method*), 23
`close()` (*Tcp method*), 26
`close()` (*TelnetCommunication method*), 27
`close()` (*VisaCommunication method*), 29
`close_shutter()` (*CryLasLaser method*), 36
`CLOSED` (*CryLasLaser.AnswersShutter attribute*), 36
`CLOSED` (*CryLasLaserShutterStatus attribute*), 42
`CLOSED` (*DoorStatus attribute*), 48
`CLOSED` (*EarthingStickStatus attribute*), 51
`CMD_EXEC_ERROR` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`CMD_NOT_ALLOWED` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`CMD_NOT_ALLOWED_CC` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`CMD_NOT_ALLOWED_CONFIGURATION` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`CMD_NOT_ALLOWED_DISABLE` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`CMD_NOT_ALLOWED_HOMING` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`CMD_NOT_ALLOWED_MOVING` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`CMD_NOT_ALLOWED_NOT_REFERENCED` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`CMD_NOT_ALLOWED_PP` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`CMD_NOT_ALLOWED_READY` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`CMR` (*PfeifferTPG.SensorTypes attribute*), 127
`CODE_OR_ADDR_INVALID` (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`com` (*SingleCommDevice property*), 163
`COM_TIME_OUT` (*LaudaProRp245eCommand attribute*), 103
`com_time_out` (*LaudaProRp245eConfig attribute*), 104
`COM_TIMEOUT` (*NewportSMC100PPSerialCommunication.ControllerErrors attribute*), 122
`command` (*LuminosMeasurementType property*), 150
`COMMAND` (*TriggerMode attribute*), 90
`command()` (*FuGProbusIV method*), 73
`communication_channel` (*TechnixConfig attribute*), 157
`CommunicationError`, 14
`CommunicationProtocol` (*class in hvl_ccb.comm.base*), 14
`config` (*ConfigurationMixin property*), 172
`CONFIG` (*FuGProbusVRegisterGroups attribute*), 77
`CONFIG` (*NewportSMC100PP.StateMessages attribute*), 113
`CONFIG` (*NewportStates attribute*), 125
`config_cls()` (*AsyncCommunicationProtocol static method*), 11
`config_cls()` (*BaseCube static method*), 44
`config_cls()` (*BaseCubeOpcUaCommunication static method*), 47
`config_cls()` (*ConfigurationMixin static method*), 172
`config_cls()` (*CryLasAttenuator static method*), 33
`config_cls()` (*CryLasAttenuatorSerialCommunication static method*), 34
`config_cls()` (*CryLasLaser static method*), 37
`config_cls()` (*CryLasLaserSerialCommunication static method*), 40
`config_cls()` (*Device static method*), 161
`config_cls()` (*Fluke8845a static method*), 60
`config_cls()` (*Fluke8845aTelnetCommunication static method*), 63
`config_cls()` (*FuGProbusIV static method*), 73
`config_cls()` (*FuGSerialCommunication static method*), 79
`config_cls()` (*HeinzingerDI static method*), 82
`config_cls()` (*HeinzingerSerialCommunication static method*), 85
`config_cls()` (*ILS2T static method*), 142
`config_cls()` (*ILS2TModbusTcpCommunication static method*), 146

`config_cls()` (*LaudaProRp245e* static method), 100
`config_cls()` (*LaudaProRp245eTcpCommunication* static method), 106
`config_cls()` (*LJMCommunication* static method), 15
`config_cls()` (*Luminos* static method), 148
`config_cls()` (*LuminosSerialCommunication* static method), 151
`config_cls()` (*MBW973* static method), 107
`config_cls()` (*MBW973SerialCommunication* static method), 110
`config_cls()` (*ModbusTcpCommunication* static method), 18
`config_cls()` (*NewportSMC100PP* static method), 114
`config_cls()` (*NewportSMC100PPSerialCommunication* static method), 122
`config_cls()` (*NullCommunicationProtocol* static method), 14
`config_cls()` (*OpcUaCommunication* static method), 20
`config_cls()` (*PfeifferTPG* static method), 127
`config_cls()` (*PfeifferTPGSerialCommunication* static method), 130
`config_cls()` (*PICube* static method), 52
`config_cls()` (*PICubeOpcUaCommunication* static method), 54
`config_cls()` (*PSI9000* static method), 55
`config_cls()` (*PSI9000VisaCommunication* static method), 58
`config_cls()` (*RTO1024* static method), 133
`config_cls()` (*RTO1024VisaCommunication* static method), 140
`config_cls()` (*SerialCommunication* static method), 23
`config_cls()` (*SyncCommunicationProtocol* static method), 14
`config_cls()` (*T560* static method), 90
`config_cls()` (*T560Communication* static method), 88
`config_cls()` (*Tcp* static method), 26
`config_cls()` (*Technix* static method), 155
`config_cls()` (*TechnixSerialCommunication* static method), 153
`config_cls()` (*TechnixTelnetCommunication* static method), 154
`config_cls()` (*TelnetCommunication* static method), 27
`config_cls()` (*VisaCommunication* static method), 29
`config_cls()` (*VisaDevice* static method), 163
`config_high_pulse()` (*LabJack* method), 95
`config_status` (*FuG* property), 68
`configdataclass()` (in module *hvl_ccb.configuration*), 173
`configuration_save_json()` (*ConfigurationMixin* method), 172
`ConfigurationMixin` (class in *hvl_ccb.configuration*), 172
`ConfigurationValueWarning`, 172
`connection_type` (*LJMCommunicationConfig* attribute), 17
`CONT_MODE` (*LaudaProRp245eCommand* attribute), 103
`continue_ramp()` (*LaudaProRp245e* method), 100
`control_mode` (*LaudaProRp245eConfig* attribute), 105
`CONVERSION` (*LEM4000S* attribute), 166
`convert()` (*LEM4000S* method), 166
`convert()` (*LMT70A* method), 166
`convert()` (*Sensor* method), 166
`convert()` (*Unit* class method), 167
`convert_to_range1()` (*MapRanges* method), 166
`convert_to_range2()` (*MapRanges* method), 166
`convert_value_to_str()` (in module *hvl_ccb.utils.conversion.utils*), 168
`ConvertibleTypes` (in module *hvl_ccb.utils.typing*), 170
`COOLOFF` (*LaudaProRp245eConfig.OperationModeEnum* attribute), 104
`COOLON` (*LaudaProRp245eConfig.OperationModeEnum* attribute), 104
`CR` (*FuGTerminators* attribute), 80
`create_serial_port()` (*SerialCommunicationConfig* method), 24
`create_telnet()` (*TelnetCommunicationConfig* method), 28
`CRLF` (*FuGTerminators* attribute), 80
`CryLasAttenuator` (class in *hvl_ccb.dev.crylas.crylas*), 32
`CryLasAttenuatorConfig` (class in *hvl_ccb.dev.crylas.crylas*), 33
`CryLasAttenuatorError`, 34
`CryLasAttenuatorSerialCommunication` (class in *hvl_ccb.dev.crylas.crylas*), 34
`CryLasAttenuatorSerialCommunicationConfig` (class in *hvl_ccb.dev.crylas.crylas*), 34
`CryLasLaser` (class in *hvl_ccb.dev.crylas.crylas*), 35
`CryLasLaser.AnswersShutter` (class in *hvl_ccb.dev.crylas.crylas*), 35
`CryLasLaser.AnswersStatus` (class in *hvl_ccb.dev.crylas.crylas*), 36
`CryLasLaser.LaserStatus` (class in *hvl_ccb.dev.crylas.crylas*), 36
`CryLasLaser.RepetitionRates` (class in *hvl_ccb.dev.crylas.crylas*), 36
`CryLasLaserConfig` (class in *hvl_ccb.dev.crylas.crylas*), 39
`CryLasLaserError`, 40
`CryLasLaserNotReadyError`, 40
`CryLasLaserPoller` (class in *hvl_ccb.dev.crylas.crylas*), 40
`CryLasLaserSerialCommunication` (class in *hvl_ccb.dev.crylas.crylas*), 40
`CryLasLaserSerialCommunicationConfig` (class in *hvl_ccb.dev.crylas.crylas*), 41

CryLasLaserShutterStatus (class in `hvl_ccb.dev.crylas.crylas`), 42
 CubeEarthingStickOperationError, 51
 CubeError, 51
 CubeRemoteControlError, 51
 CubeStatusChangeError, 51
 CubeStopError, 52
 current (FuG property), 68
 CURRENT (FuGProbusIVCommands attribute), 73
 CURRENT (FuGReadbackChannels attribute), 78
 current (Technix property), 155
 CURRENT_AC (MeasurementFunction attribute), 64
 CURRENT_DC (MeasurementFunction attribute), 64
 current_filter (Fluke8845a attribute), 60
 current_lower_limit (PSI9000Config attribute), 57
 current_monitor (FuG property), 68
 current_primary (PICube property), 52
 current_upper_limit (PSI9000Config attribute), 57
 CurrentPosition (NewportSMC100PPConfig.HomeSearch attribute), 120
 cv_mode (FuGProbusVDIRegisters property), 75

D

datachange_notification() (OpcUaSubHandler method), 22
 date_of_manufacture (LuminoxMeasurementType attribute), 150
 datetime_to_opc() (BaseCube class method), 44
 DC_140KV (PowerSetup attribute), 50
 DC_280KV (PowerSetup attribute), 50
 dc_current_range (Fluke8845a attribute), 60
 dc_voltage_range (Fluke8845a attribute), 60
 DC_VOLTAGE_TOO_LOW (NewportSMC100PP.MotorErrors attribute), 112
 DCCurrentRange (class in `hvl_ccb.dev.fluke884x.ranges`), 66
 DCVoltageRange (class in `hvl_ccb.dev.fluke884x.ranges`), 66
 default_com_cls() (BaseCube static method), 44
 default_com_cls() (CryLasAttenuator static method), 33
 default_com_cls() (CryLasLaser static method), 37
 default_com_cls() (Fluke8845a static method), 60
 default_com_cls() (FuGProbusIV static method), 73
 default_com_cls() (HeinzingerDI static method), 82
 default_com_cls() (ILS2T static method), 142
 default_com_cls() (LabJack static method), 95
 default_com_cls() (LaudaProRp245e static method), 100
 default_com_cls() (Luminox static method), 148
 default_com_cls() (MBW973 static method), 107
 default_com_cls() (NewportSMC100PP static method), 114
 default_com_cls() (PfeifferTPG static method), 127
 default_com_cls() (PICube static method), 52
 default_com_cls() (PSI9000 static method), 55
 default_com_cls() (RTO1024 static method), 133
 default_com_cls() (SingleCommDevice static method), 163
 default_com_cls() (T560 static method), 91
 default_com_cls() (Technix method), 156
 default_com_cls() (VisaDevice static method), 164
 DEFAULT_IO_SCANNING_CONTROL_VALUES (ILS2T attribute), 141
 default_n_attempts_read_text_nonempty (AsyncCommunicationProtocolConfig attribute), 13
 default_n_attempts_read_text_nonempty (FuGSerialCommunicationConfig attribute), 79
 default_n_attempts_read_text_nonempty (HeinzingerSerialCommunicationConfig attribute), 86
 default_number_of_recordings (HeinzingerConfig attribute), 81
 Device (class in `hvl_ccb.dev.base`), 160
 DEVICE_TYPE (LaudaProRp245eCommand attribute), 103
 device_type (LJMCommunicationConfig attribute), 17
 DeviceError, 161
 DeviceExistingError, 161
 DeviceFailuresError, 161
 devices_failed_start (DeviceSequenceMixin attribute), 161
 devices_failed_start (ExperimentManager attribute), 174
 devices_failed_stop (DeviceSequenceMixin attribute), 161
 devices_failed_stop (ExperimentManager attribute), 174
 DeviceSequenceMixin (class in `hvl_ccb.dev.base`), 161
 di (FuG property), 68
 digital_control (FuGProbusVDIRegisters property), 76
 DIOChannel (LabJack attribute), 94
 DIODE (MeasurementFunction attribute), 64
 DISABLE (NewportStates attribute), 125
 disable() (ILS2T method), 142
 DISABLE_FROM_JOGGING (NewportSMC100PP.StateMessages attribute), 113
 DISABLE_FROM_MOVING (NewportSMC100PP.StateMessages attribute), 113
 DISABLE_FROM_READY (NewportSMC100PP.StateMessages attribute), 113

- disable_pulses() (*LabJack method*), 96
 DisableEspStageCheck (*New-portSMC100PPConfig.EspStageConfig attribute*), 119
 disarm_trigger() (*T560 method*), 91
 disconnect() (*Client method*), 20
 DISPLACEMENT_OUT_OF_LIMIT (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
 display_enable (*Fluke8845a property*), 60
 DISPLAY_MAX_LENGTH (*Fluke8845a attribute*), 60
 display_message (*Fluke8845a property*), 61
 display_message_board() (*BaseCube method*), 44
 display_status_board() (*BaseCube method*), 44
 do_ioscanning_write() (*ILS2T method*), 142
 door_1_status (*BaseCube attribute*), 44
 door_2_status (*BaseCube attribute*), 44
 door_3_status (*BaseCube attribute*), 44
 DoorStatus (*class in hvl_ccb.dev.cube.constants*), 48
- ## E
- E (*LabJack.ThermocoupleType attribute*), 95
 E0 (*FuGErrorcodes attribute*), 71
 E1 (*FuGErrorcodes attribute*), 71
 E10 (*FuGErrorcodes attribute*), 71
 E100 (*FuGErrorcodes attribute*), 71
 E106 (*FuGErrorcodes attribute*), 71
 E11 (*FuGErrorcodes attribute*), 71
 E115 (*FuGErrorcodes attribute*), 71
 E12 (*FuGErrorcodes attribute*), 71
 E125 (*FuGErrorcodes attribute*), 71
 E13 (*FuGErrorcodes attribute*), 71
 E135 (*FuGErrorcodes attribute*), 71
 E14 (*FuGErrorcodes attribute*), 71
 E145 (*FuGErrorcodes attribute*), 71
 E15 (*FuGErrorcodes attribute*), 71
 E155 (*FuGErrorcodes attribute*), 71
 E16 (*FuGErrorcodes attribute*), 71
 E165 (*FuGErrorcodes attribute*), 71
 E2 (*FuGErrorcodes attribute*), 71
 E206 (*FuGErrorcodes attribute*), 71
 E306 (*FuGErrorcodes attribute*), 71
 E4 (*FuGErrorcodes attribute*), 72
 E5 (*FuGErrorcodes attribute*), 72
 E504 (*FuGErrorcodes attribute*), 72
 E505 (*FuGErrorcodes attribute*), 72
 E6 (*FuGErrorcodes attribute*), 72
 E666 (*FuGErrorcodes attribute*), 72
 E7 (*FuGErrorcodes attribute*), 72
 E8 (*FuGErrorcodes attribute*), 72
 E9 (*FuGErrorcodes attribute*), 72
 earthing_rod_1_status (*BaseCube attribute*), 44
 earthing_rod_2_status (*BaseCube attribute*), 44
 earthing_rod_3_status (*BaseCube attribute*), 44
 EarthingRodStatus (*class in hvl_ccb.dev.cube.constants*), 49
 EarthingStickOperatingStatus (*class in hvl_ccb.dev.cube.earthing_stick*), 51
 EarthingStickOperation (*class in hvl_ccb.dev.cube.earthing_stick*), 51
 EarthingStickStatus (*class in hvl_ccb.dev.cube.earthing_stick*), 51
 EEPROM_ACCESS_ERROR (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
 EIGHT (*HeinzingerConfig.RecordingsEnum attribute*), 81
 EIGHTBITS (*SerialCommunicationBytesize attribute*), 24
 EmptyConfig (*class in hvl_ccb.configuration*), 172
 EmptyConfig (*class in hvl_ccb.dev.base*), 162
 enable() (*ILS2T method*), 142
 enable_clock() (*LabJack method*), 96
 EnableEspStageCheck (*New-portSMC100PPConfig.EspStageConfig attribute*), 120
 encoding (*AsyncCommunicationProtocolConfig attribute*), 13
 encoding (*NewportSMC100PPSerialCommunicationConfig attribute*), 124
 encoding_error_handling (*AsyncCommunicationProtocolConfig attribute*), 13
 encoding_error_handling (*New-portSMC100PPSerialCommunicationConfig attribute*), 124
 EndOfRunSwitch (*New-portSMC100PPConfig.HomeSearch attribute*), 120
 EndOfRunSwitch_and_Index (*New-portSMC100PPConfig.HomeSearch attribute*), 120
 endpoint_name (*BaseCubeOpcUaCommunicationConfig attribute*), 48
 endpoint_name (*OpcUaCommunicationConfig attribute*), 21
 endpoint_name (*PICubeOpcUaCommunicationConfig attribute*), 54
 ERROR (*DoorStatus attribute*), 48
 ERROR (*EarthingStickStatus attribute*), 51
 ERROR (*ExperimentStatus attribute*), 175
 ERROR (*SafetyStatus attribute*), 50
 errorcode (*FuGError attribute*), 70
 ESP_STAGE_NAME_INVALID (*New-portSMC100PPSerialCommunication.ControllerErrors attribute*), 122
 ETH (*LaudaProRp245eConfig.ExtControlModeEnum attribute*), 104
 ETHERNET (*LJMCommunicationConfig.ConnectionType attribute*), 16
 EVEN (*SerialCommunicationParity attribute*), 26

event_notification() (*OpcUaSubHandler* method), 23
 EXECUTE (*FuGProbusIVCommands* attribute), 73
 execute_absolute_position() (*ILS2T* method), 143
 execute_on_x (*FuGProbusVConfigRegisters* property), 74
 execute_relative_step() (*ILS2T* method), 143
 EXECUTEONX (*FuGProbusIVCommands* attribute), 74
 exit_configuration() (*NewportSMC100PP* method), 114
 exit_configuration_wait_sec (*NewportSMC100PPConfig* attribute), 120
 EXPERIMENT_BLOCKED (*EarthingRodStatus* attribute), 49
 EXPERIMENT_READY (*EarthingRodStatus* attribute), 49
 ExperimentError, 173
 ExperimentManager (class in *hvl_ccb.experiment_manager*), 173
 ExperimentStatus (class in *hvl_ccb.experiment_manager*), 174
 EXPT100 (*LaudaProRp245eConfig.ExtControlModeEnum* attribute), 104
 EXT_FALLING_EDGE (*TriggerMode* attribute), 90
 EXT_RISING_EDGE (*TriggerMode* attribute), 90
 EXTERNAL (*TriggerSource* attribute), 65
 EXTERNAL_SOURCE (*PowerSetup* attribute), 50
 EXTERNAL_TEMP (*LaudaProRp245eCommand* attribute), 103

F

F (*LabJack.TemperatureUnit* attribute), 95
 F (*Temperature* attribute), 167
 FAHRENHEIT (*Temperature* attribute), 167
 failures (*DeviceFailuresError* attribute), 161
 FAST (*ILS2T.Ref16Jog* attribute), 141
 FAST_FILTER (*FilterRange* attribute), 67
 fetch() (*Fluke8845a* method), 61
 file_copy() (*RTO1024* method), 133
 FilterRange (class in *hvl_ccb.dev.fluke884x.ranges*), 66
 finish() (*ExperimentManager* method), 174
 FINISHED (*ExperimentStatus* attribute), 175
 FINISHING (*ExperimentStatus* attribute), 175
 fire_trigger() (*T560* method), 91
 FIRMWARE (*FuGReadbackChannels* attribute), 78
 FIVE_MHZ (*LabJack.ClockFrequency* attribute), 94
 FIVEBITS (*SerialCommunicationBytesize* attribute), 24
 FLT_INFO (*ILS2TRegAddr* attribute), 147
 FLT_MEM_DEL (*ILS2TRegAddr* attribute), 147
 FLT_MEM_RESET (*ILS2TRegAddr* attribute), 147
 Fluke8845a (class in *hvl_ccb.dev.fluke884x.base*), 60
 Fluke8845aCheckError, 64
 Fluke8845aConfig (class in *hvl_ccb.dev.fluke884x.base*), 62
 Fluke8845aError, 64
 Fluke8845aTelnetCommunication (class in *hvl_ccb.dev.fluke884x.base*), 63
 Fluke8845aTelnetCommunicationConfig (class in *hvl_ccb.dev.fluke884x.base*), 63
 Fluke8845aUnknownCommandError, 64
 FOLLOWING_ERROR (*NewportSMC100PP.MotorErrors* attribute), 112
 FOLLOWRAMP (*FuGRampModes* attribute), 78
 force_value() (*AsyncCommunicationProtocolConfig* method), 13
 force_value() (*BaseCubeConfiguration* method), 46
 force_value() (*BaseCubeOpcUaCommunicationConfig* method), 48
 force_value() (*CryLasAttenuatorConfig* method), 33
 force_value() (*CryLasAttenuatorSerialCommunicationConfig* method), 35
 force_value() (*CryLasLaserConfig* method), 39
 force_value() (*CryLasLaserSerialCommunicationConfig* method), 42
 force_value() (*EmptyConfig* method), 162, 172
 force_value() (*Fluke8845aConfig* method), 62
 force_value() (*Fluke8845aTelnetCommunicationConfig* method), 63
 force_value() (*FuGConfig* method), 69
 force_value() (*FuGSerialCommunicationConfig* method), 79
 force_value() (*HeinzingerConfig* method), 81
 force_value() (*HeinzingerSerialCommunicationConfig* method), 86
 force_value() (*ILS2TConfig* method), 145
 force_value() (*ILS2TModbusTcpCommunicationConfig* method), 146
 force_value() (*LaudaProRp245eConfig* method), 105
 force_value() (*LaudaProRp245eTcpCommunicationConfig* method), 106
 force_value() (*LJMCommunicationConfig* method), 17
 force_value() (*LuminoxConfig* method), 149
 force_value() (*LuminoxSerialCommunicationConfig* method), 152
 force_value() (*MBW973Config* method), 109
 force_value() (*MBW973SerialCommunicationConfig* method), 110
 force_value() (*ModbusTcpCommunicationConfig* method), 19
 force_value() (*NewportSMC100PPConfig* method), 120
 force_value() (*NewportSMC100PPSerialCommunicationConfig* method), 124
 force_value() (*OpcUaCommunicationConfig* method), 21
 force_value() (*PfeifferTPGConfig* method), 129
 force_value() (*PfeifferTPGSerialCommunicationCon-*

fig method), 131
 force_value() (PICubeConfiguration method), 53
 force_value() (PICubeOpcUaCommunicationConfig method), 54
 force_value() (PSI9000Config method), 57
 force_value() (PSI9000VisaCommunicationConfig method), 59
 force_value() (RTO1024Config method), 139
 force_value() (RTO1024VisaCommunicationConfig method), 140
 force_value() (SerialCommunicationConfig method), 25
 force_value() (T560CommunicationConfig method), 89
 force_value() (T560Config method), 91
 force_value() (TcpCommunicationConfig method), 27
 force_value() (TechnixConfig method), 157
 force_value() (TechnixSerialCommunicationConfig method), 154
 force_value() (TechnixTelnetCommunicationConfig method), 155
 force_value() (TelnetCommunicationConfig method), 28
 force_value() (VisaCommunicationConfig method), 31
 force_value() (VisaDeviceConfig method), 164
 FORTY_MHZ (LabJack.ClockFrequency attribute), 94
 FOUR (HeinzingerConfig.RecordingsEnum attribute), 81
 FOUR_HUNDRED_MILLI_AMPERE (ACCurrentRange attribute), 65
 FOUR_HUNDRED_MILLI_AMPERE (DCCurrentRange attribute), 66
 FOUR_WIRE_RESISTANCE (MeasurementFunction attribute), 64
 four_wire_resistance_range (Fluke8845a attribute), 61
 FREERUN (RTO1024.TriggerModes attribute), 133
 FREQUENCY (MeasurementFunction attribute), 64
 frequency (PICube property), 52
 frequency (T560 property), 91
 frequency_aperture (Fluke8845a attribute), 61
 FRM (NewportConfigCommands attribute), 112
 from_json() (ConfigurationMixin class method), 172
 FRS (NewportConfigCommands attribute), 112
 FuG (class in hvl_ccb.dev.fug.fug), 68
 FuGConfig (class in hvl_ccb.dev.fug.fug), 69
 FuGDigitalVal (class in hvl_ccb.dev.fug.fug), 70
 FuGError, 70
 FuGErrorcodes (class in hvl_ccb.dev.fug.fug), 70
 FuGMonitorModes (class in hvl_ccb.dev.fug.fug), 72
 FuGPolarities (class in hvl_ccb.dev.fug.fug), 72
 FuGProbusIV (class in hvl_ccb.dev.fug.fug), 73
 FuGProbusIVCommands (class in hvl_ccb.dev.fug.fug), 73

FuGProbusV (class in hvl_ccb.dev.fug.fug), 74
 FuGProbusVConfigRegisters (class in hvl_ccb.dev.fug.fug), 74
 FuGProbusVDIRegisters (class in hvl_ccb.dev.fug.fug), 75
 FuGProbusVDORegisters (class in hvl_ccb.dev.fug.fug), 76
 FuGProbusVMonitorRegisters (class in hvl_ccb.dev.fug.fug), 76
 FuGProbusVRegisterGroups (class in hvl_ccb.dev.fug.fug), 77
 FuGProbusVSetRegisters (class in hvl_ccb.dev.fug.fug), 77
 FuGRampModes (class in hvl_ccb.dev.fug.fug), 78
 FuGReadbackChannels (class in hvl_ccb.dev.fug.fug), 78
 FuGSerialCommunication (class in hvl_ccb.dev.fug.fug), 78
 FuGSerialCommunicationConfig (class in hvl_ccb.dev.fug.fug), 79
 FuGTerminators (class in hvl_ccb.dev.fug.fug), 80

G

gate_mode (T560 property), 91
 gate_polarity (T560 property), 91
 GateMode (class in hvl_ccb.dev.highland_t560.base), 88
 get_acceleration() (NewportSMC100PP method), 114
 get_acquire_length() (RTO1024 method), 133
 get_ain() (LabJack method), 96
 get_bath_temp() (LaudaProRp245e method), 100
 get_by_p_id() (LabJack.DeviceType class method), 94
 get_by_p_id() (LJMCommunicationConfig.DeviceType class method), 17
 get_cal_current_source() (LabJack method), 96
 get_channel_offset() (RTO1024 method), 134
 get_channel_position() (RTO1024 method), 134
 get_channel_range() (RTO1024 method), 134
 get_channel_scale() (RTO1024 method), 134
 get_channel_state() (RTO1024 method), 134
 get_clock() (LabJack method), 96
 get_controller_information() (NewportSMC100PP method), 114
 get_current() (HeinzingerDI method), 82
 get_dc_volt() (ILS2T method), 143
 get_device() (DeviceSequenceMixin method), 162
 get_device_type() (LaudaProRp245e method), 100
 get_devices() (DeviceSequenceMixin method), 162
 get_digital_input() (LabJack method), 96
 get_error_code() (ILS2T method), 143
 get_error_queue() (VisaDevice method), 164
 get_full_scale_mbar() (PfeifferTPG method), 127
 get_full_scale_unitless() (PfeifferTPG method), 127

get_identification() (*VisaDevice method*), 164
 get_interface_version() (*HeinzingerDI method*), 82
 get_motor_configuration() (*NewportSMC100PP method*), 115
 get_move_duration() (*NewportSMC100PP method*), 115
 get_negative_software_limit() (*NewportSMC100PP method*), 115
 get_number_of_recordings() (*HeinzingerDI method*), 83
 get_objects_node() (*Client method*), 20
 get_objects_node() (*Server method*), 23
 get_output() (*PSI9000 method*), 55
 get_position() (*ILS2T method*), 143
 get_position() (*NewportSMC100PP method*), 115
 get_positive_software_limit() (*NewportSMC100PP method*), 116
 get_product_id() (*LabJack method*), 96
 get_product_name() (*LabJack method*), 96
 get_product_type() (*LabJack method*), 97
 get_pulse_energy_and_rate() (*CryLasLaser method*), 37
 get_reference_point() (*RTO1024 method*), 134
 get_register() (*FuGProbusV method*), 74
 get_repetitions() (*RTO1024 method*), 135
 get_sbus_rh() (*LabJack method*), 97
 get_sbus_temp() (*LabJack method*), 97
 get_serial_number() (*HeinzingerDI method*), 83
 get_serial_number() (*LabJack method*), 97
 get_state() (*NewportSMC100PP method*), 116
 get_status() (*ILS2T method*), 143
 get_system_lock() (*PSI9000 method*), 56
 get_temperature() (*ILS2T method*), 143
 get_timestamps() (*RTO1024 method*), 135
 get_ui_lower_limits() (*PSI9000 method*), 56
 get_uip_upper_limits() (*PSI9000 method*), 56
 get_voltage() (*HeinzingerDI method*), 83
 get_voltage_current_setpoint() (*PSI9000 method*), 56
 GetAttr (*class in hvl_ccb.utils.conversion.utils*), 168
 go_home() (*NewportSMC100PP method*), 116
 go_to_configuration() (*NewportSMC100PP method*), 116
 GREEN_NOT_READY (*SafetyStatus attribute*), 50
 GREEN_READY (*SafetyStatus attribute*), 50

H

HARDWARE (*CryLasLaser.RepetitionRates attribute*), 36
 HEAD (*CryLasLaser.AnswersStatus attribute*), 36
 HeinzingerConfig (*class in hvl_ccb.dev.heinzinger.base*), 81
 HeinzingerConfig.RecordingsEnum (*class in hvl_ccb.dev.heinzinger.base*), 81
 HeinzingerDI (*class in hvl_ccb.dev.heinzinger.base*), 82
 HeinzingerDI.OutputStatus (*class in hvl_ccb.dev.heinzinger.base*), 82
 HeinzingerPNC (*class in hvl_ccb.dev.heinzinger.base*), 84
 HeinzingerPNC.UnitCurrent (*class in hvl_ccb.dev.heinzinger.base*), 84
 HeinzingerPNC.UnitVoltage (*class in hvl_ccb.dev.heinzinger.base*), 84
 HeinzingerPNCDeviceNotRecognizedError, 87
 HeinzingerPNCError, 87
 HeinzingerPNCMaxCurrentExceededError, 87
 HeinzingerPNCMaxVoltageExceededError, 87
 HeinzingerSerialCommunication (*class in hvl_ccb.dev.heinzinger.base*), 85
 HeinzingerSerialCommunicationConfig (*class in hvl_ccb.dev.heinzinger.base*), 85
 HIGH (*LabJack.DIOStatus attribute*), 94
 high_resolution (*FuGProbusVSetRegisters property*), 77
 home_search_polling_interval (*NewportSMC100PPConfig attribute*), 120
 home_search_timeout (*NewportSMC100PPConfig attribute*), 120
 home_search_type (*NewportSMC100PPConfig attribute*), 120
 home_search_velocity (*NewportSMC100PPConfig attribute*), 120
 HOME_STARTED (*NewportSMC100PPSerialCommunication.ControllerError attribute*), 122
 HomeSwitch (*NewportSMC100PPConfig.HomeSearch attribute*), 120
 HomeSwitch_and_Index (*NewportSMC100PPConfig.HomeSearch attribute*), 120
 HOMING (*NewportStates attribute*), 125
 HOMING_FROM_RS232 (*NewportSMC100PP.StateMessages attribute*), 113
 HOMING_FROM_SMC (*NewportSMC100PP.StateMessages attribute*), 113
 HOMING_TIMEOUT (*NewportSMC100PP.MotorErrors attribute*), 113
 host (*ModbusTcpCommunicationConfig attribute*), 19
 host (*OpcUaCommunicationConfig attribute*), 21
 host (*TcpCommunicationConfig attribute*), 27
 host (*TelnetCommunicationConfig attribute*), 28
 host (*VisaCommunicationConfig attribute*), 31
 HT (*NewportConfigCommands attribute*), 112
 HUNDRED_VOLT (*ACVoltageRange attribute*), 65
 HUNDRED_VOLT (*DCVoltageRange attribute*), 66
 hvl_ccb module, 175
 hvl_ccb.comm module, 32

hvl_ccb.comm.base	hvl_ccb.dev.fug
module, 11	module, 80
hvl_ccb.comm.labjack_ljm	hvl_ccb.dev.fug.fug
module, 15	module, 67
hvl_ccb.comm.modbus_tcp	hvl_ccb.dev.heinzinger
module, 18	module, 87
hvl_ccb.comm.opc	hvl_ccb.dev.heinzinger.base
module, 20	module, 81
hvl_ccb.comm.serial	hvl_ccb.dev.heinzinger.constants
module, 23	module, 87
hvl_ccb.comm.tcp	hvl_ccb.dev.highland_t560
module, 26	module, 92
hvl_ccb.comm.telnet	hvl_ccb.dev.highland_t560.base
module, 27	module, 88
hvl_ccb.comm.visa	hvl_ccb.dev.highland_t560.channel
module, 29	module, 90
hvl_ccb.configuration	hvl_ccb.dev.highland_t560.device
module, 172	module, 90
hvl_ccb.dev	hvl_ccb.dev.labjack
module, 165	module, 99
hvl_ccb.dev.base	hvl_ccb.dev.labjack.labjack
module, 160	module, 92
hvl_ccb.dev.crylas	hvl_ccb.dev.lauda
module, 43	module, 107
hvl_ccb.dev.crylas.crylas	hvl_ccb.dev.lauda.lauda
module, 32	module, 100
hvl_ccb.dev.cube	hvl_ccb.dev.mbw973
module, 55	module, 111
hvl_ccb.dev.cube.alarms	hvl_ccb.dev.mbw973.mbw973
module, 43	module, 107
hvl_ccb.dev.cube.base	hvl_ccb.dev.newport
module, 43	module, 126
hvl_ccb.dev.cube.constants	hvl_ccb.dev.newport.newport
module, 48	module, 111
hvl_ccb.dev.cube.earthing_stick	hvl_ccb.dev.pfeiffer_tpg
module, 51	module, 132
hvl_ccb.dev.cube.errors	hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg
module, 51	module, 126
hvl_ccb.dev.cube.picube	hvl_ccb.dev.rs_rto1024
module, 52	module, 141
hvl_ccb.dev.cube.support	hvl_ccb.dev.rs_rto1024.rs_rto1024
module, 55	module, 132
hvl_ccb.dev.ea_psi9000	hvl_ccb.dev.se_ils2t
module, 59	module, 148
hvl_ccb.dev.ea_psi9000.ea_psi9000	hvl_ccb.dev.se_ils2t.se_ils2t
module, 55	module, 141
hvl_ccb.dev.fluke884x	hvl_ccb.dev.sst_luminox
module, 67	module, 153
hvl_ccb.dev.fluke884x.base	hvl_ccb.dev.sst_luminox.sst_luminox
module, 60	module, 148
hvl_ccb.dev.fluke884x.constants	hvl_ccb.dev.technix
module, 64	module, 158
hvl_ccb.dev.fluke884x.ranges	hvl_ccb.dev.technix.base
module, 65	module, 153

hvl_ccb.dev.technix.device
 module, 155
 hvl_ccb.dev.utils
 module, 163
 hvl_ccb.dev.visa
 module, 163
 hvl_ccb.error
 module, 173
 hvl_ccb.experiment_manager
 module, 173
 hvl_ccb.utils
 module, 172
 hvl_ccb.utils.conversion
 module, 168
 hvl_ccb.utils.conversion.map_range
 module, 165
 hvl_ccb.utils.conversion.sensor
 module, 166
 hvl_ccb.utils.conversion.unit
 module, 167
 hvl_ccb.utils.conversion.utils
 module, 168
 hvl_ccb.utils.enum
 module, 168
 hvl_ccb.utils.poller
 module, 169
 hvl_ccb.utils.typing
 module, 170
 hvl_ccb.utils.validation
 module, 171
 hysteresis_compensation (NewportSMC100PPConfig attribute), 120
 |
 ID (FuGProbusIVCommands attribute), 74
 identification (Fluke8845a property), 61
 Identification_error (PfeifferTPG.SensorStatus attribute), 126
 identifier (LJMCommunicationConfig attribute), 17
 identify_device() (FuG method), 68
 identify_device() (HeinzingerPNC method), 85
 identify_sensors() (PfeifferTPG method), 127
 IKR (PfeifferTPG.SensorTypes attribute), 127
 IKR11 (PfeifferTPG.SensorTypes attribute), 127
 IKR9 (PfeifferTPG.SensorTypes attribute), 127
 ILS2T (class in hvl_ccb.dev.se_ils2t.se_ils2t), 141
 ILS2T.ActionsPtp (class in hvl_ccb.dev.se_ils2t.se_ils2t), 141
 ILS2T.Mode (class in hvl_ccb.dev.se_ils2t.se_ils2t), 141
 ILS2T.Ref16Jog (class in hvl_ccb.dev.se_ils2t.se_ils2t), 141
 ILS2T.State (class in hvl_ccb.dev.se_ils2t.se_ils2t), 142
 ILS2TConfig (class in hvl_ccb.dev.se_ils2t.se_ils2t), 145
 ILS2TError, 146
 ILS2TModbusTcpCommunication (class in hvl_ccb.dev.se_ils2t.se_ils2t), 146
 ILS2TModbusTcpCommunicationConfig (class in hvl_ccb.dev.se_ils2t.se_ils2t), 146
 ILS2TRegAddr (class in hvl_ccb.dev.se_ils2t.se_ils2t), 147
 ILS2TRegDatatype (class in hvl_ccb.dev.se_ils2t.se_ils2t), 147
 IMMEDIATE (TriggerSource attribute), 65
 IMMEDIATELY (FuGRampModes attribute), 78
 IMPULSE_140KV (PowerSetup attribute), 50
 IMR (PfeifferTPG.SensorTypes attribute), 127
 INACTIVE (CryLasLaser.AnswersStatus attribute), 36
 INACTIVE (DoorStatus attribute), 48
 INACTIVE (EarthingStickStatus attribute), 51
 inhibit (Technix property), 156
 init_attenuation (CryLasAttenuatorConfig attribute), 34
 init_monitored_nodes() (OpcUaCommunication method), 20
 init_shutter_status (CryLasLaserConfig attribute), 39
 initialize() (NewportSMC100PP method), 117
 INITIALIZED (ExperimentStatus attribute), 175
 INITIALIZING (ExperimentStatus attribute), 175
 INITIALIZING (SafetyStatus attribute), 50
 initiate_trigger() (Fluke8845a method), 61
 INPUT (FuGProbusVRegisterGroups attribute), 77
 INPUT (GateMode attribute), 88
 INSTALL (AutoInstallMode attribute), 88
 INT32 (ILS2TRegDatatype attribute), 148
 INT_SYNTHESIZER (TriggerMode attribute), 90
 interface_type (PSI9000VisaCommunicationConfig attribute), 59
 interface_type (RTO1024VisaCommunicationConfig attribute), 140
 interface_type (VisaCommunicationConfig attribute), 31
 internal (LabJack.CjcType attribute), 93
 INTERNAL (LaudaProRp245eConfig.ExtControlModeEnum attribute), 104
 IO_SCANNING (ILS2TRegAddr attribute), 147
 IoScanningModeValueError, 148
 is_configdataclass (AsyncCommunicationProtocolConfig attribute), 13
 is_configdataclass (BaseCubeConfiguration attribute), 46
 is_configdataclass (CryLasAttenuatorConfig attribute), 34
 is_configdataclass (CryLasLaserConfig attribute), 39
 is_configdataclass (EmptyConfig attribute), 163, 173
 is_configdataclass (Fluke8845aConfig attribute), 62
 is_configdataclass (FuGConfig attribute), 70

[is_configdataclass \(HeinzingerConfig attribute\)](#), 81
[is_configdataclass \(ILS2TConfig attribute\)](#), 145
[is_configdataclass \(LaudaProRp245eConfig attribute\)](#), 105
[is_configdataclass \(LJMCommunicationConfig attribute\)](#), 17
[is_configdataclass \(LuminosConfig attribute\)](#), 149
[is_configdataclass \(MBW973Config attribute\)](#), 109
[is_configdataclass \(ModbusTcpCommunicationConfig attribute\)](#), 19
[is_configdataclass \(NewportSMC100PPConfig attribute\)](#), 120
[is_configdataclass \(OpcUaCommunicationConfig attribute\)](#), 21
[is_configdataclass \(PfeifferTPGConfig attribute\)](#), 129
[is_configdataclass \(T560Config attribute\)](#), 92
[is_configdataclass \(TcpCommunicationConfig attribute\)](#), 27
[is_configdataclass \(TechnixConfig attribute\)](#), 157
[is_configdataclass \(VisaCommunicationConfig attribute\)](#), 31
[is_done\(\) \(MBW973 method\)](#), 107
[is_error\(\) \(ExperimentManager method\)](#), 174
[is_finished\(\) \(ExperimentManager method\)](#), 174
[is_generic_type_hint\(\) \(in module hvl_ccb.utils.typing\)](#), 170
[is_in_range\(\) \(ILS2TRegDatatype method\)](#), 148
[is_inactive \(CryLasLaser.LaserStatus property\)](#), 36
[is_open \(Client property\)](#), 20
[is_open \(LJMCommunication property\)](#), 15
[is_open \(OpcUaCommunication property\)](#), 20
[is_open \(SerialCommunication property\)](#), 23
[is_open \(TelnetCommunication property\)](#), 28
[is_polling\(\) \(Poller method\)](#), 169
[is_ready \(CryLasLaser.LaserStatus property\)](#), 36
[is_running\(\) \(ExperimentManager method\)](#), 174
[is_started \(Technix property\)](#), 156
[is_valid_scale_range_reversed_str\(\) \(PfeifferTPGConfig.Model method\)](#), 129

J

[J \(LabJack.ThermocoupleType attribute\)](#), 95
[jerk_time \(NewportSMC100PPConfig attribute\)](#), 120
[JOG \(ILS2T.Mode attribute\)](#), 141
[jog_run\(\) \(ILS2T method\)](#), 143
[jog_stop\(\) \(ILS2T method\)](#), 143
[JOGGING \(NewportStates attribute\)](#), 125
[JOGGING_FROM_DISABLE \(NewportSMC100PP.StateMessages attribute\)](#), 113
[JOGGING_FROM_READY \(NewportSMC100PP.StateMessages attribute\)](#), 113

[JOGN_FAST \(ILS2TRegAddr attribute\)](#), 147
[JOGN_SLOW \(ILS2TRegAddr attribute\)](#), 147
[JR \(NewportConfigCommands attribute\)](#), 112

K

[K \(LabJack.TemperatureUnit attribute\)](#), 95
[K \(LabJack.ThermocoupleType attribute\)](#), 95
[K \(Temperature attribute\)](#), 167
[KELVIN \(Temperature attribute\)](#), 167
[keys\(\) \(AsyncCommunicationProtocolConfig class method\)](#), 13
[keys\(\) \(BaseCubeConfiguration class method\)](#), 46
[keys\(\) \(BaseCubeOpcUaCommunicationConfig class method\)](#), 48
[keys\(\) \(CryLasAttenuatorConfig class method\)](#), 34
[keys\(\) \(CryLasAttenuatorSerialCommunicationConfig class method\)](#), 35
[keys\(\) \(CryLasLaserConfig class method\)](#), 40
[keys\(\) \(CryLasLaserSerialCommunicationConfig class method\)](#), 42
[keys\(\) \(EmptyConfig class method\)](#), 163, 173
[keys\(\) \(Fluke8845aConfig class method\)](#), 62
[keys\(\) \(Fluke8845aTelnetCommunicationConfig class method\)](#), 63
[keys\(\) \(FuGConfig class method\)](#), 70
[keys\(\) \(FuGSerialCommunicationConfig class method\)](#), 79
[keys\(\) \(HeinzingerConfig class method\)](#), 81
[keys\(\) \(HeinzingerSerialCommunicationConfig class method\)](#), 86
[keys\(\) \(ILS2TConfig class method\)](#), 145
[keys\(\) \(ILS2TModbusTcpCommunicationConfig class method\)](#), 146
[keys\(\) \(LaudaProRp245eConfig class method\)](#), 105
[keys\(\) \(LaudaProRp245eTcpCommunicationConfig class method\)](#), 106
[keys\(\) \(LJMCommunicationConfig class method\)](#), 17
[keys\(\) \(LuminosConfig class method\)](#), 149
[keys\(\) \(LuminosSerialCommunicationConfig class method\)](#), 152
[keys\(\) \(MBW973Config class method\)](#), 109
[keys\(\) \(MBW973SerialCommunicationConfig class method\)](#), 110
[keys\(\) \(ModbusTcpCommunicationConfig class method\)](#), 19
[keys\(\) \(NewportSMC100PPConfig class method\)](#), 120
[keys\(\) \(NewportSMC100PPSerialCommunicationConfig class method\)](#), 125
[keys\(\) \(OpcUaCommunicationConfig class method\)](#), 21
[keys\(\) \(PfeifferTPGConfig class method\)](#), 129
[keys\(\) \(PfeifferTPGSerialCommunicationConfig class method\)](#), 131
[keys\(\) \(PICubeConfiguration class method\)](#), 53

keys() (*PICubeOpcUaCommunicationConfig* class method), 54
 keys() (*PSI9000Config* class method), 58
 keys() (*PSI9000VisaCommunicationConfig* class method), 59
 keys() (*RTO1024Config* class method), 139
 keys() (*RTO1024VisaCommunicationConfig* class method), 140
 keys() (*SerialCommunicationConfig* class method), 25
 keys() (*T560CommunicationConfig* class method), 89
 keys() (*T560Config* class method), 92
 keys() (*TcpCommunicationConfig* class method), 27
 keys() (*TechnixConfig* class method), 157
 keys() (*TechnixSerialCommunicationConfig* class method), 154
 keys() (*TechnixTelnetCommunicationConfig* class method), 155
 keys() (*TelnetCommunicationConfig* class method), 28
 keys() (*VisaCommunicationConfig* class method), 31
 keys() (*VisaDeviceConfig* class method), 165
 kV (*HeinzingerPNC.UnitVoltage* attribute), 85

L

LabJack (class in *hvl_ccb.dev.labjack.labjack*), 93
 LabJack.AInRange (class in *hvl_ccb.dev.labjack.labjack*), 93
 LabJack.BitLimit (class in *hvl_ccb.dev.labjack.labjack*), 93
 LabJack.CalMicroAmpere (class in *hvl_ccb.dev.labjack.labjack*), 93
 LabJack.CjcType (class in *hvl_ccb.dev.labjack.labjack*), 93
 LabJack.ClockFrequency (class in *hvl_ccb.dev.labjack.labjack*), 94
 LabJack.DeviceType (class in *hvl_ccb.dev.labjack.labjack*), 94
 LabJack.DIOStatus (class in *hvl_ccb.dev.labjack.labjack*), 94
 LabJack.TemperatureUnit (class in *hvl_ccb.dev.labjack.labjack*), 95
 LabJack.ThermocoupleType (class in *hvl_ccb.dev.labjack.labjack*), 95
 LabJackError, 99
 LabJackIdentifierDIOError, 99
 laser_off() (*CryLasLaser* method), 37
 laser_on() (*CryLasLaser* method), 37
 LaudaProRp245e (class in *hvl_ccb.dev.lauda.lauda*), 100
 LaudaProRp245eCommand (class in *hvl_ccb.dev.lauda.lauda*), 102
 LaudaProRp245eCommandError, 104
 LaudaProRp245eConfig (class in *hvl_ccb.dev.lauda.lauda*), 104
 LaudaProRp245eConfig.ExtControlModeEnum (class in *hvl_ccb.dev.lauda.lauda*), 104
 LaudaProRp245eConfig.OperationModeEnum (class in *hvl_ccb.dev.lauda.lauda*), 104
 LaudaProRp245eTcpCommunication (class in *hvl_ccb.dev.lauda.lauda*), 105
 LaudaProRp245eTcpCommunicationConfig (class in *hvl_ccb.dev.lauda.lauda*), 106
 LEM4000S (class in *hvl_ccb.utils.conversion.sensor*), 166
 LF (*FuGTerminators* attribute), 80
 LFCR (*FuGTerminators* attribute), 80
 LINE_1 (*MessageBoard* attribute), 49
 LINE_10 (*MessageBoard* attribute), 49
 LINE_11 (*MessageBoard* attribute), 49
 LINE_12 (*MessageBoard* attribute), 49
 LINE_13 (*MessageBoard* attribute), 49
 LINE_14 (*MessageBoard* attribute), 49
 LINE_15 (*MessageBoard* attribute), 49
 LINE_2 (*MessageBoard* attribute), 49
 LINE_3 (*MessageBoard* attribute), 49
 LINE_4 (*MessageBoard* attribute), 49
 LINE_5 (*MessageBoard* attribute), 49
 LINE_6 (*MessageBoard* attribute), 49
 LINE_7 (*MessageBoard* attribute), 49
 LINE_8 (*MessageBoard* attribute), 49
 LINE_9 (*MessageBoard* attribute), 49
 list_directory() (*RTO1024* method), 135
 LJMCommunication (class in *hvl_ccb.comm.labjack_ljm*), 15
 LJMCommunicationConfig (class in *hvl_ccb.comm.labjack_ljm*), 16
 LJMCommunicationConfig.ConnectionType (class in *hvl_ccb.comm.labjack_ljm*), 16
 LJMCommunicationConfig.DeviceType (class in *hvl_ccb.comm.labjack_ljm*), 16
 LJMCommunicationError, 18
 lm34 (*LabJack.CjcType* attribute), 94
 LMT70A (class in *hvl_ccb.utils.conversion.sensor*), 166
 load_configuration() (*RTO1024* method), 135
 load_device_configuration() (*T560* method), 91
 local_display() (*RTO1024* method), 135
 LOCKED (*DoorStatus* attribute), 49
 LOW (*LabJack.DIOStatus* attribute), 94
 LOWER_TEMP (*LaudaProRp245eCommand* attribute), 103
 lower_temp (*LaudaProRp245eConfig* attribute), 105
 Luminos (class in *hvl_ccb.dev.sst_luminos.sst_luminos*), 148
 LuminosConfig (class in *hvl_ccb.dev.sst_luminos.sst_luminos*), 149
 LuminosError, 150
 LuminosMeasurementType (class in *hvl_ccb.dev.sst_luminos.sst_luminos*), 150
 LuminosMeasurementTypeDict (in module *hvl_ccb.dev.sst_luminos.sst_luminos*), 151
 LuminosMeasurementTypeError, 151

LuminosMeasurementTypeValue (in module *hvl_ccb.dev.sst_luminos.sst_luminos*), 151
 LuminosOutputMode (class in *hvl_ccb.dev.sst_luminos.sst_luminos*), 151
 LuminosOutputModeError, 151
 LuminosSerialCommunication (class in *hvl_ccb.dev.sst_luminos.sst_luminos*), 151
 LuminosSerialCommunicationConfig (class in *hvl_ccb.dev.sst_luminos.sst_luminos*), 151
 LUT (*LMT70A* attribute), 166

M

mA (*HeinzingerPNC.UnitCurrent* attribute), 84
 MANUAL (*EarthingStickOperatingStatus* attribute), 51
 MapBitAsymRange (class in *hvl_ccb.utils.conversion.map_range*), 165
 MapBitSymRange (class in *hvl_ccb.utils.conversion.map_range*), 166
 MapRanges (class in *hvl_ccb.utils.conversion.map_range*), 166
 MARK (*SerialCommunicationParity* attribute), 26
 max_current (*FuG* property), 68
 max_current (*HeinzingerPNC* property), 85
 max_current (*Technix* property), 156
 max_current (*TechnixConfig* attribute), 157
 max_current_hardware (*FuG* property), 68
 max_current_hardware (*HeinzingerPNC* property), 85
 max_pr_number (*LaudaProRp245eConfig* attribute), 105
 max_pump_level (*LaudaProRp245eConfig* attribute), 105
 max_timeout_retry_nr (*OpcUaCommunicationConfig* attribute), 22
 max_voltage (*FuG* property), 68
 max_voltage (*HeinzingerPNC* property), 85
 max_voltage (*Technix* property), 156
 max_voltage (*TechnixConfig* attribute), 157
 max_voltage_hardware (*FuG* property), 68
 max_voltage_hardware (*HeinzingerPNC* property), 85
 MAXIMUM (*LabJack.ClockFrequency* attribute), 94
 MBW973 (class in *hvl_ccb.dev.mbw973.mbw973*), 107
 MBW973Config (class in *hvl_ccb.dev.mbw973.mbw973*), 109
 MBW973ControlRunningError, 109
 MBW973Error, 109
 MBW973PumpRunningError, 110
 MBW973SerialCommunication (class in *hvl_ccb.dev.mbw973.mbw973*), 110
 MBW973SerialCommunicationConfig (class in *hvl_ccb.dev.mbw973.mbw973*), 110
 measure() (*Fluke8845a* method), 61
 measure() (*PfeifferTPG* method), 128
 measure_all() (*PfeifferTPG* method), 128
 measure_current() (*HeinzingerDI* method), 83
 measure_voltage() (*HeinzingerDI* method), 83
 measure_voltage_current() (*PSI9000* method), 56
 measurement_function (*Fluke8845a* property), 61
 MeasurementFunction (class in *hvl_ccb.dev.fluke884x.constants*), 64
 MEDIUM_FILTER (*FilterRange* attribute), 67
 MessageBoard (class in *hvl_ccb.dev.cube.constants*), 49
 micro_step_per_full_step_factor (*NewportSMC100PPConfig* attribute), 121
 MILLIMETER_MERCURY (*Pressure* attribute), 167
 MINIMUM (*LabJack.ClockFrequency* attribute), 94
 MMHG (*Pressure* attribute), 167
 ModbusTcpCommunication (class in *hvl_ccb.comm.modbus_tcp*), 18
 ModbusTcpCommunicationConfig (class in *hvl_ccb.comm.modbus_tcp*), 19
 ModbusTcpConnectionFailedError, 19
 model (*PfeifferTPGConfig* attribute), 129
 module
 hvl_ccb, 175
 hvl_ccb.comm, 32
 hvl_ccb.comm.base, 11
 hvl_ccb.comm.labjack_ljm, 15
 hvl_ccb.comm.modbus_tcp, 18
 hvl_ccb.comm.opc, 20
 hvl_ccb.comm.serial, 23
 hvl_ccb.comm.tcp, 26
 hvl_ccb.comm.telnet, 27
 hvl_ccb.comm.visa, 29
 hvl_ccb.configuration, 172
 hvl_ccb.dev, 165
 hvl_ccb.dev.base, 160
 hvl_ccb.dev.crylas, 43
 hvl_ccb.dev.crylas.crylas, 32
 hvl_ccb.dev.cube, 55
 hvl_ccb.dev.cube.alarms, 43
 hvl_ccb.dev.cube.base, 43
 hvl_ccb.dev.cube.constants, 48
 hvl_ccb.dev.cube.earthing_stick, 51
 hvl_ccb.dev.cube.errors, 51
 hvl_ccb.dev.cube.picube, 52
 hvl_ccb.dev.cube.support, 55
 hvl_ccb.dev.ea_psi9000, 59
 hvl_ccb.dev.ea_psi9000.ea_psi9000, 55
 hvl_ccb.dev.fluke884x, 67
 hvl_ccb.dev.fluke884x.base, 60
 hvl_ccb.dev.fluke884x.constants, 64
 hvl_ccb.dev.fluke884x.ranges, 65
 hvl_ccb.dev.fug, 80
 hvl_ccb.dev.fug.fug, 67
 hvl_ccb.dev.heinzinger, 87
 hvl_ccb.dev.heinzinger.base, 81
 hvl_ccb.dev.heinzinger.constants, 87
 hvl_ccb.dev.highland_t560, 92
 hvl_ccb.dev.highland_t560.base, 88

- hvl_ccb.dev.highland_t560.channel, 90
 - hvl_ccb.dev.highland_t560.device, 90
 - hvl_ccb.dev.labjack, 99
 - hvl_ccb.dev.labjack.labjack, 92
 - hvl_ccb.dev.lauda, 107
 - hvl_ccb.dev.lauda.lauda, 100
 - hvl_ccb.dev.mbw973, 111
 - hvl_ccb.dev.mbw973.mbw973, 107
 - hvl_ccb.dev.newport, 126
 - hvl_ccb.dev.newport.newport, 111
 - hvl_ccb.dev.pfeiffer_tpg, 132
 - hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg, 126
 - hvl_ccb.dev.rs_rto1024, 141
 - hvl_ccb.dev.rs_rto1024.rs_rto1024, 132
 - hvl_ccb.dev.se_ils2t, 148
 - hvl_ccb.dev.se_ils2t.se_ils2t, 141
 - hvl_ccb.dev.sst_luminox, 153
 - hvl_ccb.dev.sst_luminox.sst_luminox, 148
 - hvl_ccb.dev.technix, 158
 - hvl_ccb.dev.technix.base, 153
 - hvl_ccb.dev.technix.device, 155
 - hvl_ccb.dev.utils, 163
 - hvl_ccb.dev.visa, 163
 - hvl_ccb.error, 173
 - hvl_ccb.experiment_manager, 173
 - hvl_ccb.utils, 172
 - hvl_ccb.utils.conversion, 168
 - hvl_ccb.utils.conversion.map_range, 165
 - hvl_ccb.utils.conversion.sensor, 166
 - hvl_ccb.utils.conversion.unit, 167
 - hvl_ccb.utils.conversion.utils, 168
 - hvl_ccb.utils.enum, 168
 - hvl_ccb.utils.poller, 169
 - hvl_ccb.utils.typing, 170
 - hvl_ccb.utils.validation, 171
 - MONITOR_I (*FuGProbusVRegisterGroups* attribute), 77
 - MONITOR_V (*FuGProbusVRegisterGroups* attribute), 77
 - most_recent_error (*FuGProbusVConfigRegisters* property), 74
 - motion_distance_per_full_step (*NewportSMC100PPConfig* attribute), 121
 - motor_config (*NewportSMC100PPConfig* property), 121
 - move_to_absolute_position() (*NewportSMC100PP* method), 117
 - move_to_relative_position() (*NewportSMC100PP* method), 117
 - move_wait_sec (*NewportSMC100PPConfig* attribute), 121
 - MOVING (*NewportSMC100PP.StateMessages* attribute), 113
 - MOVING (*NewportStates* attribute), 125
 - MS_NOMINAL_CURRENT (*PSI9000* attribute), 55
 - MS_NOMINAL_VOLTAGE (*PSI9000* attribute), 55
 - MULTI_COMMANDS_MAX (*VisaCommunication* attribute), 29
 - MULTI_COMMANDS_SEPARATOR (*VisaCommunication* attribute), 29
- ## N
- name (*Fluke8845aConfig* attribute), 62
 - NameEnum (*class in hvl_ccb.utils.enum*), 168
 - NAMES (*SerialCommunicationParity* attribute), 26
 - names() (*RTO1024.TriggerModes* class method), 133
 - namespace_index (*BaseCubeConfiguration* attribute), 46
 - NED_END_OF_TURN (*NewportSMC100PP.MotorErrors* attribute), 113
 - NEG (*ILS2T.Ref16Jog* attribute), 141
 - NEG_FAST (*ILS2T.Ref16Jog* attribute), 141
 - NEGATIVE (*FuGPolarities* attribute), 73
 - NEGATIVE (*Polarity* attribute), 50
 - negative_software_limit (*NewportSMC100PPConfig* attribute), 121
 - NewportConfigCommands (*class in hvl_ccb.dev.newport.newport*), 111
 - NewportControllerError, 112
 - NewportError, 112
 - NewportMotorError, 112
 - NewportMotorPowerSupplyWasCutError, 112
 - NewportSerialCommunicationError, 125
 - NewportSMC100PP (*class in hvl_ccb.dev.newport.newport*), 112
 - NewportSMC100PP.MotorErrors (*class in hvl_ccb.dev.newport.newport*), 112
 - NewportSMC100PP.StateMessages (*class in hvl_ccb.dev.newport.newport*), 113
 - NewportSMC100PPConfig (*class in hvl_ccb.dev.newport.newport*), 119
 - NewportSMC100PPConfig.EspStageConfig (*class in hvl_ccb.dev.newport.newport*), 119
 - NewportSMC100PPConfig.HomeSearch (*class in hvl_ccb.dev.newport.newport*), 120
 - NewportSMC100PPSerialCommunication (*class in hvl_ccb.dev.newport.newport*), 121
 - NewportSMC100PPSerialCommunication.ControllerErrors (*class in hvl_ccb.dev.newport.newport*), 121
 - NewportSMC100PPSerialCommunicationConfig (*class in hvl_ccb.dev.newport.newport*), 124
 - NewportStates (*class in hvl_ccb.dev.newport.newport*), 125
 - NewportUncertainPositionError, 126
 - NO (*FuGDigitalVal* attribute), 70
 - NO_ERROR (*NewportSMC100PPSerialCommunication.ControllerErrors* attribute), 122
 - NO_REF (*NewportStates* attribute), 125

NO_REF_ESP_STAGE_ERROR (New-
 portSMC100PP.StateMessages attribute), 113
 NO_REF_FROM_CONFIG (New-
 portSMC100PP.StateMessages attribute), 113
 NO_REF_FROM_DISABLED (New-
 portSMC100PP.StateMessages attribute), 113
 NO_REF_FROM_HOMING (New-
 portSMC100PP.StateMessages attribute), 113
 NO_REF_FROM_JOGGING (New-
 portSMC100PP.StateMessages attribute), 113
 NO_REF_FROM_MOVING (New-
 portSMC100PP.StateMessages attribute), 113
 NO_REF_FROM_READY (New-
 portSMC100PP.StateMessages attribute), 113
 NO_REF_FROM_RESET (New-
 portSMC100PP.StateMessages attribute), 113
 No_sensor (PfeifferTPG.SensorStatus attribute), 126
 NO_SOURCE (PowerSetup attribute), 50
 noise_level_measurement_channel_1 (BaseCube-
 Configuration attribute), 47
 noise_level_measurement_channel_2 (BaseCube-
 Configuration attribute), 47
 noise_level_measurement_channel_3 (BaseCube-
 Configuration attribute), 47
 noise_level_measurement_channel_4 (BaseCube-
 Configuration attribute), 47
 NONE (ILS2T.Ref16Jog attribute), 142
 NONE (LabJack.ThermocoupleType attribute), 95
 None (PfeifferTPG.SensorTypes attribute), 127
 NONE (SerialCommunicationParity attribute), 26
 NORMAL (RTO1024.TriggerModes attribute), 133
 noSen (PfeifferTPG.SensorTypes attribute), 127
 noSENSOR (PfeifferTPG.SensorTypes attribute), 127
 nr_trials_activate (LuminoxConfig attribute), 150
 NullCommunicationProtocol (class in
 hvl_ccb.comm.base), 14
 Number (in module hvl_ccb.utils.typing), 170
 number_of_decimals (HeinzingerConfig attribute), 82
 number_of_sensors (PfeifferTPG property), 128
 OFF (TriggerMode attribute), 90
 OH (NewportConfigCommands attribute), 112
 Ok (PfeifferTPG.SensorStatus attribute), 126
 on (FuG property), 68
 ON (FuGDigitalVal attribute), 70
 on (FuGProbusVDIRegisters property), 76
 ON (HeinzingerDI.OutputStatus attribute), 82
 ON (ILS2T.State attribute), 142
 ONE (HeinzingerConfig.RecordingsEnum attribute), 81
 ONE (LabJack.AInRange attribute), 93
 ONE (SerialCommunicationStopbits attribute), 26
 ONE_AMPERE (ACCurrentRange attribute), 65
 ONE_AMPERE (DCCurrentRange attribute), 66
 ONE_HUNDRED_MICRO_AMPERE (DCCurrentRange
 attribute), 66
 ONE_HUNDRED_MILLI_AMPERE (ACCurrentRange at-
 tribute), 65
 ONE_HUNDRED_MILLI_AMPERE (DCCurrentRange
 attribute), 66
 ONE_HUNDRED_MILLI_SECOND (ApertureRange at-
 tribute), 66
 ONE_HUNDRED_MILLI_VOLT (ACVoltageRange attribute),
 65
 ONE_HUNDRED_MILLI_VOLT (DCVoltageRange at-
 tribute), 66
 ONE_HUNDRED_MILLION_OHM (ResistanceRange at-
 tribute), 67
 ONE_HUNDRED_OHM (ResistanceRange attribute), 67
 ONE_HUNDRED_THOUSAND_OHM (ResistanceRange at-
 tribute), 67
 ONE_HUNDREDTH (LabJack.AInRange attribute), 93
 ONE_MILLI_AMPERE (DCCurrentRange attribute), 66
 ONE_MILLION_OHM (ResistanceRange attribute), 67
 ONE_POINT_FIVE (SerialCommunicationStopbits at-
 tribute), 26
 ONE_SECOND (ApertureRange attribute), 66
 ONE_TENTH (LabJack.AInRange attribute), 93
 ONE_THOUSAND_OHM (ResistanceRange attribute), 67
 ONE_THOUSAND_VOLT (DCVoltageRange attribute), 66
 ONE_VOLT (ACVoltageRange attribute), 65
 ONE_VOLT (DCVoltageRange attribute), 66
 ONLYUPWARDSOFFTOZERO (FuGRampModes attribute),
 78
 OPC_MAX_YEAR (BaseCube attribute), 43
 OPC_MIN_YEAR (BaseCube attribute), 43
 OpcUaCommunication (class in hvl_ccb.comm.opc), 20
 OpcUaCommunicationConfig (class in
 hvl_ccb.comm.opc), 21
 OpcUaCommunicationIOError, 22
 OpcUaCommunicationTimeoutError, 22
 OpcUaSubHandler (class in hvl_ccb.comm.opc), 22
 OPEN (DoorStatus attribute), 49
 OPEN (EarthingStickOperation attribute), 51
 OPEN (EarthingStickStatus attribute), 51
 ODD (SerialCommunicationParity attribute), 26
 OFF (AutoInstallMode attribute), 88
 OFF (FuGDigitalVal attribute), 70
 OFF (GateMode attribute), 88
 OFF (HeinzingerDI.OutputStatus attribute), 82

`open()` (*CommunicationProtocol* method), 14
`open()` (*LaudaProRp245eTcpCommunication* method), 106
`open()` (*LJMCommunication* method), 15
`open()` (*ModbusTcpCommunication* method), 18
`open()` (*NullCommunicationProtocol* method), 14
`open()` (*OpcUaCommunication* method), 20
`open()` (*SerialCommunication* method), 23
`open()` (*Tcp* method), 26
`open()` (*TelnetCommunication* method), 28
`open()` (*VisaCommunication* method), 30
`open_interlock` (*Technix* property), 156
`open_shutter()` (*CryLasLaser* method), 37
`open_timeout` (*VisaCommunicationConfig* attribute), 31
`OPENED` (*CryLasLaser.AnswersShutter* attribute), 36
`OPENED` (*CryLasLaserShutterStatus* attribute), 42
`operate` (*BaseCube* property), 44
`operate` (*PICube* property), 52
`OPERATION_MODE` (*LaudaProRp245eCommand* attribute), 103
`operation_mode` (*LaudaProRp245eConfig* attribute), 105
`optional_defaults()` (*AsyncCommunicationProtocolConfig* class method), 13
`optional_defaults()` (*BaseCubeConfiguration* class method), 47
`optional_defaults()` (*BaseCubeOpcUaCommunicationConfig* class method), 48
`optional_defaults()` (*CryLasAttenuatorConfig* class method), 34
`optional_defaults()` (*CryLasAttenuatorSerialCommunicationConfig* class method), 35
`optional_defaults()` (*CryLasLaserConfig* class method), 40
`optional_defaults()` (*CryLasLaserSerialCommunicationConfig* class method), 42
`optional_defaults()` (*EmptyConfig* class method), 163, 173
`optional_defaults()` (*Fluke8845aConfig* class method), 62
`optional_defaults()` (*Fluke8845aTelnetCommunicationConfig* class method), 63
`optional_defaults()` (*FuGConfig* class method), 70
`optional_defaults()` (*FuGSerialCommunicationConfig* class method), 80
`optional_defaults()` (*HeinzingerConfig* class method), 82
`optional_defaults()` (*HeinzingerSerialCommunicationConfig* class method), 86
`optional_defaults()` (*ILS2TConfig* class method), 145
`optional_defaults()` (*ILS2TModbusTcpCommunicationConfig* class method), 146
`optional_defaults()` (*LaudaProRp245eConfig* class method), 105
`optional_defaults()` (*LaudaProRp245eTcpCommunicationConfig* class method), 106
`optional_defaults()` (*LJMCommunicationConfig* class method), 17
`optional_defaults()` (*LuminoxConfig* class method), 150
`optional_defaults()` (*LuminoxSerialCommunicationConfig* class method), 152
`optional_defaults()` (*MBW973Config* class method), 109
`optional_defaults()` (*MBW973SerialCommunicationConfig* class method), 110
`optional_defaults()` (*ModbusTcpCommunicationConfig* class method), 19
`optional_defaults()` (*NewportSMC100PPConfig* class method), 121
`optional_defaults()` (*NewportSMC100PPSerialCommunicationConfig* class method), 125
`optional_defaults()` (*OpcUaCommunicationConfig* class method), 22
`optional_defaults()` (*PfeifferTPGConfig* class method), 129
`optional_defaults()` (*PfeifferTPGSerialCommunicationConfig* class method), 131
`optional_defaults()` (*PICubeConfiguration* class method), 53
`optional_defaults()` (*PICubeOpcUaCommunicationConfig* class method), 54
`optional_defaults()` (*PSI9000Config* class method), 58
`optional_defaults()` (*PSI9000VisaCommunicationConfig* class method), 59
`optional_defaults()` (*RTO1024Config* class method), 139
`optional_defaults()` (*RTO1024VisaCommunicationConfig* class method), 140
`optional_defaults()` (*SerialCommunicationConfig* class method), 25
`optional_defaults()` (*T560CommunicationConfig* class method), 89
`optional_defaults()` (*T560Config* class method), 92
`optional_defaults()` (*TcpCommunicationConfig* class method), 27
`optional_defaults()` (*TechnixConfig* class method), 157
`optional_defaults()` (*TechnixSerialCommunication-*

- Config class method), 154
- optional_defaults() (TechnixTelnetCommunicationConfig class method), 155
- optional_defaults() (TelnetCommunicationConfig class method), 29
- optional_defaults() (VisaCommunicationConfig class method), 31
- optional_defaults() (VisaDeviceConfig class method), 165
- OT (NewportConfigCommands attribute), 112
- out (FuGProbusVDORegisters property), 76
- OUTPUT (FuGProbusIVCommands attribute), 74
- OUTPUT (GateMode attribute), 88
- output (Technix property), 156
- output_off() (FuGProbusIV method), 73
- output_off() (HeinzingerDI method), 83
- output_on() (HeinzingerDI method), 83
- OUTPUT_POWER_EXCEEDED (NewportSMC100PP.MotorErrors attribute), 113
- output_status (HeinzingerDI property), 83
- OUTPUTONCMD (FuGProbusVRegisterGroups attribute), 77
- OUTPUTX0 (FuGProbusVRegisterGroups attribute), 77
- OUTPUTX1 (FuGProbusVRegisterGroups attribute), 77
- OUTPUTX2 (FuGProbusVRegisterGroups attribute), 77
- OUTPUTXCMD (FuGProbusVRegisterGroups attribute), 77
- outX0 (FuG property), 69
- outX1 (FuG property), 69
- outX2 (FuG property), 69
- outXCMD (FuG property), 69
- Overrange (PfeifferTPG.SensorStatus attribute), 126
- ## P
- PA (Pressure attribute), 167
- PARAM_MISSING_OR_INVALID (NewportSMC100PPSerialCommunication.ControllerErrors attribute), 122
- parity (CryLasAttenuatorSerialCommunicationConfig attribute), 35
- parity (CryLasLaserSerialCommunicationConfig attribute), 42
- parity (FuGSerialCommunicationConfig attribute), 80
- parity (HeinzingerSerialCommunicationConfig attribute), 86
- parity (LuminoxSerialCommunicationConfig attribute), 152
- parity (MBW973SerialCommunicationConfig attribute), 111
- parity (NewportSMC100PPSerialCommunicationConfig attribute), 125
- parity (PfeifferTPGSerialCommunicationConfig attribute), 131
- Parity (SerialCommunicationConfig attribute), 24
- parity (SerialCommunicationConfig attribute), 25
- parse_read_measurement_value() (LuminoxMeasurementType method), 150
- partial_pressure_o2 (LuminoxMeasurementType attribute), 150
- PASCAL (Pressure attribute), 167
- pause() (LaudaProRp245e method), 100
- pause_ramp() (LaudaProRp245e method), 100
- PBR (PfeifferTPG.SensorTypes attribute), 127
- PEAK_CURRENT_LIMIT (NewportSMC100PP.MotorErrors attribute), 113
- peak_output_current_limit (NewportSMC100PPConfig attribute), 121
- percent_o2 (LuminoxMeasurementType attribute), 150
- PERIOD (MeasurementFunction attribute), 64
- period (T560 property), 91
- period_aperture (Fluke8845a attribute), 61
- PfeifferTPG (class in hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg), 126
- PfeifferTPG.SensorStatus (class in hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg), 126
- PfeifferTPG.SensorTypes (class in hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg), 126
- PfeifferTPGConfig (class in hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg), 129
- PfeifferTPGConfig.Model (class in hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg), 129
- PfeifferTPGError, 130
- PfeifferTPGSerialCommunication (class in hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg), 130
- PfeifferTPGSerialCommunicationConfig (class in hvl_ccb.dev.pfeiffer_tpg.pfeiffer_tpg), 130
- PICube (class in hvl_ccb.dev.cube.picube), 52
- PICubeConfiguration (class in hvl_ccb.dev.cube.picube), 53
- PICubeOpcUaCommunication (class in hvl_ccb.dev.cube.picube), 54
- PICubeOpcUaCommunicationConfig (class in hvl_ccb.dev.cube.picube), 54
- PICubeTestParameterError, 52
- PKR (PfeifferTPG.SensorTypes attribute), 127
- Polarity (class in hvl_ccb.dev.cube.constants), 49
- Polarity (class in hvl_ccb.dev.highland_t560.base), 88
- POLARITY (FuGProbusIVCommands attribute), 74
- polarity (PICube property), 52
- Poller (class in hvl_ccb.utils.poller), 169
- polling (LuminoxOutputMode attribute), 151
- polling_delay_sec (BaseCubeConfiguration attribute), 47
- polling_interval (MBW973Config attribute), 109
- polling_interval_sec (BaseCubeConfiguration attribute), 47
- polling_interval_sec (TechnixConfig attribute), 157

polling_period (*CryLasLaserConfig* attribute), 40
 polling_timeout (*CryLasLaserConfig* attribute), 40
 port (*Fluke8845aTelnetCommunicationConfig* attribute), 64
 port (*ModbusTcpCommunicationConfig* attribute), 19
 port (*OpcUaCommunicationConfig* attribute), 22
 port (*SerialCommunicationConfig* attribute), 25
 port (*T560CommunicationConfig* attribute), 89
 port (*TcpCommunicationConfig* attribute), 27
 port (*TechnixTelnetCommunicationConfig* attribute), 155
 port (*TelnetCommunicationConfig* attribute), 29
 port (*VisaCommunicationConfig* attribute), 31
 POS (*ILS2T.Ref16Jog* attribute), 142
 POS_END_OF_TURN (*NewportSMC100PP.MotorErrors* attribute), 113
 POS_FAST (*ILS2T.Ref16Jog* attribute), 142
 POSITION (*ILS2T.RegAddr* attribute), 147
 POSITION_OUT_OF_LIMIT (*NewportSMC100PPSerialCommunication.ControllerErrors* attribute), 122
 POSITIVE (*FuGPolarities* attribute), 73
 POSITIVE (*Polarity* attribute), 50
 positive_software_limit (*NewportSMC100PPConfig* attribute), 121
 post_force_value() (*NewportSMC100PPConfig* method), 121
 post_stop_pause_sec (*TechnixConfig* attribute), 157
 POUNDS_PER_SQUARE_INCH (*Pressure* attribute), 167
 POWER_INVERTER_220V (*PowerSetup* attribute), 50
 power_limit (*PSI9000Config* attribute), 58
 power_setup (*PICube* property), 52
 PowerSetup (class in *hvl_ccb.dev.cube.constants*), 50
 prepare_ultra_segmentation() (*RTO1024* method), 135
 preserve_type() (in module *hvl_ccb.utils.conversion.utils*), 168
 Pressure (class in *hvl_ccb.utils.conversion.unit*), 167
 PSI (*Pressure* attribute), 167
 PSI9000 (class in *hvl_ccb.dev.ea_psi9000.ea_psi9000*), 55
 PSI9000Config (class in *hvl_ccb.dev.ea_psi9000.ea_psi9000*), 57
 PSI9000Error, 58
 PSI9000VisaCommunication (class in *hvl_ccb.dev.ea_psi9000.ea_psi9000*), 58
 PSI9000VisaCommunicationConfig (class in *hvl_ccb.dev.ea_psi9000.ea_psi9000*), 59
 PT100 (*LabJack.ThermocoupleType* attribute), 95
 PT1000 (*LabJack.ThermocoupleType* attribute), 95
 PT500 (*LabJack.ThermocoupleType* attribute), 95
 PTP (*ILS2T.Mode* attribute), 141
 pump_init (*LaudaProRp245eConfig* attribute), 105
 PUMP_LEVEL (*LaudaProRp245eCommand* attribute), 103

Q

QIL (*NewportConfigCommands* attribute), 112
 QUERY (*FuGProbusIVCommands* attribute), 74
 query() (*CryLasLaserSerialCommunication* method), 41
 query() (*Fluke8845aTelnetCommunication* method), 63
 query() (*FuGSerialCommunication* method), 79
 query() (*NewportSMC100PPSerialCommunication* method), 122
 query() (*PfeifferTPGSerialCommunication* method), 130
 query() (*SyncCommunicationProtocol* method), 15
 query() (*T560Communication* method), 88
 query() (*VisaCommunication* method), 30
 query_all() (*CryLasLaserSerialCommunication* method), 41
 query_command() (*LaudaProRp245eTcpCommunication* method), 106
 query_multiple() (*NewportSMC100PPSerialCommunication* method), 123
 query_polling() (*Luminex* method), 148
 query_status() (*Technix* method), 156
 QUEUE (*AutoInstallMode* attribute), 88
 QUICK_STOP (*SafetyStatus* attribute), 50
 QUICKSTOP (*ILS2T.State* attribute), 142
 quickstop() (*ILS2T* method), 144
 quit_error() (*BaseCube* method), 45

R

R (*LabJack.ThermocoupleType* attribute), 95
 raise() (*FuGErrorcodes* method), 72
 RAMP_ACC (*ILS2T.RegAddr* attribute), 147
 RAMP_CONTINUE (*LaudaProRp245eCommand* attribute), 103
 RAMP_DECEL (*ILS2T.RegAddr* attribute), 147
 RAMP_DELETE (*LaudaProRp245eCommand* attribute), 103
 RAMP_ITERATIONS (*LaudaProRp245eCommand* attribute), 103
 RAMP_N_MAX (*ILS2T.RegAddr* attribute), 147
 RAMP_PAUSE (*LaudaProRp245eCommand* attribute), 103
 RAMP_SELECT (*LaudaProRp245eCommand* attribute), 103
 RAMP_SET (*LaudaProRp245eCommand* attribute), 103
 RAMP_START (*LaudaProRp245eCommand* attribute), 103
 RAMP_STOP (*LaudaProRp245eCommand* attribute), 103
 RAMP_TYPE (*ILS2T.RegAddr* attribute), 147
 rampmode (*FuGProbusVSetRegisters* property), 77
 ramprate (*FuGProbusVSetRegisters* property), 77
 rampstate (*FuGProbusVSetRegisters* property), 78
 RAMPUPWARDS (*FuGRampModes* attribute), 78
 RangeEnum (class in *hvl_ccb.utils.enum*), 169

- RATEDCURRENT (*FuGReadbackChannels* attribute), 78
 RATEDVOLTAGE (*FuGReadbackChannels* attribute), 78
 read() (*AsyncCommunicationProtocol* method), 11
 read() (*BaseCube* method), 45
 read() (*CryLasLaserSerialCommunication* method), 41
 read() (*LaudaProRp245eTcpCommunication* method), 106
 read() (*MBW973* method), 108
 read() (*OpcUaCommunication* method), 20
 read() (*Tcp* method), 26
 read_all() (*AsyncCommunicationProtocol* method), 11
 read_bytes() (*AsyncCommunicationProtocol* method), 11
 read_bytes() (*SerialCommunication* method), 23
 read_bytes() (*TelnetCommunication* method), 28
 read_float() (*MBW973* method), 108
 read_holding_registers() (*ModbusTcpCommunication* method), 18
 read_input_registers() (*ModbusTcpCommunication* method), 18
 read_int() (*MBW973* method), 108
 read_measurement() (*RTO1024* method), 135
 read_measurements() (*MBW973* method), 108
 read_name() (*LJMCommunication* method), 16
 read_nonempty() (*AsyncCommunicationProtocol* method), 12
 read_output_while_polling (*TechnixConfig* attribute), 157
 read_resistance() (*LabJack* method), 97
 read_single_bytes() (*SerialCommunication* method), 23
 read_streaming() (*Luminex* method), 149
 read_termination (*VisaCommunicationConfig* attribute), 32
 read_text() (*AsyncCommunicationProtocol* method), 12
 read_text() (*NewportSMC100PPSerialCommunication* method), 123
 read_text_nonempty() (*AsyncCommunicationProtocol* method), 12
 READ_TEXT_SKIP_PREFIXES (*CryLasLaserSerialCommunication* attribute), 40
 read_thermocouple() (*LabJack* method), 97
 readback_data (*FuGProbusVConfigRegisters* property), 75
 READBACKCHANNEL (*FuGProbusIVCommands* attribute), 74
 ready (*BaseCube* property), 45
 READY (*CryLasLaser.AnswersStatus* attribute), 36
 READY (*ILS2T.State* attribute), 142
 READY (*NewportStates* attribute), 126
 READY_ACTIVE (*CryLasLaser.LaserStatus* attribute), 36
 READY_FROM_DISABLE (*NewportSMC100PP.StateMessages* attribute), 113
 READY_FROM_HOMING (*NewportSMC100PP.StateMessages* attribute), 113
 READY_FROM_JOGGING (*NewportSMC100PP.StateMessages* attribute), 113
 READY_FROM_MOVING (*NewportSMC100PP.StateMessages* attribute), 114
 READY_INACTIVE (*CryLasLaser.LaserStatus* attribute), 36
 RED_OPERATE (*SafetyStatus* attribute), 50
 RED_READY (*SafetyStatus* attribute), 51
 reg_3 (*FuGProbusVDIRegisters* property), 76
 RegAddr (*ILS2T* attribute), 142
 RegDatatype (*ILS2T* attribute), 142
 register_pulse_time (*TechnixConfig* attribute), 157
 RELATIVE_POSITION_MOTOR (*ILS2T.ActionsPtp* attribute), 141
 RELATIVE_POSITION_TARGET (*ILS2T.ActionsPtp* attribute), 141
 remote (*Technix* property), 156
 remove_device() (*DeviceSequenceMixin* method), 162
 required_keys() (*AsyncCommunicationProtocolConfig* class method), 14
 required_keys() (*BaseCubeConfiguration* class method), 47
 required_keys() (*BaseCubeOpcUaCommunicationConfig* class method), 48
 required_keys() (*CryLasAttenuatorConfig* class method), 34
 required_keys() (*CryLasAttenuatorSerialCommunicationConfig* class method), 35
 required_keys() (*CryLasLaserConfig* class method), 40
 required_keys() (*CryLasLaserSerialCommunicationConfig* class method), 42
 required_keys() (*EmptyConfig* class method), 163, 173
 required_keys() (*Fluke8845aConfig* class method), 62
 required_keys() (*Fluke8845aTelnetCommunicationConfig* class method), 64
 required_keys() (*FuGConfig* class method), 70
 required_keys() (*FuGSerialCommunicationConfig* class method), 80
 required_keys() (*HeinzingerConfig* class method), 82
 required_keys() (*HeinzingerSerialCommunicationConfig* class method), 86
 required_keys() (*ILS2TConfig* class method), 145
 required_keys() (*ILS2TModbusTcpCommunicationConfig* class method), 146
 required_keys() (*LaudaProRp245eConfig* class method), 105

[required_keys\(\)](#) (*LaudaProRp245eTcpCommunicationConfig* class method), 107
[required_keys\(\)](#) (*LJMCommunicationConfig* class method), 18
[required_keys\(\)](#) (*LuminosConfig* class method), 150
[required_keys\(\)](#) (*LuminosSerialCommunicationConfig* class method), 152
[required_keys\(\)](#) (*MBW973Config* class method), 109
[required_keys\(\)](#) (*MBW973SerialCommunicationConfig* class method), 111
[required_keys\(\)](#) (*ModbusTcpCommunicationConfig* class method), 19
[required_keys\(\)](#) (*NewportSMC100PPConfig* class method), 121
[required_keys\(\)](#) (*NewportSMC100PPSerialCommunicationConfig* class method), 125
[required_keys\(\)](#) (*OpCuaCommunicationConfig* class method), 22
[required_keys\(\)](#) (*PfeifferTPGConfig* class method), 130
[required_keys\(\)](#) (*PfeifferTPGSerialCommunicationConfig* class method), 131
[required_keys\(\)](#) (*PICubeConfiguration* class method), 53
[required_keys\(\)](#) (*PICubeOpCuaCommunicationConfig* class method), 54
[required_keys\(\)](#) (*PSI9000Config* class method), 58
[required_keys\(\)](#) (*PSI9000VisaCommunicationConfig* class method), 59
[required_keys\(\)](#) (*RTO1024Config* class method), 139
[required_keys\(\)](#) (*RTO1024VisaCommunicationConfig* class method), 140
[required_keys\(\)](#) (*SerialCommunicationConfig* class method), 25
[required_keys\(\)](#) (*T560CommunicationConfig* class method), 89
[required_keys\(\)](#) (*T560Config* class method), 92
[required_keys\(\)](#) (*TcpCommunicationConfig* class method), 27
[required_keys\(\)](#) (*TechnixConfig* class method), 157
[required_keys\(\)](#) (*TechnixSerialCommunicationConfig* class method), 154
[required_keys\(\)](#) (*TechnixTelnetCommunicationConfig* class method), 155
[required_keys\(\)](#) (*TelnetCommunicationConfig* class method), 29
[required_keys\(\)](#) (*VisaCommunicationConfig* class method), 32
[required_keys\(\)](#) (*VisaDeviceConfig* class method), 165
[RESET](#) (*FuGProbusIVCommands* attribute), 74
[reset\(\)](#) (*Fluke8845a* method), 61
[reset\(\)](#) (*FuGProbusIV* method), 73
[reset\(\)](#) (*NewportSMC100PP* method), 117
[reset\(\)](#) (*VisaDevice* method), 164
[reset_error\(\)](#) (*ILS2T* method), 144
[reset_interface\(\)](#) (*HeinzingerDI* method), 83
[reset_ramp\(\)](#) (*LaudaProRp245e* method), 101
[ResistanceRange](#) (class in *hvl_ccb.dev.fluke884x.ranges*), 67
[response_sleep_time](#) (*CryLasAttenuatorConfig* attribute), 34
[RMS_CURRENT_LIMIT](#) (*NewportSMC100PP.MotorErrors* attribute), 113
[rpm_max_init](#) (*ILS2TConfig* attribute), 145
[rs485_address](#) (*NewportSMC100PPConfig* attribute), 121
[RT01024](#) (class in *hvl_ccb.dev.rs_rto1024.rs_rto1024*), 132
[RT01024.TriggerModes](#) (class in *hvl_ccb.dev.rs_rto1024.rs_rto1024*), 132
[RT01024Config](#) (class in *hvl_ccb.dev.rs_rto1024.rs_rto1024*), 139
[RT01024Error](#), 139
[RT01024VisaCommunication](#) (class in *hvl_ccb.dev.rs_rto1024.rs_rto1024*), 139
[RT01024VisaCommunicationConfig](#) (class in *hvl_ccb.dev.rs_rto1024.rs_rto1024*), 140
[run\(\)](#) (*ExperimentManager* method), 174
[run\(\)](#) (*LaudaProRp245e* method), 101
[run_continuous_acquisition\(\)](#) (*RTO1024* method), 136
[run_single_acquisition\(\)](#) (*RTO1024* method), 136
[RUNNING](#) (*ExperimentStatus* attribute), 175

S

[S](#) (*LabJack.ThermocoupleType* attribute), 95
[SA](#) (*NewportConfigCommands* attribute), 112
[SafetyStatus](#) (class in *hvl_ccb.dev.cube.constants*), 50
[save_configuration\(\)](#) (*RTO1024* method), 136
[save_device_configuration\(\)](#) (*T560* method), 91
[save_waveform_history\(\)](#) (*RTO1024* method), 136
[SCALE](#) (*ILS2TRegAddr* attribute), 147
[ScalingFactorValueError](#), 148
[screw_scaling](#) (*NewportSMC100PPConfig* attribute), 121
[send_command\(\)](#) (*NewportSMC100PPSerialCommunication* method), 123
[send_command\(\)](#) (*PfeifferTPGSerialCommunication* method), 130
[send_hello\(\)](#) (*Client* method), 20
[send_pulses\(\)](#) (*LabJack* method), 97
[send_stop\(\)](#) (*NewportSMC100PPSerialCommunication* method), 124
[Sensor](#) (class in *hvl_ccb.utils.conversion.sensor*), 166

Sensor_error (*PfeifferTPG.SensorStatus* attribute), 126
 Sensor_off (*PfeifferTPG.SensorStatus* attribute), 126
 sensor_status (*LuminoxMeasurementType* attribute), 150
 SERIAL (*LaudaProRp245eConfig.ExtControlModeEnum* attribute), 104
 serial_number (*LuminoxMeasurementType* attribute), 151
 SerialCommunication (class in *hvl_ccb.comm.serial*), 23
 SerialCommunicationBytesize (class in *hvl_ccb.comm.serial*), 24
 SerialCommunicationConfig (class in *hvl_ccb.comm.serial*), 24
 SerialCommunicationIOError, 25
 SerialCommunicationParity (class in *hvl_ccb.comm.serial*), 25
 SerialCommunicationStopbits (class in *hvl_ccb.comm.serial*), 26
 Server (class in *hvl_ccb.comm.opc*), 23
 set_acceleration() (*NewportSMC100PP* method), 117
 set_acquire_length() (*RTO1024* method), 136
 set_ain_differential() (*LabJack* method), 98
 set_ain_range() (*LabJack* method), 98
 set_ain_resistance() (*LabJack* method), 98
 set_ain_resolution() (*LabJack* method), 98
 set_ain_thermocouple() (*LabJack* method), 98
 set_analog_output() (*LabJack* method), 99
 set_attenuation() (*CryLasAttenuator* method), 33
 set_channel_offset() (*RTO1024* method), 136
 set_channel_position() (*RTO1024* method), 137
 set_channel_range() (*RTO1024* method), 137
 set_channel_scale() (*RTO1024* method), 137
 set_channel_state() (*RTO1024* method), 137
 set_clock() (*LabJack* method), 99
 set_control_mode() (*LaudaProRp245e* method), 101
 set_current() (*HeinzingerDI* method), 84
 set_current() (*HeinzingerPNC* method), 85
 set_digital_output() (*LabJack* method), 99
 set_external_temp() (*LaudaProRp245e* method), 101
 set_full_scale_mbar() (*PfeifferTPG* method), 128
 set_full_scale_unitless() (*PfeifferTPG* method), 128
 set_init_attenuation() (*CryLasAttenuator* method), 33
 set_init_shutter_status() (*CryLasLaser* method), 37
 set_jog_speed() (*ILS2T* method), 144
 set_lower_limits() (*PSI9000* method), 56
 set_max_acceleration() (*ILS2T* method), 144
 set_max_deceleration() (*ILS2T* method), 144
 set_max_rpm() (*ILS2T* method), 144
 set_measuring_options() (*MBW973* method), 108
 set_message_board() (*BaseCube* method), 45
 set_motor_configuration() (*NewportSMC100PP* method), 118
 set_negative_software_limit() (*NewportSMC100PP* method), 118
 set_number_of_recordings() (*HeinzingerDI* method), 84
 set_output() (*PSI9000* method), 56
 set_positive_software_limit() (*NewportSMC100PP* method), 118
 set_pulse_energy() (*CryLasLaser* method), 38
 set_pump_level() (*LaudaProRp245e* method), 101
 set_ramp_iterations() (*LaudaProRp245e* method), 101
 set_ramp_program() (*LaudaProRp245e* method), 101
 set_ramp_segment() (*LaudaProRp245e* method), 102
 set_ramp_type() (*ILS2T* method), 144
 set_reference_point() (*RTO1024* method), 138
 set_register() (*FuGProbusV* method), 74
 set_repetition_rate() (*CryLasLaser* method), 38
 set_repetitions() (*RTO1024* method), 138
 set_status_board() (*BaseCube* method), 45
 set_system_lock() (*PSI9000* method), 56
 set_temp_set_point() (*LaudaProRp245e* method), 102
 set_transmission() (*CryLasAttenuator* method), 33
 set_trigger_level() (*RTO1024* method), 138
 set_trigger_mode() (*RTO1024* method), 138
 set_trigger_source() (*RTO1024* method), 138
 set_upper_limits() (*PSI9000* method), 56
 set_voltage() (*HeinzingerDI* method), 84
 set_voltage() (*HeinzingerPNC* method), 85
 set_voltage_current() (*PSI9000* method), 57
 SetAttr (class in *hvl_ccb.utils.conversion.utils*), 168
 SETCURRENT (*FuGProbusVRegisterGroups* attribute), 77
 setvalue (*FuGProbusVSetRegisters* property), 78
 SETVOLTAGE (*FuGProbusVRegisterGroups* attribute), 77
 SEVEN_HUNDRED_FIFTY_VOLT (*ACVoltageRange* attribute), 65
 SEVENBITS (*SerialCommunicationBytesize* attribute), 24
 SHORT_CIRCUIT (*NewportSMC100PP.MotorErrors* attribute), 113
 shunt (*LEM4000S* attribute), 166
 SHUTDOWN_CURRENT_LIMIT (*PSI9000* attribute), 55
 SHUTDOWN_VOLTAGE_LIMIT (*PSI9000* attribute), 55
 ShutterStatus (*CryLasLaser* attribute), 36
 ShutterStatus (*CryLasLaserConfig* attribute), 39
 SingleCommDevice (class in *hvl_ccb.dev.base*), 163
 SIXBITS (*SerialCommunicationBytesize* attribute), 24
 SIXTEEN (*HeinzingerConfig.RecordingsEnum* attribute), 81
 SL (*NewportConfigCommands* attribute), 112
 SLOW_FILTER (*FilterRange* attribute), 67
 SN (*FuGReadbackChannels* attribute), 78

SOFTWARE_INTERNAL_SIXTY (Cry- stop() (*CryLasLaser* method), 38
 LasLaser.RepetitionRates attribute), 36 stop() (*Device* method), 161
 SOFTWARE_INTERNAL_TEN (Cry- stop() (*DeviceSequenceMixin* method), 162
 LasLaser.RepetitionRates attribute), 36 stop() (*ExperimentManager* method), 174
 SOFTWARE_INTERNAL_TWENTY (Cry- stop() (*Fluke8845a* method), 61
 LasLaser.RepetitionRates attribute), 36 stop() (*FuGProbusIV* method), 73
 software_revision (*LuminosMeasurementType* stop() (*HeinzingerDI* method), 84
 attribute), 151 stop() (*ILS2T* method), 144
 SPACE (*SerialCommunicationParity* attribute), 26 stop() (*LabJack* method), 99
 SPECIALRAMPUPWARDS (*FuGRampModes* attribute), 78 stop() (*LaudaProRp245e* method), 102
 spoll() (*VisaCommunication* method), 30 stop() (*Luminos* method), 149
 spoll_handler() (*VisaDevice* method), 164 stop() (*MBW973* method), 108
 SR (*NewportConfigCommands* attribute), 112 stop() (*NewportSMC100PP* method), 119
 srq_mask (*FuGProbusVConfigRegisters* property), 75 stop() (*PfeifferTPG* method), 129
 srq_status (*FuGProbusVConfigRegisters* property), 75 stop() (*PSI9000* method), 57
 stage_configuration (*NewportSMC100PPConfig* at- stop() (*RTO1024* method), 139
 tribute), 121 stop() (*SingleCommDevice* method), 163
 START (*LaudaProRp245eCommand* attribute), 103 stop() (*Technix* method), 156
 start() (*BaseCube* method), 45 stop() (*VisaDevice* method), 164
 start() (*CryLasAttenuator* method), 33 stop_acquisition() (*RTO1024* method), 139
 start() (*CryLasLaser* method), 38 stop_motion() (*NewportSMC100PP* method), 119
 start() (*Device* method), 161 stop_polling() (*Poller* method), 170
 start() (*DeviceSequenceMixin* method), 162 stop_ramp() (*LaudaProRp245e* method), 102
 start() (*ExperimentManager* method), 174 STOP_SAFETY_STATUSES (in module
 hvl_ccb.dev.cube.constants), 50
 start() (*Fluke8845a* method), 61 stopbits (*CryLasAttenuatorSerialCommunicationCon-*
 fig attribute), 35
 start() (*FuG* method), 69 stopbits (*CryLasLaserSerialCommunicationConfig* at-
 tribute), 42
 start() (*FuGProbusIV* method), 73 stopbits (*FuGSerialCommunicationConfig* attribute),
 80
 start() (*HeinzingerDI* method), 84 stopbits (*HeinzingerSerialCommunicationConfig* at-
 tribute), 86
 start() (*HeinzingerPNC* method), 85 stopbits (*LuminosSerialCommunicationConfig* at-
 tribute), 152
 start() (*ILS2T* method), 144 stopbits (*MBW973SerialCommunicationConfig* at-
 tribute), 111
 start() (*LabJack* method), 99 stopbits (*NewportSMC100PPSerialCommunicationConfig*
 attribute), 125
 start() (*LaudaProRp245e* method), 102 stopbits (*PfeifferTPGSerialCommunicationConfig* at-
 tribute), 131
 start() (*Luminos* method), 149 Stopbits (*SerialCommunicationConfig* attribute), 24
 start() (*MBW973* method), 108 stopbits (*SerialCommunicationConfig* attribute), 25
 start() (*NewportSMC100PP* method), 119 streaming (*LuminosOutputMode* attribute), 151
 start() (*PfeifferTPG* method), 128 StrEnumBase (class in *hvl_ccb.utils.enum*), 169
 start() (*PSI9000* method), 57 sub_handler (*BaseCubeOpcUaCommunicationConfig*
 attribute), 48
 start() (*RTO1024* method), 139 sub_handler (*OpcUaCommunicationConfig* attribute),
 22
 start() (*SingleCommDevice* method), 163 SyncCommunicationProtocol (class in
 hvl_ccb.comm.base), 14
 start() (*Technix* method), 156 SyncCommunicationProtocolConfig (class in
 hvl_ccb.comm.base), 15
 start() (*VisaDevice* method), 164
 start_control() (*MBW973* method), 108
 start_polling() (*Poller* method), 170
 start_ramp() (*LaudaProRp245e* method), 102
 STARTING (*ExperimentStatus* attribute), 175
 States (*NewportSMC100PP* attribute), 114
 status (*BaseCube* property), 45
 status (*ExperimentManager* property), 174
 status (*FuGProbusVConfigRegisters* property), 75
 status (*FuGProbusVDOResisters* property), 76
 status (*Technix* property), 156
 STATUSBYTE (*FuGReadbackChannels* attribute), 78
 STOP (*LaudaProRp245eCommand* attribute), 103
 stop() (*BaseCube* method), 46

T

- T (*LabJack.ThermocoupleType* attribute), 95
- t13_socket_1 (*BaseCube* attribute), 46
- t13_socket_2 (*BaseCube* attribute), 46
- t13_socket_3 (*BaseCube* attribute), 46
- T1MS (*FuGMonitorModes* attribute), 72
- T200MS (*FuGMonitorModes* attribute), 72
- T20MS (*FuGMonitorModes* attribute), 72
- T256US (*FuGMonitorModes* attribute), 72
- T4 (*LabJack.DeviceType* attribute), 94
- T4 (*LJMCommunicationConfig.DeviceType* attribute), 17
- T40MS (*FuGMonitorModes* attribute), 72
- T4MS (*FuGMonitorModes* attribute), 72
- T560 (*class in hvl_ccb.dev.highland_t560.device*), 90
- T560Communication (*class in hvl_ccb.dev.highland_t560.base*), 88
- T560CommunicationConfig (*class in hvl_ccb.dev.highland_t560.base*), 89
- T560Config (*class in hvl_ccb.dev.highland_t560.device*), 91
- T560Error, 90
- T7 (*LabJack.DeviceType* attribute), 94
- T7 (*LJMCommunicationConfig.DeviceType* attribute), 17
- T7_PRO (*LabJack.DeviceType* attribute), 94
- T7_PRO (*LJMCommunicationConfig.DeviceType* attribute), 17
- T800MS (*FuGMonitorModes* attribute), 72
- T80MS (*FuGMonitorModes* attribute), 72
- target_pulse_energy (*CryLasLaser* property), 38
- Tcp (*class in hvl_ccb.comm.tcp*), 26
- TCP (*LJMCommunicationConfig.ConnectionType* attribute), 16
- TcpCommunicationConfig (*class in hvl_ccb.comm.tcp*), 26
- TCPIP_INSTR (*VisaCommunicationConfig.InterfaceType* attribute), 30
- TCPIP_SOCKET (*VisaCommunicationConfig.InterfaceType* attribute), 30
- TEC1 (*CryLasLaser.AnswersStatus* attribute), 36
- TEC2 (*CryLasLaser.AnswersStatus* attribute), 36
- Technix (*class in hvl_ccb.dev.technix.device*), 155
- TechnixConfig (*class in hvl_ccb.dev.technix.device*), 156
- TechnixError, 153
- TechnixFaultError, 153
- TechnixSerialCommunication (*class in hvl_ccb.dev.technix.base*), 153
- TechnixSerialCommunicationConfig (*class in hvl_ccb.dev.technix.base*), 153
- TechnixTelnetCommunication (*class in hvl_ccb.dev.technix.base*), 154
- TechnixTelnetCommunicationConfig (*class in hvl_ccb.dev.technix.base*), 154
- TelnetCommunication (*class in hvl_ccb.comm.telnet*), 27
- TelnetCommunicationConfig (*class in hvl_ccb.comm.telnet*), 28
- TelnetError, 29
- TEMP (*ILS2TRegAddr* attribute), 147
- TEMP_SET_POINT (*LaudaProRp245eCommand* attribute), 103
- temp_set_point_init (*LaudaProRp245eConfig* attribute), 105
- Temperature (*class in hvl_ccb.utils.conversion.unit*), 167
- temperature_sensor (*LuminoxMeasurementType* attribute), 151
- temperature_unit (*LMT70A* attribute), 166
- TEN (*LabJack.AInRange* attribute), 93
- TEN (*LabJack.CalMicroAmpere* attribute), 93
- TEN_AMPERE (*ACCurrentRange* attribute), 65
- TEN_AMPERE (*DCCurrentRange* attribute), 66
- TEN_MHZ (*LabJack.ClockFrequency* attribute), 94
- TEN_MILLI_AMPERE (*ACCurrentRange* attribute), 65
- TEN_MILLI_AMPERE (*DCCurrentRange* attribute), 66
- TEN_MILLI_SECOND (*ApertureRange* attribute), 66
- TEN_MILLION_OHM (*ResistanceRange* attribute), 67
- TEN_THOUSAND_OHM (*ResistanceRange* attribute), 67
- TEN_VOLT (*ACVoltageRange* attribute), 65
- TEN_VOLT (*DCVoltageRange* attribute), 66
- terminator (*AsyncCommunicationProtocolConfig* attribute), 14
- terminator (*CryLasAttenuatorSerialCommunicationConfig* attribute), 35
- terminator (*CryLasLaserSerialCommunicationConfig* attribute), 42
- terminator (*Fluke8845aTelnetCommunicationConfig* attribute), 64
- TERMINATOR (*FuGProbusIVCommands* attribute), 74
- terminator (*FuGProbusVConfigRegisters* property), 75
- terminator (*FuGSerialCommunicationConfig* attribute), 80
- terminator (*HeinzingerSerialCommunicationConfig* attribute), 87
- terminator (*LaudaProRp245eTcpCommunicationConfig* attribute), 107
- terminator (*LuminoxSerialCommunicationConfig* attribute), 152
- terminator (*MBW973SerialCommunicationConfig* attribute), 111
- terminator (*NewportSMC100PPSerialCommunicationConfig* attribute), 125
- terminator (*PfeifferTPGSerialCommunicationConfig* attribute), 132
- terminator (*T560CommunicationConfig* attribute), 90
- terminator_str() (*SerialCommunicationConfig* method), 25

THIRTY_TWO_BIT (*LabJack.BitLimit* attribute), 93
 THREE_AMPERE (*ACCurrentRange* attribute), 65
 THREE_AMPERE (*DCCurrentRange* attribute), 66
 timeout (*CryLasAttenuatorSerialCommunicationConfig* attribute), 35
 timeout (*CryLasLaserSerialCommunicationConfig* attribute), 42
 timeout (*FuGSerialCommunicationConfig* attribute), 80
 timeout (*HeinzingerSerialCommunicationConfig* attribute), 87
 timeout (*LuminosSerialCommunicationConfig* attribute), 153
 timeout (*MBW973SerialCommunicationConfig* attribute), 111
 timeout (*NewportSMC100PPSerialCommunicationConfig* attribute), 125
 timeout (*PfeifferTPGSerialCommunicationConfig* attribute), 132
 timeout (*SerialCommunicationConfig* attribute), 25
 timeout (*TelnetCommunicationConfig* attribute), 29
 timeout (*VisaCommunicationConfig* attribute), 32
 timeout_interval (*BaseCubeConfiguration* attribute), 47
 timeout_status_change (*BaseCubeConfiguration* attribute), 47
 timeout_test_parameters (*PICubeConfiguration* attribute), 53
 TORR (*Pressure* attribute), 167
 TPG25xA (*PfeifferTPGConfig.Model* attribute), 129
 TPGx6x (*PfeifferTPGConfig.Model* attribute), 129
 TPR (*PfeifferTPG.SensorTypes* attribute), 127
 transmission (*CryLasAttenuator* property), 33
 trigger() (*Fluke8845a* method), 61
 trigger_delay (*Fluke8845a* property), 61
 trigger_level (*T560* property), 91
 trigger_mode (*T560* property), 91
 trigger_source (*Fluke8845a* property), 62
 TriggerMode (class in *hvl_ccb.dev.highland_t560.base*), 90
 TriggerSource (class in *hvl_ccb.dev.fluke884x.constants*), 64
 TWELVE_HUNDRED_FIFTY_KHZ (*LabJack.ClockFrequency* attribute), 94
 TWENTY_FIVE_HUNDRED_KHZ (*LabJack.ClockFrequency* attribute), 94
 TWENTY_MHZ (*LabJack.ClockFrequency* attribute), 94
 TWO (*HeinzingerConfig.RecordingsEnum* attribute), 81
 TWO (*SerialCommunicationStopbits* attribute), 26
 TWO_HUNDRED (*LabJack.CalMicroAmpere* attribute), 93
 TWO_WIRE_RESISTANCE (*MeasurementFunction* attribute), 64
 two_wire_resistance_range (*Fluke8845a* attribute), 62

U

Underrange (*PfeifferTPG.SensorStatus* attribute), 126
 Unit (class in *hvl_ccb.utils.conversion.unit*), 167
 unit (*ILS2TModbusTcpCommunicationConfig* attribute), 147
 unit (*ModbusTcpCommunicationConfig* attribute), 19
 unit (*PfeifferTPG* property), 129
 unit() (*RangeEnum* class method), 169
 unit_current (*HeinzingerPNC* property), 85
 unit_voltage (*HeinzingerPNC* property), 85
 UNKNOWN (*HeinzingerDI.OutputStatus* attribute), 82
 UNKNOWN (*HeinzingerPNC.UnitCurrent* attribute), 84
 UNKNOWN (*HeinzingerPNC.UnitVoltage* attribute), 85
 UNREADY_INACTIVE (*CryLasLaser.LaserStatus* attribute), 36
 update_laser_status() (*CryLasLaser* method), 38
 update_parameter (*OpcUaCommunicationConfig* attribute), 22
 update_repetition_rate() (*CryLasLaser* method), 38
 update_shutter_status() (*CryLasLaser* method), 39
 update_target_pulse_energy() (*CryLasLaser* method), 39
 UpdateEspStageInfo (NewportSMC100PPConfig.EspStageConfig attribute), 120
 UPPER_TEMP (*LaudaProRp245eCommand* attribute), 103
 upper_temp (*LaudaProRp245eConfig* attribute), 105
 USB (*LaudaProRp245eConfig.ExtControlModeEnum* attribute), 104
 USB (*LJMCommunicationConfig.ConnectionType* attribute), 16
 use_external_clock() (*T560* method), 91
 user_position_offset (*NewportSMC100PPConfig* attribute), 121
 user_steps() (*ILS2T* method), 144

V

V (*HeinzingerPNC.UnitVoltage* attribute), 85
 VA (*NewportConfigCommands* attribute), 112
 validate_and_resolve_host() (in module *hvl_ccb.utils.validation*), 171
 validate_bool() (in module *hvl_ccb.utils.validation*), 171
 validate_number() (in module *hvl_ccb.utils.validation*), 171
 validate_pump_level() (*LaudaProRp245e* method), 102
 validate_tcp_port() (in module *hvl_ccb.utils.validation*), 171
 value (*FuGProbusVMonitorRegisters* property), 76
 value (*LabJack.AInRange* property), 93
 value_raw (*FuGProbusVMonitorRegisters* property), 76
 ValueEnum (class in *hvl_ccb.utils.enum*), 169

VB (*NewportConfigCommands* attribute), 112
velocity (*NewportSMC100PPConfig* attribute), 121
visa_backend (*VisaCommunicationConfig* attribute), 32
VisaCommunication (class in *hvl_ccb.comm.visa*), 29
VisaCommunicationConfig (class in *hvl_ccb.comm.visa*), 30
VisaCommunicationConfig.InterfaceType (class in *hvl_ccb.comm.visa*), 30
VisaCommunicationError, 32
VisaDevice (class in *hvl_ccb.dev.visa*), 163
VisaDeviceConfig (class in *hvl_ccb.dev.visa*), 164
VOLT (*ILS2TRegAddr* attribute), 147
voltage (*FuG* property), 69
VOLTAGE (*FuGProbusIVCommands* attribute), 74
VOLTAGE (*FuGReadbackChannels* attribute), 78
voltage (*Technix* property), 156
VOLTAGE_AC (*MeasurementFunction* attribute), 64
voltage_actual (*PICube* property), 52
VOLTAGE_DC (*MeasurementFunction* attribute), 64
voltage_filter (*Fluke8845a* attribute), 62
voltage_lower_limit (*PSI9000Config* attribute), 58
voltage_max (*PICube* property), 53
voltage_monitor (*FuG* property), 69
voltage_primary (*PICube* property), 53
voltage_regulation (*Technix* property), 156
voltage_upper_limit (*PSI9000Config* attribute), 58

W

WAIT_AFTER_WRITE (*VisaCommunication* attribute), 29
wait_for_polling_result() (*Poller* method), 170
wait_operation_complete() (*VisaDevice* method), 164
wait_sec_initialisation (*PSI9000Config* attribute), 58
wait_sec_max_disable (*ILS2TConfig* attribute), 146
wait_sec_post_absolute_position (*ILS2TConfig* attribute), 146
wait_sec_post_activate (*LuminorConfig* attribute), 150
wait_sec_post_cannot_disable (*ILS2TConfig* attribute), 146
wait_sec_post_enable (*ILS2TConfig* attribute), 146
wait_sec_post_relative_step (*ILS2TConfig* attribute), 146
wait_sec_pre_read_or_write (*LaudaProRp245eTcpCommunicationConfig* attribute), 107
wait_sec_read_text_nonempty (*AsyncCommunicationProtocolConfig* attribute), 14
wait_sec_read_text_nonempty (*FuGSerialCommunicationConfig* attribute), 80
wait_sec_read_text_nonempty (*HeinzingerSerialCommunicationConfig* attribute), 87

wait_sec_settings_effect (*PSI9000Config* attribute), 58
wait_sec_stop_commands (*FuGConfig* attribute), 70
wait_sec_stop_commands (*HeinzingerConfig* attribute), 82
wait_sec_system_lock (*PSI9000Config* attribute), 58
wait_sec_trials_activate (*LuminorConfig* attribute), 150
wait_timeout_retry_sec (*OpcUaCommunicationConfig* attribute), 22
wait_until_motor_initialized() (*NewportSMC100PP* method), 119
wait_until_ready() (*CryLasLaser* method), 39
WIFI (*LJMCommunicationConfig.ConnectionType* attribute), 16
write() (*AsyncCommunicationProtocol* method), 12
write() (*BaseCube* method), 46
write() (*MBW973* method), 109
write() (*OpcUaCommunication* method), 21
write() (*Tcp* method), 26
write() (*VisaCommunication* method), 30
write_absolute_position() (*ILS2T* method), 145
write_bytes() (*AsyncCommunicationProtocol* method), 12
write_bytes() (*SerialCommunication* method), 23
write_bytes() (*TelnetCommunication* method), 28
write_command() (*LaudaProRp245eTcpCommunication* method), 106
write_name() (*LJMCommunication* method), 16
write_names() (*LJMCommunication* method), 16
write_registers() (*ModbusTcpCommunication* method), 19
write_relative_step() (*ILS2T* method), 145
write_termination (*VisaCommunicationConfig* attribute), 32
write_text() (*AsyncCommunicationProtocol* method), 13
WRONG_ESP_STAGE (*NewportSMC100PP.MotorErrors* attribute), 113

X

x_stat (*FuGProbusVDIRegisters* property), 76
XOUTPUTS (*FuGProbusIVCommands* attribute), 74

Y

YES (*FuGDigitalVal* attribute), 70

Z

ZX (*NewportConfigCommands* attribute), 112