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**canlib**

***Release 1.19.205***

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The canlib module is a Python wrapper for [Kvaser CANlib SDK](#).

*“The CANlib Software Development Kit is your Application Programming Interface for working with all Kvaser hardware platforms.”*

Using the Python canlib package, you will be able to control most aspects of any Kvaser CAN interface via Python.



## CONTENTS

### 1.1 Welcome

The canlib package is a Python wrapper for [Kvaser CANlib SDK](#).

*“The CANlib Software Development Kit is your Application Programming Interface for working with all Kvaser hardware platforms.”*

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canlib - a Python wrapper for Kvaser CANlib

### 1.2 Supported Libraries and Installation

The Python canlib module wraps the Kvaser CANlib API in order to make it easy to control most aspects of any Kvaser CAN interface. For more information about Kvaser please go to <https://www.kvaser.com/>.

The latest version of this package is available on the [Kvaser Download page](#) ([pycanlib.zip](#)).

#### 1.2.1 Supported platforms

Windows and Linux using Python v3.6+ (both 32 and 64 bit).

#### 1.2.2 Supported libraries

The following libraries are currently supported:

Library	Module	Windows	Linux
CANlib	can-lib.canlib	canlib32.dll	libcanlib.so
kvaMemoLibXML	can-lib.kvamemolibxml	kvaMemoLibXML.dll	libkvamemolibxml.so
kvrlib	canlib.kvrlib	kvrlib.dll, irisdll.dll, irisflash.dll, libxml2.dll	not supported
kvmlib	can-lib.kvmlib	kvaMemoLib0600.dll, kvaMemoLib0700.dll, kvaMemoLib.dll, kvmlib.dll	not supported, <sup>2</sup> libkvamemolib0700.so, libkvamemolib.so, libkvmlib.so
kvclib	can-lib.kvclib	kvclib.dll <sup>1</sup>	libkvclib.so
kvaDbLib	can-lib.kvadblib	kvaDbLib.dll	libkvadblib.so
LINlib	canlib.linlib	linlib.dll	liblinlib.so

### 1.2.3 Installation

Install the Python package from [PyPI](#) using e.g. `pip`:

```
$ pip install canlib
```

If you have downloaded the package zip file from the [Kvaser Download page](#), first unzip `pycanlib.zip`. Then navigate to the unzipped `pycanlib` using the command line. It should contain the file `canlib-x.y.z-py2.py3-none-any.whl`, where `x,y,z` are version numbers. Run the following command:

```
$ pip install canlib-x.y.z-py2.py3-none-any.whl
```

The Kvaser CANlib DLLs or shared libraries also need to be installed:

#### Windows

On **Windows**, first install the `canlib32.dll` by downloading and installing “Kvaser Drivers for Windows” which can be found on the [Kvaser Download page](#) (`kvaser_drivers_setup.exe`) This will also install `kvrlib.dll`, `irisdll.dll`, `irisflash.dll` and `libxml2.dll` used by `kvrlib`.

The “Kvaser CANlib SDK” also needs to be downloaded from the same place (`canlib.exe`) and installed if more than just CANlib will be used. This will install the rest of the supported library dll’s.

The two packages, “Kvaser Drivers for Windows” and “Kvaser CANlib SDK”, contains both 32 and 64 bit versions of the included dll’s.

<sup>2</sup> The `kvaMemoLib0600.dll`, which supports older devices, is not supported under Linux.

<sup>1</sup> The `kvclib.dll` depends on dll files from matlab wich are installed alongside `kvclib.dll`.



## Linux

On **Linux**, first install the `libcanlib.so` by downloading and installing “Kvaser LINUX Driver and SDK” which can be found on the [Kvaser Download page](#) (`linuxcan.tar.gz`).

If more than just CANlib will be used, the rest of the supported libraries will be available by downloading and installing “Linux SDK library” (`kvlibsdk.tar.gz`).

### 1.2.4 Usage

Example of using `canlib` to list some information about connected Kvaser devices:

```
from canlib import canlib

num_channels = canlib.getNumberOfChannels()
print(f"Found {num_channels} channels")
for ch in range(num_channels):
    chd = canlib.ChannelData(ch)
    print(f"{ch}. {chd.channel_name} ({chd.card_upc_no} / {chd.card_serial_no})")
```

Which may result in:

```
Found 4 channels
0. Kvaser Memorator Pro 2xHS v2 (channel 0) (73-30130-00819-9 / 12330)
1. Kvaser Memorator Pro 2xHS v2 (channel 1) (73-30130-00819-9 / 12330)
2. Kvaser Virtual CAN Driver (channel 0) (00-00000-00000-0 / 0)
3. Kvaser Virtual CAN Driver (channel 1) (00-00000-00000-0 / 0)
```

### 1.2.5 Support

You are invited to visit the Kvaser web pages at <https://www.kvaser.com/support/>. If you don't find what you are looking for, you can obtain support on a time-available basis by sending an e-mail to [support@kvaser.com](mailto:support@kvaser.com).

Bug reports, contributions, suggestions for improvements, and similar things are much appreciated and can be sent by e-mail to [support@kvaser.com](mailto:support@kvaser.com).

### 1.2.6 What's new

A complete set of release notes are available in the package documentation included in the zip file available at the [Kvaser Download page](#).

### 1.2.7 Links

- Kvaser CANlib SDK Page: <https://www.kvaser.com/developer/canlib-sdk/>
- Description of CANlib SDK library contents: <https://www.kvaser.com/developer-blog/get-hardware-kvaser-sdk-libraries/>

## 1.2.8 Wrapped libraries

- *canlib*
- *kvadblib*
- *kvamemolibxml*
- *kvcllib*
- *kvmlib*
- *kvrlib*
- *linlib*

## 1.3 Tutorials

### 1.3.1 canlib

#### Contents

- *canlib*
  - *List connected devices*
  - *Send and receive single frame*
  - *Send and receive CAN FD frame*

The following sections contain sample code for inspiration on how to use Kvaser Python canlib.

#### List connected devices

This code print some basic information (device name, EAN number and serial number) from all connected devices.

```
from canlib import canlib

num_channels = canlib.getNumberOfChannels()
print("Found %d channels" % num_channels)
for ch in range(0, num_channels):
    chdata = canlib.ChannelData(ch)
    print("%d. %s (%s / %s)" % (ch, chdata.device_name,
                              chdata.card_upc_no,
                              chdata.card_serial_no))
```

## Send and receive single frame

Here is some basic code to send and receive a single frame.

```

from canlib import canlib, Frame
from canlib.canlib import ChannelData

def setUpChannel(channel=0,
                 openFlags=canlib.Open.ACCEPT_VIRTUAL,
                 outputControl=canlib.Driver.NORMAL):
    ch = canlib.openChannel(channel, openFlags)
    print("Using channel: %s, EAN: %s" % (ChannelData(channel).channel_name,
                                         ChannelData(channel).card_upc_no))

    ch.setBusOutputControl(outputControl)
    # Specifying a bus speed of 250 kbit/s. See documentation
    # for more information on how to set bus parameters.
    params = canlib.busparams.BusParamsTq(
        tq=8,
        phase1=2,
        phase2=2,
        sjw=1,
        prescaler=40,
        prop=3
    )
    ch.set_bus_params_tq(params)
    ch.busOn()
    return ch

def tearDownChannel(ch):
    ch.busOff()
    ch.close()

print("canlib version:", canlib.dllversion())

ch0 = setUpChannel(channel=0)
ch1 = setUpChannel(channel=1)

frame = Frame(
    id_=100,
    data=[1, 2, 3, 4],
    flags=canlib.MessageFlag.EXT
)
ch1.write(frame)

while True:
    try:
        frame = ch0.read()
        print(frame)
        break
    except (canlib.canNoMsg) as ex:
        pass

```

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```
except (canlib.canError) as ex:
    print(ex)

tearDownChannel(ch0)
tearDownChannel(ch1)
```

## Send and receive CAN FD frame

Here are some minimal code to send and receive a CAN FD frame.

```
from canlib import canlib, Frame

# Specifying an arbitration phase bus speed of 1 Mbit/s,
# and a data phase bus speed of 2 Mbit/s. See documentation
# for more information on how to set bus parameters.
params_arbitration = canlib.busparams.BusParamsTq(
    tq=40,
    phase1=8,
    phase2=8,
    sjw=8,
    prescaler=2,
    prop=23
)
params_data = canlib.busparams.BusParamsTq(
    tq=20,
    phase1=15,
    phase2=4,
    sjw=4,
    prescaler=2,
    prop=0
)

# open channel as CAN FD using the flag
ch0 = canlib.openChannel(channel=0, flags=canlib.Open.CAN_FD)
ch0.setBusOutputControl(drivertype=canlib.Driver.NORMAL)
ch0.set_bus_params_tq(params_arbitration, params_data)
ch0.busOn()

ch1 = canlib.openChannel(channel=1, flags=canlib.Open.CAN_FD)
ch1.setBusOutputControl(drivertype=canlib.Driver.NORMAL)
ch1.set_bus_params_tq(params_arbitration, params_data)
ch1.busOn()

# set FDF flag to send using CAN FD
# set BRS flag to send using higher bit rate in the data phase
frame = Frame(
    id_=100,
    data=range(32),
    flags=canlib.MessageFlag.FDF | canlib.MessageFlag.BRS
)
print('Sending', frame)
```

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```

ch0.write(frame)

frame = ch1.read(timeout=1000)
print('Receiving', frame)

ch0.busOff()
ch1.busOff()

```

### 1.3.2 kvrlib

#### Contents

- *kvrlib*
  - *Connect to your remote device*

The following sections contain sample code for inspiration on how to use Kvaser Python kvrlib.

#### Connect to your remote device

Use the discovery functions to scan and connect to a remote device. Our remote device has serial number 16 and is already connected to the same network as our computer:

```

from canlib import kvrlib

SERIAL_NO = 10545

print("kvrlib version: %s" % kvrlib.getVersion())
print("Connecting to device with serial number %s" % SERIAL_NO)

addressList = kvrlib.kvrDiscovery.getDefaultAddresses(kvrlib.kvrAddressTypeFlag_
↳ BROADCAST)
print("Looking for device using addresses: %s" % addressList)
discovery = kvrlib.kvrDiscovery()
discovery.setAddresses(addressList)
deviceInfos = discovery.getResults()
print("Scanning result:\n%s" % deviceInfos)
# Connect to device with correct SERIAL_NO
for deviceInfo in deviceInfos:
    if deviceInfo.ser_no == SERIAL_NO:
        deviceInfo.connect()
        print('\nConnecting to the following device:')
        print('-----')
        print(deviceInfo)
        discovery.storeDevices(deviceInfos)
        break;
discovery.close()

```

This results in the following:

```

kvrlib version: 2070
Connecting to device with serial number 10545
Looking for device using addresses: 10.0.255.255:0 (IPV4_PORT)
Scanning result:
[
name/hostname   : "MiMi-06348-000710" / "kv-06348-000710"
  ean/serial    : 73301-30006348 / 710
  fw           : 2.4.231
  addr/cli/AP  : 10.0.3.138 (IPV4) / 10.0.3.84 (IPV4) / - (UNKNOWN)
  availability : Availability.STORED|FOUND_BY_SCAN
  usage/access : DeviceUsage.FREE / Accessibility.PUBLIC
  pass/enc.key : yes / yes,
name/hostname   : "TestClient1-2-DUT-01" / "swtdut01"
  ean/serial    : 73301-30006713 / 10545
  fw           : 3.4.822
  addr/cli/AP  : 10.0.3.54 (IPV4) / 10.0.3.98 (IPV4) / - (UNKNOWN)
  availability : Availability.STORED|FOUND_BY_SCAN
  usage/access : DeviceUsage.REMOTE / Accessibility.PUBLIC
  pass/enc.key : yes / yes]

```

Connecting to the following device:

```

-----
name/hostname   : "TestClient1-2-DUT-01" / "swtdut01"
  ean/serial    : 73301-30006713 / 10545
  fw           : 3.4.822
  addr/cli/AP  : 10.0.3.54 (IPV4) / 10.0.3.98 (IPV4) / - (UNKNOWN)
  availability : Availability.STORED|FOUND_BY_SCAN
  usage/access : DeviceUsage.REMOTE / Accessibility.PUBLIC
  pass/enc.key : yes / yes

```

### 1.3.3 linlib

The following sections contain sample code for inspiration on how to use Kvaser Python linlib.

#### Basic master slave usage

This code opens up one master and one slave, sets bitrate and then the slave sends a wakeup message to the master.

```

# import the linlib wrapper from the canlib package
from canlib import linlib

# print information about device firmware version
print(linlib.getChannelData(channel_number=0,
                           item=linlib.ChannelData.CARD_FIRMWARE_REV))

# open the first channel as a Master
master = linlib.openChannel(channel_number=0,
                           channel_type=linlib.ChannelType.MASTER)

# open the next channel as a Slave

```

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```

slave = linlib.openChannel(channel_number=1,
                           channel_type=linlib.ChannelType.SLAVE)

# setup bitrate
master.setBitrate(10000)
slave.setBitrate(10000)

# activate the LIN interface by going bus on
master.busOn()
slave.busOn()

# send a wakeup frame from the slave
slave.writeWakeup()

# read the frame when it arrives at the master
frame = master.read(timeout=100)
print(frame)

# go bus off
master.busOff()
slave.busOff()

```

### Sending message from master

Our next example uses two shorthand helper functions to open the channels. We then send some messages from the master and see that they arrive.

```

from canlib import linlib, Frame

# open the first channel as Master, using helper function
master = linlib.openMaster(0)

# open the next channel as a Slave, using helper function
slave = linlib.openSlave(1)

# go bus on
master.busOn()
slave.busOn()

# send some messages from master
NUM_MESSAGES = 2
for i in range(NUM_MESSAGES):
    master.writeMessage(Frame(id_=i, data=[1, 2, 3, 4, 5, 6, 7, 8]))
master.writeSync(100)

# print the received messages at the slave
for i in range(NUM_MESSAGES):
    frame = slave.read(timeout=100)
    print(frame)

# the master should also have recorded the messages

```

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```
for i in range(NUM_MESSAGES):
    frame = master.read(timeout=100)
    print(frame)

# go bus off
master.busOff()
slave.busOff()
```

## Requesting LIN 2.0 message

As a last example, let's look at using LIN 2.0 and setting up a message, using the Frame object, on the slave which is then requested by the master.

```
from canlib import linlib, Frame

ID = 0x17
DATA = bytearray([1, 2, 3, 4])

# open the first channel as Master, using helper function
master = linlib.openMaster(0, bps=200000)

# open the next channel as a Slave, using helper function
slave = linlib.openSlave(1)

master.busOn()
slave.busOn()

# configure channels to use LIN 2.0
slave.setupLIN(flags=linlib.Setup.ENHANCED_CHECKSUM | linlib.Setup.VARIABLE_DLC)
master.setupLIN(flags=linlib.Setup.ENHANCED_CHECKSUM | linlib.Setup.VARIABLE_DLC)

# setup a message in the slave
slave.updateMessage(Frame(id_=ID, data=DATA))

# request the message and print it
master.requestMessage(ID)
frame = master.read(timeout=100)
print(frame)

# clear the message
slave.clearMessage(0x17)

# we should now get an empty message
master.requestMessage(0x17)
frame = master.read(timeout=100)
print(frame)

# go bus off
master.busOff()
slave.busOff()
```



## 1.4 Using canlib (CANlib)

The canlib module wraps the CAN bus API (CANlib), which is used to interact with Kvaser CAN devices connected to your computer and the CAN bus. At its core you have functions to set bus parameters (e.g. bit rate), go bus on/off and read/write CAN messages. You can also use CANlib to download and start t programs on supported devices.

### 1.4.1 Introduction

#### Hello, CAN!

Let's start with a simple example:

```
# The CANlib library is initialized when the canlib module is imported.
from canlib import canlib, Frame

# Open a channel to a CAN circuit. In this case we open channel 0 which
# should be the first channel on the CAN interface. EXCLUSIVE means we don't
# want to share this channel with any other currently executing program.
# We also set the CAN bus bit rate to 250 kBit/s, using a set of predefined
# bus parameters.
ch = canlib.openChannel(
    channel=0,
    flags=canlib.Open.EXCLUSIVE,
    bitrate= canlib.can_BITRATE_250K,
)

# Set the CAN bus driver type to NORMAL.
ch.setBusOutputControl(canlib.Driver.NORMAL)

# Activate the CAN chip.
ch.busOn()

# Transmit a message with (11-bit) CAN id = 123, length 6 and contents
# (decimal) 72, 69, 76, 76, 79, 33.
frame = Frame(id_=123, data=b'HELLO!', dlc=6)
ch.write(frame)

# Wait until the message is sent or at most 500 ms.
ch.writeSync(timeout=500)

# Inactivate the CAN chip.
ch.busOff()

# Close the channel.
ch.close()
```

## canlib Core API Calls

The following calls can be considered the “core” of canlib as they are essential for almost any program that uses the CAN bus:

- *openChannel* and *close*
- *busOn* and *busOff*
- *read*
- *write* and *writeSync*

## 1.4.2 Initialization

### Library Initialization

The underlying CANlib library is initialized when the module `canlib.canlib` is imported. This will initialize the CANlib library and enumerate all currently available CAN channels.

### Library Deinitialization and Cleanup

Strictly speaking it is not necessary to clean up anything before terminating the application. If the application quits unexpectedly, the device driver will ensure the CAN controller is deactivated and the driver will also ensure the firmware (if any) is left in a consistent state.

To reinitialize the library in an orderly fashion you may want to call `canlib.Channel.writeSync` with a short timeout for each open handle before closing them with `canlib.Channel.close`, to ensure the transmit queues are empty. You can then start afresh by calling `canlib.reinitializeLibrary`.

---

**Note:** When calling `canlib.reinitializeLibrary`, all previously opened CAN handles (`canlib.Channel`) will be closed and invalidated.

---

### Manually Enumerating CAN channels

The function `canlib.enumerate_hardware` scans all currently connected devices and creates a completely new set of CANlib channel numbers, while still keeping all currently opened channel handles valid and usable. This can be viewed upon as a replacement for calling `canlib.reinitializeLibrary` which do invalidate all open channel handles.

One thing to keep in mind when using this functionality is to never track devices based on their CANlib channel number, since this number may change anytime `enumerate_hardware` is called. To retrieve information about a specific channel use `Channel.channel_data` to get a safe `ChannelData`, instead of relying on an old `ChannelData` object created from a channel number.

---

**Note:** On Linux, no re-enumeration is needed since enumeration takes place when a device is plugged in or unplugged.

---

## 1.4.3 Devices and Channels

### Identifying Devices and Channels

Once we have imported `canlib.canlib`, which enumerates the connected Kvaser CAN devices, we can call `getNumberOfChannels` to get the number of enumerated channels in our system.

This code snippet reads the number of enumerated channels found in the PC:

```
>>> from canlib import canlib
>>> canlib.getNumberOfChannels()
8
```

### Channel Information

Use `ChannelData` to obtain data for a specific channel, for example, the hardware type of the CAN interface.

We can use `ChannelData` for the CANlib channel numbers 0, 1, 2,..., n-1 (where n is the number returned by `getNumberOfChannels`) to get information about that specific channel.

To uniquely identify a device, we need to look at both the `ChannelData.card_upc_no` and `ChannelData.card_serial_no`.

The following code snippet loops through all known channels and prints the type of the CAN card they're on.

```
>>> from canlib import canlib
...
... num_channels = canlib.getNumberOfChannels()
... print("Found %d channels" % num_channels)
... for channel in range(0, num_channels):
...     chdata = canlib.ChannelData(channel)
...     print("%d. %s (%s / %s)" % (
...         channel,
...         chdata.channel_name,
...         chdata.card_upc_no,
...         chdata.card_serial_no)
...     )
Found 8 channels
0. Kvaser Leaf Light HS (channel 0) (73-30130-00241-8 / 1346)
1. Kvaser Memorator Pro 2xHS v2 (channel 0) (73-30130-00819-9 / 11573)
2. Kvaser Memorator Pro 2xHS v2 (channel 1) (73-30130-00819-9 / 11573)
3. Kvaser Leaf Pro HS v2 (channel 0) (73-30130-00843-4 / 10012)
4. Kvaser Hybrid 2xCAN/LIN (channel 0) (73-30130-00965-3 / 1100)
5. Kvaser Hybrid 2xCAN/LIN (channel 1) (73-30130-00965-3 / 1100)
6. Kvaser Virtual CAN Driver (channel 0) (00-00000-00000-0 / 0)
7. Kvaser Virtual CAN Driver (channel 1) (00-00000-00000-0 / 0)
```

## Customized Channel Name

It is possible to set the customized name returned by `ChannelData.card_serial_no` on the device using Kvaser Device Guide by right clicking on the device channel and selecting “Edit Channel Name”

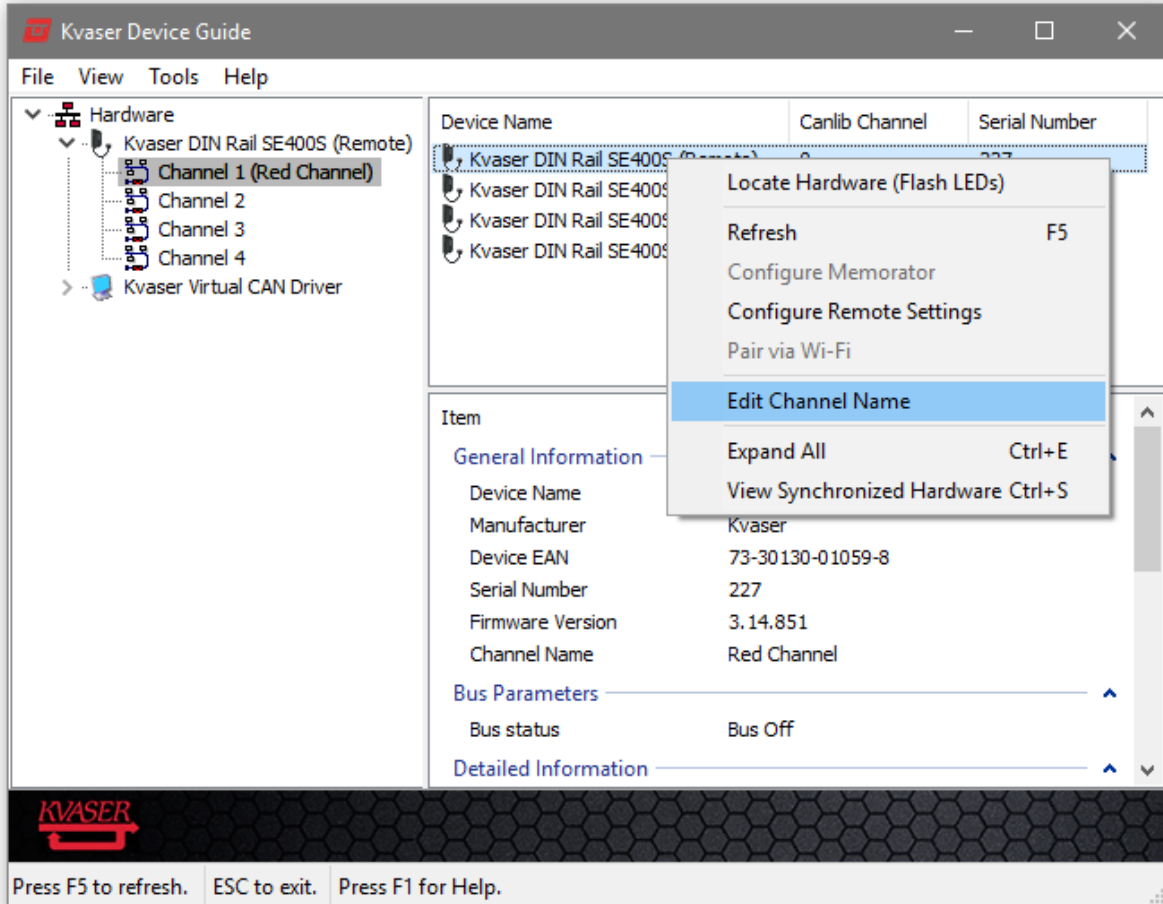


Fig. 1: Setting the device’s Channel Name from inside Kvaser Device Guide

Now we can read the customized name:

```
>>> from canlib import canlib
>>> chdata = canlib.ChannelData(channel_number=0)
>>> chdata.custom_name
'Red Channel'
```

## Virtual Channels

CANlib supports virtual channels that you can use for development, test or demonstration purposes when you don't have any hardware installed.

To open a virtual channel, call `openChannel` with the appropriate channel number, and specify `ACCEPT_VIRTUAL` in the flags argument to `canOpenChannel()`.

### 1.4.4 Open Channel

Once we have imported `canlib.canlib` to enumerate the connected Kvaser CAN devices, the next call is likely to be a call to `openChannel`, which returns a `Channel` object for the specific CAN circuit. This object is then used for subsequent calls to the library. The `openChannel` function's first argument is the number of the desired channel, the second argument is modifier flags `Open`.

`openChannel` may raise several different exceptions, one of which is `CanNotFound`. This means that the channel specified in the first parameter was not found, or that the flags passed to `openChannel` is not applicable to the specified channel.

#### Open as CAN

No special `Open` modifier flag is needed in the flags argument to `openChannel` when opening a channel in CAN mode.

```
>>> from canlib import canlib
>>> canlib.openChannel(channel=0, flags=canlib.Open.EXCLUSIVE)
<canlib.canlib.channel.Channel object at 0x0000015B787EDA90>
```

#### Open as CAN FD

To open a channel in CAN FD mode, either `CAN_FD` or `CAN_FD_NONISO` needs to be given in the flags argument to `openChannel`.

This example opens channel 0 in CAN FD mode for exclusive usage by this application:

```
>>> from canlib import canlib
>>> ch = canlib.openChannel(
...     channel=0,
...     flags=canlib.Open.CAN_FD | canlib.Open.EXCLUSIVE,
... )
>>> ch.close()
```

#### Close Channel

Closing a channel is done using `close`. If no other handles are referencing the same CANlib channel, the channel is taken off bus.

The CAN channel can also be opened and closed using a context manager:

```
>>> from canlib import canlib
>>> with canlib.openChannel(channel=1) as ch:
...     ...
```

## Check Channel Capabilities

Channel specific information and capabilities are made available by reading attributes of an instance of type *ChannelData*.

The device clock frequency can be obtained via `frequency()` :

```
>>> from canlib import canlib
>>> chd = canlib.ChannelData(channel_number=0)
>>> clock_info = chd.clock_info
>>> clock_info.frequency()
80000000
```

The capabilities of a channel can be obtained by reading attribute `channel_cap` and `channel_cap_ex`:

```
>>> from canlib import canlib
>>> chd = canlib.ChannelData(channel_number=0)
>>> chd.channel_cap
ChannelCap.IO_API|SCRIPT|LOGGER|SINGLE_SHOT|SILENT_MODE|CAN_FD_NONISO|CAN_FD|
TXACKNOWLEDGE|TXREQUEST|GENERATE_ERROR|ERROR_COUNTERS|BUS_STATISTICS|EXTENDED_CAN
>>> chd.channel_cap_ex[0]
ChannelCapEx.BUSPARAMS_TQ
```

A bitwise AND operator can be used to see if a channel has a specific capability.

```
>>> if (chd.channel_cap & canlib.ChannelCap.CAN_FD):
>>>     print("Channel has support for CAN FD!")
Channel has support for CAN FD!
```

The above printouts are just an example, and will differ for different devices and installed firmware.

## Set CAN Bitrate

After opening the channel in classic CAN mode (see *Open as CAN*), use `set_bus_params_tq` to specify the bit timing parameters on the CAN bus. Bit timing parameters are packaged in an instance of type *BusParamsTq*. Note that the synchronization segment is excluded as it is always one time quantum long.

**Example:** Set the bus speed to 500 kbit/s on a CAN device with an 80 MHz oscillator:

```
>>> from canlib import canlib
>>> ch = canlib.openChannel(channel=0)
>>> params = canlib.busparams.BusParamsTq(
...     tq=8,
...     phase1=2,
...     phase2=2,
...     sjw=1,
...     prescaler=20,
...     prop=3
... )
>>> ch.set_bus_params_tq(params)
```

In the example a prescaler of 20 is used, resulting in each bit comprising of 160 time quanta ( $8 * 20$ ). The nominal bus speed is given by  $80 * 10^6 / (20 * 8) = 500 * 10^3$ .

If uncertain how to set a specific bus speed, one can use `calc_busparamstq`, which returns a *BusParamsTq* object:

```
>>> calc_busparamstq(
...   target_bitrate=470_000,
...   target_sample_point=82,
...   target_sync_jump_width=15.3,
...   clk_freq=clock_info.frequency(),
...   target_prop_tq=50,
...   prescaler=2)
BusParamsTq(tq=85, prop=25, phase1=44, phase2=15, sjw=13, prescaler=2)
```

For users that are not interested in specifying individual bit timing parameters, CANlib also provides a set of default parameter settings for the most common bus speeds through the *Bitrate* class. The predefined bitrate constants may be set directly in the call to *openChannel*:

```
>>> ch = canlib.openChannel(channel=0, bitrate=canlib.Bitrate.BITRATE_500K)
```

Table 1: Bit timing parameters for some of the most common bus speeds on a CAN device with an 80 MHz oscillator<sup>1</sup>

	tq	phase1	phase2	sjw	prop	prescaler	Sample point	Bitrate
<i>BITRATE_10K</i>	4	4	4	1	7	500	75%	10 kbit/s
<i>BITRATE_50K</i>	4	4	4	1	7	100	75%	50 kbit/s
<i>BITRATE_62K</i>	4	4	4	1	7	80	75%	62 kbit/s
<i>BITRATE_83K</i>	2	2	2	2	3	120	75%	83 kbit/s
<i>BITRATE_100K</i>	4	4	4	1	7	50	75%	100 kbit/s
<i>BITRATE_125K</i>	4	4	4	1	7	40	75%	125 kbit/s
<i>BITRATE_128K</i>	2	2	2	1	3	40	75%	250 kbit/s
<i>BITRATE_500K</i>	2	2	2	1	3	20	75%	500 kbit/s
<i>BITRATE_1M</i>	2	2	2	1	3	10	75%	1 Mbit/s

If uncertain how to calculate bit timing parameters, appropriate values can be acquired using the *Bit Timing Calculator*. Note that in classic CAN mode, only the nominal bus parameters are of concern when using the Bit Timing Calculator.

## Set CAN FD Bitrate

After opening a channel in CAN FD mode (see *Open as CAN FD*), bit timing parameters for both the arbitration and data phases need to be set. This is done by a call to *set\_bus\_params\_tq*, with two separate instances of type *BusParamsTq* as arguments.

**Example:** Set the arbitration phase bitrate to 500 kbit/s and the data phase bitrate to 1000 kbit/s, with sampling points at 80%.

```
>>> from canlib import canlib
>>> ch = canlib.openChannel(channel=0, flags=canlib.Open.CAN_FD)
>>> params_arbitration = canlib.busparams.BusParamsTq(
...   tq=80,
...   phase1=16,
...   phase2=16,
...   sjw=16,
...   prescaler=2,
...   prop=47
```

(continues on next page)

<sup>1</sup> See *Check Channel Capabilities* for information on clock frequency.

(continued from previous page)

```

... )
>>> params_data = canlib.busparams.BusParamsTq(
...     tq=40,
...     phase1=31,
...     phase2=8,
...     sjw=8,
...     prescaler=2,
...     prop=0
... )
>>> ch.set_bus_params_tq(params_arbitration, params_data)

```

For users that are not interested in specifying individual bit timing parameters, CANlib also provides a set of default parameter settings for the most common bus speeds through the *BitrateFD* class. The predefined bitrates may be set directly in the call to *openChannel*:

```

>>> ch = canlib.openChannel(
...     channel=0,
...     flags=canlib.Open.CAN_FD,
...     bitrate=canlib.BitrateFD.BITRATE_500K_80P,
...     data_bitrate=canlib.BitrateFD.BITRATE_1M_80P,
... )

```

For CAN FD bus speeds other than the predefined *BitrateFD*, bit timing parameters have to be specified manually.

Table 2: Available predefined bitrate constants with corresponding bit timing parameters for a CAN FD device with an 80 MHz oscillator Page 19, 1

	tq	phase1	phase2	sjw	prop	prescaler	Sample point	Bitrate
<a href="#">BITRATE_500K_80P</a>	40	8	8	8	23	4	80%	500 kbit/s
<a href="#">BITRATE_1M_80P</a>	40	8	8	8	23	2	80%	1 Mbit/s
<a href="#">BITRATE_2M_80P</a>	20	15	4	4	0	2	80%	2 Mbit/s
<a href="#">BITRATE_4M_80P</a>	10	7	2	2	0	2	80%	4 Mbit/s
<a href="#">BITRATE_8M_60P</a>	5	2	2	1	0	2	60%	8 Mbit/s

If uncertain how to calculate bit timing parameters, appropriate values can be acquired using the [Bit Timing Calculator](#).

## CAN Driver Modes

Use *setBusOutputControl* to set the bus driver mode. This is usually set to *NORMAL* to obtain the standard push-pull type of driver. Some controllers also support *SILENT* which makes the controller receive only, not transmit anything, not even ACK bits. This might be handy for e.g. when listening to a CAN bus without interfering.

```

>>> from canlib import canlib
>>> with canlib.openChannel(channel=1) as ch:
...     ch.setBusOutputControl(canlib.Driver.SILENT)
...     ...

```

*NORMAL* is set by default.



## Legacy Functions

The following functions are still supported by canlib.

### Set CAN Bitrate

`setBusParams` can be used to set the CAN bus parameters, including bitrate, the position of the sampling point etc, they are also described in most CAN controller data sheets. Depending on device and installed firmware, the requested parameters may be subject to scaling in order to accommodate device specific restrictions. As such, reading back bus parameters using `getBusParamsFd` can return bus parameter settings different than the ones supplied. Note however, that a successful call to `setBusParamsFd` will always result in the requested bit rate being set on the bus, along with bus parameters that for all intents and purposes are equivalent to the ones requested.

Set the speed to 125 kbit/s, each bit comprising 8 (= 1 + 4 + 3) quanta, the sampling point occurs at 5/8 of a bit; SJW = 1; one sampling point:

```
>>> ch.setBusParams(freq=125000, tseg1=4, tseg2=3, sjw=1, noSamp=1)
```

Set the speed to 111111 kbit/s, the sampling point to 75%, the SJW to 2 and the number of samples to 1:

```
>>> ch.setBusParams(freq=111111, tseg1=5, tseg2=2, sjw=2, noSamp=1)
```

For full bit timing control, use `set_bus_params_tq` instead.

### Set CAN FD Bitrate

After a channel has been opened in CAN FD mode, `setBusParams`, and `setBusParamsFd` can be used to set the arbitration and data phase bitrates respectively. Depending on device and installed firmware, the requested parameters may be subject to scaling in order to accommodate device specific restrictions. As such, reading back bus parameters using `getBusParamsFd` can return bus parameter settings different than the ones supplied. Note however, that a successful call to `setBusParamsFd` will always result in the requested bit rate being set on the bus, along with bus parameters that for all intents and purposes are equivalent to the ones requested.

Set the nominal bitrate to 500 kbit/s and the data phase bitrate to 1000 kbit/s, with sampling points at 80%.

```
>>> ch.setBusParams(freq=500000, tseg1=63, tseg2=16, sjw=16, noSamp=1);
>>> ch.setBusParamsFd(freq_brs=1000000, tseg1_brs=31, tseg2_brs=8, sjw_brs=8);
```

For full bit timing control, use `set_bus_params_tq` instead.

## 1.4.5 CAN Frames

### CAN Data Frames

The CAN Data Frame, represented by the `Frame` object, is the most common message type, which consists of the following major parts (a few details are omitted for the sake of brevity):

**CAN identifier:** `canlib.Frame.id` The CAN identifier, or Arbitration Field, determines the priority of the message when two or more nodes are contending for the bus. The CAN identifier contains for:

- CAN 2.0A, an 11-bit Identifier and one bit, the RTR bit, which is dominant for data frames.
- CAN 2.0B, a 29-bit Identifier, with the EXT bit set, (which also contains two recessive bits: SRR and IDE) and the RTR bit.

**Data field:** *canlib.Frame.data* The Data field contains zero to eight bytes of data.

**Data Length Code:** *canlib.Frame.dlc* The DLC field specifies the number of data bytes in the Data field.

**CRC Field:** The CRC Field contains a 15-bit checksum calculated on most parts of the message. This checksum is used for error detection.

**Acknowledgement Slot:** Any CAN controller that has been able to correctly receive the message sends an Acknowledgement bit at the end of each message. The transmitter checks for the presence of the Acknowledge bit and retransmits the message if no acknowledge was detected.

---

**Note:** It is worth noting that the presence of an Acknowledgement Bit on the bus does not mean that any of the intended addressees has received the message. The only thing we know is that one or more nodes on the bus has received it correctly. The Identifier in the Arbitration Field is not, despite of its name, necessarily identifying the contents of the message.

---

The *canlib.Frame.flags* attribute consists of message information flags, according to *MessageFlag*.

## CAN FD Data Frames

A standard CAN network is limited to 1 MBit/s, with a maximum payload of 8 bytes per frame. CAN FD increases the effective data-rate by allowing longer data fields - up to 64 bytes per frame - without changing the CAN physical layer. CAN FD also retains normal CAN bus arbitration, increasing the bit-rate by switching to a shorter bit time only at the end of the arbitration process and returning to a longer bit time at the CRC Delimiter, before the receivers send their acknowledge bits. A realistic bandwidth gain of 3 to 8 times what's possible in CAN will particularly benefit flashing applications.

## Error Frames

Nearly all hardware platforms support detection of Error Frames. If an Error Frame arrives, the flag *ERROR\_FRAME* is set in the *Frame*. The identifier is garbage if an Error Frame is received, but for LAPcan it happens to be 2048 plus the error code from the SJA1000.

Many platforms support transmission of Error Frames as well. To send Error Frames, set the *ERROR\_FRAME* flag in the *Frame* before sending using *write*.

Simply put, the Error Frame is a special message that violates the framing rules of a CAN message. It is transmitted when a node detects a fault and will cause all other nodes to detect a fault - so they will send Error Frames, too. The transmitter will then automatically try to retransmit the message. There is an elaborate scheme of error counters that ensures that a node can't destroy the bus traffic by repeatedly transmitting error frames.

The Error Frame consists of an Error Flag, which is 6 bits of the same value (thus violating the bit-stuffing rule) and an Error Delimiter, which is 8 recessive bits. The Error Delimiter provides some space in which the other nodes on the bus can send their Error Flags when they detect the first Error Flag.

## Remote Requests

You can send remote requests by passing the *RTR* flag to *write*. Received remote frames are reported by *read* et.al. using the same flag.

The Remote Frame is just like the Data Frame, with two important differences:

- It is explicitly marked as a Remote Frame (the RTR bit in the Arbitration Field is recessive)
- There is no Data Field.

The intended purpose of the Remote Frame is to solicit the transmission of the corresponding Data Frame. If, say, node A transmits a Remote Frame with the Arbitration Field set to 234, then node B, if properly initialized, might respond with a Data Frame with the Arbitration Field also set to 234.

Remote Frames can be used to implement a type of request-response type of bus traffic management. In practice, however, the Remote Frame is little used. It is also worth noting that the CAN standard does not prescribe the behaviour outlined here. Most CAN controllers can be programmed either to automatically respond to a Remote Frame, or to notify the local CPU instead.

There's one catch with the Remote Frame: the Data Length Code must be set to the length of the expected response message even though no data is sent. Otherwise the arbitration will not work.

Sometimes it is claimed that the node responding to the Remote Frame is starting its transmission as soon as the identifier is recognized, thereby "filling up" the empty Remote Frame. This is not the case.

## Overload Frames

Overload Frames aren't used nowadays. Certain old CAN controllers (Intel 82526) used them to delay frame processing in certain cases.

## Other frame features of interest

There are some other frame features of interest:

- You can send wakeup frames (used for Single-Wire CAN) if your hardware supports it, for example, a LAPcan plus a DRVcan S. Just set the *WAKEUP* flag.
- For "low-speed CAN" (1053/1054 type transceivers), the *NERR* flag is set if a frame is received in "fault-tolerant" mode.

## 1.4.6 Send and Receive

### Bus On / Bus Off

When the CAN controller is on bus, it is receiving messages and is sending acknowledge bits in response to all correctly received messages. A controller that is off bus is not taking part in the bus communication at all.

When you have a *Channel* object, use *busOn* to go on bus and *busOff* to go off bus.

If you have multiple *Channel* objects to the same controller, the controller will go off bus when the last of the *Channel* objects go off bus (i.e. all *Channel* objects must be off bus for the controller to be off bus). You can use *readStatus* and watch the flag *BUS\_OFF* to see if the controller has gone off bus.

You can set a channel to silent mode by using the *SILENT* mode if you want it to be on-bus without interfering with the traffic in any way, see *CAN Driver Modes*.

This example opens a channel, takes it on-bus, then takes it off-bus and closes it:

```
>>> from canlib import canlib
... with canlib.openChannel(channel=1) as ch:
...     ch.busOn()
...     ...
...     ch.busOff()
```

## Reading Messages

Incoming messages are placed in a queue in the driver. In most cases the hardware does message buffering as well. You can read the first message in the queue by calling `read`, which will raise the exception `CanNoMsg` if there was no message available.

The `flags` attribute of the `Frame` returned by `read` contains a combination of the `MessageFlag` flags, including `FDF`, `BRS`, and `ESI` if the CAN FD protocol is enabled, and error flags such as `OVERRUN` which provides you with more information about the message; for example, a frame with a 29-bit identifier will have the `EXT` bit set, and a remote frame will have the `RTR` bit set. Note that the flag argument is a combination of the `MessageFlag`, so more than one flag might be set.

See *CAN Frames* for more information.

Sometimes it is desirable to have a peek into the more remote parts of the queue. Is there, for example, any message waiting that has a certain identifier?

- If you want to read just a message with a specified identifier, and throw all others away, you can call `readSpecificSkip`. This routine will return the first message with the specified identifier, discarding any other message in front of the desired one.
- If you want to wait until a message arrives (or a timeout occurs) and then read it, call `read` with a timeout.
- If you want to wait until there is at least one message in the queue with a certain identifier, but you don't want to read it, call `readSyncSpecific`.

The following code fragment reads the next available CAN message, (using default bitrate 500 kbit/s):

```
>>> from canlib import canlib
... with canlib.openChannel(channel=0) as ch:
...     ch.busOn()
...     frame = ch.read(timeout=1000)
...     ch.busOff()
>>> frame
Frame(id=709, data=bytearray(b'\xb5R'), dlc=2, flags=<MessageFlag.STD: 2>, timestamp=3)
```

## Acceptance Filters

You can set filters to reduce the number of received messages. CANlib supports setting of the hardware filters on the CAN interface board. This is done with the `canAccept` function.

You set an acceptance code and an acceptance mask which together determine which CAN identifiers are accepted or rejected.

If you want to remove an acceptance filter, call `canAccept` with the mask set to `NULL_MASK`.

To set the mask to `0xF0` and the code to `0x60`:

```
>>> from canlib import canlib
>>> ch = canlib.openChannel(channel=0)
>>> ch.canAccept(0x0f0, canlib.AcceptFilterFlag.SET_MASK_STD)
>>> ch.canAccept(0x060, canlib.AcceptFilterFlag.SET_CODE_STD)
>>> ...
>>> ch.close()
```

This code snippet will cause all messages having a standard (11-bit) identifier with bit 7 - bit 4 in the identifier equal to 0110 (binary) will pass through. Other messages with standard identifiers will be rejected.

How acceptance filters can be used in a smaller project:

```
>>> from canlib import canlib
>>> ch = canlib.openChannel(channel=0)
>>> # The acceptance filter only have to be called once for each ch object
>>> ch.canAccept(0x0f0, canlib.AcceptFilterFlag.SET_MASK_STD)
>>> ch.canAccept(0x060, canlib.AcceptFilterFlag.SET_CODE_STD)
>>> ...
>>> # We can now run the rest of the program and the acceptance filter
>>> # will reject unwanted CAN messages.
>>> while(True):
>>>     frame = ch.read()
>>>     ...
>>> ...
```

## Code and Mask Format

Explanation of the code and mask format used by the `canAccept` function:

A binary 1 in a mask means “the corresponding bit in the code is relevant” A binary 0 in a mask means “the corresponding bit in the code is not relevant” A relevant binary 1 in a code means “the corresponding bit in the identifier must be 1” A relevant binary 0 in a code means “the corresponding bit in the identifier must be 0”

In other words, the message is accepted if  $((\text{code XOR id}) \text{ AND mask}) == 0$ .

## Sending Messages

You transmit messages by calling `write`. Outgoing CAN messages are buffered in a transmit queue and sent on a First-In First-Out basis. You can use `writeSync` to wait until the messages in the queue have been sent.

Sending a CAN message:

```
>>> from canlib import canlib, Frame
... with canlib.openChannel(channel=0) as ch:
...     ch.busOn()
...     frame = Frame(id_=234, data=[1,2])
...     ch.write(frame)
...     ch.busOff()
```

## Using Extended CAN (CAN 2.0B)

“Standard” CAN has 11-bit identifiers in the range 0 - 2047. “Extended” CAN, also called CAN 2.0B, has 29-bit identifiers. You specify which kind of identifiers you want to use in your call to `canWrite()`: if you set the `EXT` flag in the flag argument, the message will be transmitted with a 29-bit identifier. Conversely, received 29-bit-identifier messages have the `EXT` flag set.

The following code fragment sends a CAN message on an already open channel. The CAN message will have identifier 1234 (extended) and DLC = 8. The contents of the data bytes will be whatever the data array happens to contain:

```
>>> frame = Frame(id=1234, data=[1,2,3,4,5,6,7,8], flags=canlib.MessageFlag.EXT)
>>> frame
Frame(id=1234, data=bytearray(b'\x01\x02\x03\x04\x05\x06\x07\x08'), dlc=8, flags=
↳<MessageFlag.EXT: 4>, timestamp=None)
>>> ch.write(frame)
```

## Object Buffers

Object buffers are currently not supported in the Python wrapper.

## 1.4.7 Bus Errors

### Obtaining Bus Status Information

Use `read_error_counters` to read the error counters of the CAN controller. There are two such counters in a CAN controller (they are required by the protocol definition). Not all CAN controllers allow access to the error counters, so CANlib may provide you with an “educated guess” instead.

Use `readStatus` to obtain the bus status (error active, error passive, bus off; as defined by the CAN standard).

### Overruns

If the CAN interface or the driver runs out of buffer space, or if the bus load is so high that the CAN controller can't keep up with the traffic, an overload condition is flagged to the application.

The driver will set the `HW_OVERRUN` and/or `SW_OVERRUN` flags in the flag argument of `read` and its relatives. The flag(s) will be set in the first message read from the driver after the overrun or overload condition happened.

Not all hardware platforms can detect the difference between hardware overruns and software overruns, so your application should test for both conditions. You can use the symbol `OVERRUN` for this purpose.

### Error Frames

When a CAN controller detects an error, it transmits an error frame. This is a special CAN message that causes all other CAN controllers on the bus to notice that an error has occurred.

CANlib will report error frames to the application just like it reports any other CAN message, but the `ERROR_FRAME` flag will be set in the flags parameter when e.g. `read` returns.

When an error frame is received, its identifier, DLC and data bytes will be undefined. You should test if a message is an error frame before checking its identifier, DLC or data bytes.

In an healthy CAN system, error frames should rarely, if ever, occur. Error frames usually mean there is some type of serious problem in the system, such as a bad connector, a bad cable, bus termination missing or faulty, or another node transmitting at wrong bit rate, and so on.

## 1.4.8 Time Measurement

CAN messages are time stamped as they arrive. This time stamping is, depending on your hardware platform, done either by the CAN interface hardware or by CANlib.

In the former case, the accuracy is pretty good, in the order of 1 - 10 microseconds; when CANlib does the job, the accuracy is more like 100 microseconds to 10 milliseconds and you may experience a rather large jitter. This is because Windows is not a real-time operating system.

Use `Channel.readTimer` to read the current time, the return value is the current time using the clock of that channel.

### Accuracy

The accuracy of the time stamps depends on the hardware.

The members of the Kvaser Leaf family have an onboard CPU. The time stamp accuracy varies (check the hardware manual) but the high-end members have very precise time stamping. The accuracy can be as good as one microsecond depending on the hardware. If more than one Leaf is used, their clocks are automatically kept in sync by the Kvaser MagiSync™ technology.

Other CAN interfaces, like the Kvaser Leaf, LAPcan and USBcan II, have an on-board CPU and clock and provide very accurate time stamps for incoming CAN messages. The accuracy is typically 10-20 microseconds.

Certain interfaces, like the PCIcan (PCI) series of boards, don't have an on-board CPU so the driver relies on the clock in the PC to timestamp the incoming messages. As Windows is not a real-time operating system, this gives an accuracy which is in the order of one millisecond.

### Resolution

The resolution of the time stamps is, by default, 1 ms. It can be changed to a better resolution if desired.

Use `IOControl` attribute `timer_scale` to change the resolution of the time stamps, if desired. This will not affect the accuracy of the time stamps.

## 1.4.9 Using Threads

### Handles are thread-specific

CANlib supports programs with multiple threads as long as one important condition is met: A handle to a CAN circuit should be used in only one thread.

This means that you cannot share e.g. `canlib.Channel` objects between threads. Each thread has to open its own handle to the circuit.

Also note that you must call `busOn` and `busOff` once for each handle even if the handles are opened on the same physical channel.

## Local echo feature

If you are using the same channel via multiple handles, note that the default behaviour is that the different handles will “hear” each other just as if each handle referred to a channel of its own. If you open, say, channel 0 from thread A and thread B and then send a message from thread A, it will be “received” by thread B. This behaviour can be changed using *IOControl* and `local_txecho`.

## Init access

Init access means that the thread that owns the handle can set bit rate and CAN driver mode. Init access is the default. At most one thread can have init access to any given channel. If you try to set the bit rate or CAN driver mode for a handle to which you don’t have init access, the call will silently fail, unless you enable access error reporting by using *IOControl* and `report_access_errors`. Access error reporting is by default off.

## Using the same handle in different threads

In spite of what was said above, you can use a single handle in different threads, provided you create the appropriate mutual exclusion mechanisms yourself. Two threads should never call CANlib simultaneously unless they are using different handles.

## 1.4.10 I/O Pin Handling

### Initialize

Some Kvaser products feature I/O pins that can be used in real-time applications using a part of the API dedicated to I/O Pin Handling. This API is initialized by confirming the I/O pin configuration, see `kvIoConfirmConfig`. Before the configuration is confirmed the user can only retrieve information about the pins.

```
>>> from canlib import canlib, Device
... device = Device.find(serial=66666)
... channel = device.channel_number()
... ch = canlib.openChannel(channel)
... config = canlib.iopin.Configuration(ch)
... ch.get_io_pin(86).pin_type
<PinType.ANALOG: 2>
>>> for pin in config:
...     print(pin)
Pin 0: <PinType.DIGITAL: 1> <Direction.OUT: 8> bits=1 range=0.0-24.0 (<ModuleType.
↳DIGITAL: 1>)
Pin 1: <PinType.DIGITAL: 1> <Direction.OUT: 8> bits=1 range=0.0-24.0 (<ModuleType.
↳DIGITAL: 1>)
:
Pin 31: <PinType.DIGITAL: 1> <Direction.IN: 4> bits=1 range=0.0-24.0 HL_filter=5000 LH_
↳filter=5000 (<ModuleType.DIGITAL: 1>)
```

After the configuration has been confirmed the user may set or read any values of the I/O pins:

```
>>> config.confirm()

>>> ch.get_io_pin(0).value
0
```

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```
>>> ch.get_io_pin(0).value = 1
>>> ch.get_io_pin(0).value
1
```

## Pin Information

Pins are identified by their pin number, which is a number from zero up to, but not including, the value returned by *number\_of\_io\_pins*. Using the pin number, the specific properties of any pin is retrieved and set using *canlib.iopin.IoPin*.

## I/O pin types

There are currently three types of pins that is supported by the API dedicated to I/O Pin Handling. These include analog, digital and relay pins. To learn what pin type a given pin is, use *canlib.iopin.IoPin.pin\_type*. See *PinType* to see all supported types.

## Analog Pins

The analog pins are represented by multiple bits, the number of bits can be retrieved by calling `~.canlib.iopin.IoPin.number_of_bits``. The value of an analog pin is within in the interval given by *range\_min* and *range\_max*. The analog input pin has two configurable properties, namely the low pass filter order and the hysteresis. See *lp\_filter\_order* and *hysteresis*. Pins are read and set using *value*. When reading an output, the latest value set is retrieved.

## Digital Pins

The digital pins have two configurable properties, namely the low-to-high and the high-to-low filter time. See *high\_low\_filter* and *low\_high\_filter*. Pins are read and set using *value*. When reading an output, the latest value set is retrieved.

## Relay Pins

The relay pins have no configurable properties. All of these pins are considered as outputs. Pins are set and read using *value*.

## 1.5 Examples

This section contains a number of examples or how-tos solving common problems. They are all scripts ready to be run, using python's *argparse* to accept arguments.

## 1.5.1 Convert a .kme50 file to plain ASCII

```

"""convert_kme_asc.py -- Convert a .kme50 logfile into plain ASCII

This example script uses canlib.kvlclib to convert a logfile from .kme50 format
into plain ASCII.

"""
import argparse
from pathlib import Path

from canlib import kvlclib

def try_set_property(cnv, property, value=None):
    # Check if the format supports the given property
    if cnv.format.isPropertySupported(property):
        # If a value is specified, set the property to this value
        if value is not None:
            cnv.setProperty(property, value)

        # Get the property's default value
        default = cnv.format.getPropertyDefault(property)
        print(f' {property} is supported (Default: {default})')

        # Get the property's current value
        value = cnv.getProperty(property)
        print(f'    Current value: {value}')
    else:
        print(f' {property} is not supported')

def convert_events(cnv):
    # Get estimated number of remaining events in the input file. This
    # can be useful for displaying progress during conversion.
    total = cnv.eventCount()
    print(f"Converting about {total} events...")
    while True:
        try:
            # Convert events from input file one by one until EOF
            # is reached
            cnv.convertEvent()
            if cnv.isOutputFilenameNew():
                print(f"New output filename: '{cnv.getOutputFilename()}'")
                print(f"About {cnv.eventCount()} events left...")
        except kvlclib.KvlcEndOfFile:
            if cnv.isOverrunActive():
                print("NOTE! The extracted data contained overrun.")
                cnv.resetOverrunActive()
            if cnv.isDataTruncated():
                print("NOTE! The extracted data was truncated.")
                cnv.resetStatusTruncated()
        break

```

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```
if __name__ == '__main__':
    parser = argparse.ArgumentParser(description="Convert a .kme50 logfile into plain_
↳ASCII.")
    parser.add_argument(
        'filename', metavar='LOGFILE.KME50', help="The filename of the .kme50 logfile.")
    )
    args = parser.parse_args()
    in_file = Path(args.filename)

    # set up formats
    out_fmt = kvlclib.WriterFormat(kvlclib.FileFormat.PLAIN_ASC)
    in_fmt = kvlclib.ReaderFormat(kvlclib.FileFormat.KME50)

    # set resulting output file name taking advantage of the extension
    # defined in the format.
    out_file = in_file.with_suffix('.') + out_fmt.extension)
    print(f"Output filename is '{out_file}'")

    # create converter
    cnv = kvlclib.Converter(out_file, out_fmt)

    # Set input file and format
    cnv.setInputFile(in_file, kvlclib.FileFormat.KME50)

    # split output files into max 100 MB files
    # The name of the resulting files will now end in '-partX.txt',
    # thus the first file will be named logfile-part0.txt, assuming we use
    # logfile.kme50 as input file name.
    try_set_property(cnv, kvlclib.Property.SIZE_LIMIT, 100)

    # allow output file to overwrite existing files
    try_set_property(cnv, kvlclib.Property.OVERWRITE, 1)

    # we are only interested in the first channel
    cnv.setProperty(kvlclib.Property.CHANNEL_MASK, 1)

    # add nice header to the output file
    try_set_property(cnv, kvlclib.Property.WRITE_HEADER, 1)

    # we are converting CAN traffic with max 8 bytes, so we can minimize
    # the width of the data output to 8 bytes
    try_set_property(cnv, kvlclib.Property.LIMIT_DATA_BYTES, 8)

    convert_events(cnv)

    # force flush result to disk
    cnv.flush()
```

## Description

We have created a wrapper function `try_set_property` that will examine the property we are trying to set, and ignore the setting if the current format used does not support the property. While converting events in the `convert_events` function, we also inform the user if any overruns or data truncation was detected.

## Sample Output

```
C:\example>python convert_kme_asc.py gensig.kme50
Output filename is 'C:\example\gensig.txt'
  Property.SIZE_LIMIT is supported (Default: 0)
    Current value: 100
  Property.OVERWRITE is supported (Default: 0)
    Current value: 1
  Property.WRITE_HEADER is supported (Default: 0)
    Current value: 1
  Property.LIMIT_DATA_BYTES is supported (Default: 64)
    Current value: 8
Converting about 310 events...
New output filename: 'C:\example\gensig-part0.txt'
About 309 events left...
```

## 1.5.2 Create a Database

```
"""create_db.py -- Creating a .dbc database from scratch

This script will use canlib.kvadbllib to create a new database file filled with
arbitrary data.

"""

import argparse
from collections import namedtuple

from canlib import kvadbllib

Message = namedtuple('Message', 'name id dlc signals')
Signal = namedtuple('Signal', 'name size scaling limits unit')
EnumSignal = namedtuple('EnumSignal', 'name size scaling limits unit enums')

_messages = [
    Message(
        name='EngineData',
        id=100,
        dlc=8,
        signals=[
            Signal(
                name='PetrolLevel',
                size=(24, 8),
                scaling=(1, 0),
```

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```

        limits=(0, 255),
        unit="l",
    ),
    Signal(
        name='EngPower',
        size=(48, 16),
        scaling=(0.01, 0),
        limits=(0, 150),
        unit="kW",
    ),
    Signal(
        name='EngForce',
        size=(32, 16),
        scaling=(1, 0),
        limits=(0, 0),
        unit="N",
    ),
    EnumSignal(
        name='IdleRunning',
        size=(23, 1),
        scaling=(1, 0),
        limits=(0, 0),
        unit="",
        enums={'Running': 0, 'Idle': 1},
    ),
    Signal(
        name='EngTemp',
        size=(16, 7),
        scaling=(2, -50),
        limits=(-50, 150),
        unit="degC",
    ),
    Signal(
        name='EngSpeed',
        size=(0, 16),
        scaling=(1, 0),
        limits=(0, 8000),
        unit="rpm",
    ),
],
),
Message(
    name='GearBoxInfo',
    id=1020,
    dlc=1,
    signals=[
        Signal(
            name='EcoMode',
            size=(6, 2),
            scaling=(1, 0),
            limits=(0, 1),
            unit="",

```

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```

    ),
    EnumSignal(
        name='ShiftRequest',
        size=(3, 1),
        scaling=(1, 0),
        limits=(0, 0),
        unit="",
        enums={'Shift_Request_On': 1, 'Shift_Request_Off': 0},
    ),
    EnumSignal(
        name='Gear',
        size=(0, 3),
        scaling=(1, 0),
        limits=(0, 5),
        unit="",
        enums={
            'Idle': 0,
            'Gear_1': 1,
            'Gear_2': 2,
            'Gear_3': 3,
            'Gear_4': 4,
            'Gear_5': 5,
        },
    ),
],
),
]

```

```

def create_database(name, filename):
    db = kvadblib.Dbc(name=name)

    for _msg in _messages:
        message = db.new_message(
            name=_msg.name,
            id=_msg.id,
            dlc=_msg.dlc,
        )

        for _sig in _msg.signals:
            if isinstance(_sig, EnumSignal):
                _type = kvadblib.SignalType.ENUM_UNSIGNED
                _enums = _sig.enums
            else:
                _type = kvadblib.SignalType.UNSIGNED
                _enums = {}
            message.new_signal(
                name=_sig.name,
                type=_type,
                byte_order=kvadblib.SignalByteOrder.INTEL,
                mode=kvadblib.SignalMultiplexMode.MUX_INDEPENDENT,
                size=kvadblib.ValueSize(*_sig.size),
            )

```

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```

        scaling=kvadblib.ValueScaling(*_sig.scaling),
        limits=kvadblib.ValueLimits(*_sig.limits),
        unit=_sig.unit,
        enums=_enums,
    )

    db.write_file(filename)
    db.close()

if __name__ == '__main__':
    parser = argparse.ArgumentParser(description="Create a database from scratch.")
    parser.add_argument('filename', help=("The filename to save the database to.))
    parser.add_argument(
        '-n',
        '--name',
        default='Engine example',
        help=("The name of the database (not the filename, the internal name)."),
    )
    args = parser.parse_args()

    create_database(args.name, args.filename)

```

## Description

While the name of the created database and the filename it is saved as is passed as arguments to `create_database`, the contents of the database is defined in the variable `_messages`. This is a list of `Message` namedtuples that describes all the messages to be put in the database:

- Their name, id, and dlc fields are passed to `new_message`.
- Their signals attribute is a list of `Signal` or `EnumSignal` namedtuples. All their fields will be passed to `new_signal`.

## Sample Output

With the `_messages` variable as shown above, the following `.dbc` file is created:

```

VERSION "HIPBNYYYYYYYYYYYYYYYYYYYYYYYYYYYYYYYYYYYY/4/%%%/4/'%**4YYY///"

NS_ :
  NS_DESC_
  CM_
  BA_DEF_
  BA_
  VAL_
  CAT_DEF_
  CAT_
  FILTER
  BA_DEF_DEF_

```

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```

EV_DATA_
ENVVAR_DATA_
SGTYPE_
SGTYPE_VAL_
BA_DEF_SGTYPE_
BA_SGTYPE_
SIG_TYPE_REF_
VAL_TABLE_
SIG_GROUP_
SIG_VALTYPE_
SIGTYPE_VALTYPE_
BO_TX_BU_
BA_DEF_REL_
BA_REL_
BA_DEF_DEF_REL_
BU_SG_REL_
BU_EV_REL_
BU_BO_REL_
SG_MUL_VAL_

```

BS\_:

BU\_:

```

BO_ 100 EngineData: 8 Vector__XXX
SG_ PetrolLevel : 24|8@1+ (1,0) [0|255] "l" Vector__XXX
SG_ EngPower : 48|16@1+ (0.01,0) [0|150] "kW" Vector__XXX
SG_ EngForce : 32|16@1+ (1,0) [0|0] "N" Vector__XXX
SG_ IdleRunning : 23|1@1+ (1,0) [0|0] "" Vector__XXX
SG_ EngTemp : 16|7@1+ (2,-50) [-50|150] "°C" Vector__XXX
SG_ EngSpeed : 0|16@1+ (1,0) [0|8000] "rpm" Vector__XXX

```

```

BO_ 1020 GearBoxInfo: 1 Vector__XXX
SG_ EcoMode : 6|2@1+ (1,0) [0|1] "" Vector__XXX
SG_ ShiftRequest : 3|1@1+ (1,0) [0|0] "" Vector__XXX
SG_ Gear : 0|3@1+ (1,0) [0|5] "" Vector__XXX

```

```

BA_DEF_ "BusType" STRING ;
BA_DEF_DEF_ "BusType" "";
BA_ "BusType" "CAN";
VAL_ 100 IdleRunning 0 "Running" 1 "Idle" ;
VAL_ 1020 ShiftRequest 1 "Shift_Request_On" 0 "Shift_Request_Off" ;
VAL_ 1020 Gear 0 "Idle" 2 "Gear_2" 1 "Gear_1" 5 "Gear_5" 3 "Gear_3" 4 "Gear_4" ;

```



### 1.5.3 Monitor a Channel Using a Database

"""dbmonitor.py -- Read CAN messages using a database

*This script will use canlib.canlib and canlib.kvadbllib to monitor a CAN channel, and look up all messages received in a database before printing them.*

*It requires a CANlib channel with a connected device capable of receiving CAN messages, some source of CAN messages, and the same database that the source is using to generate the messages.*

*In this example the channel is opened with flag canOPEN\_ACCEPT\_LARGE\_DLC (optional). This enables a DLC larger than 8 bytes (up to 15 for classic CAN). If canOPEN\_ACCEPT\_LARGE\_DLC is excluded, generated frames with DLC > 8, will attain a DLC of 8 on the receiving end, which may compromise the DLC equivalence check.*

*The source of the messages may be e.g. the pinger.py example script.*

```

"""
import argparse

from canlib import canlib, kvadbllib

bitrates = {
    '1M': canlib.Bitrate.BITRATE_1M,
    '500K': canlib.Bitrate.BITRATE_500K,
    '250K': canlib.Bitrate.BITRATE_250K,
    '125K': canlib.Bitrate.BITRATE_125K,
    '100K': canlib.Bitrate.BITRATE_100K,
    '62K': canlib.Bitrate.BITRATE_62K,
    '50K': canlib.Bitrate.BITRATE_50K,
    '83K': canlib.Bitrate.BITRATE_83K,
    '10K': canlib.Bitrate.BITRATE_10K,
}

def printframe(db, frame):
    try:
        bmsg = db.interpret(frame)
    except kvadbllib.KvdNoMessage:
        print(f"<<< No message found for frame with id {frame.id} >>>")
        return

    if not bmsg._message.dlc == bmsg._frame.dlc:
        print(
            "<<< Could not interpret message because DLC does not match for"
            f" frame with id {frame.id} >>>"
        )
        print(f"\t- DLC (database): {bmsg._message.dlc}")
        print(f"\t- DLC (received frame): {bmsg._frame.dlc}")
        return

```

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```

msg = bmsg._message

print('', msg.name)

if msg.comment:
    print('', f'"{msg.comment}"')

for bsig in bmsg:
    print('', bsig.name + ':', bsig.value, bsig.unit)

print('')

def monitor_channel(channel_number, db_name, bitrate, ticktime):
    db = kvadblib.Dbc(filename=db_name)

    ch = canlib.openChannel(channel_number, canlib.canOPEN_ACCEPT_LARGE_DLC,
↪bitrate=bitrate)
    ch.setBusOutputControl(canlib.canDRIVER_NORMAL)
    ch.busOn()

    timeout = 0.5
    tick_countup = 0
    if ticktime <= 0:
        ticktime = None
    elif ticktime < timeout:
        timeout = ticktime

    print("Listening...")
    while True:
        try:
            frame = ch.read(timeout=int(timeout * 1000))
            printframe(db, frame)
        except canlib.CanNoMsg:
            if ticktime is not None:
                tick_countup += timeout
                while tick_countup > ticktime:
                    print("tick")
                    tick_countup -= ticktime
            except KeyboardInterrupt:
                print("Stop.")
                break

if __name__ == '__main__':
    parser = argparse.ArgumentParser(
        description="Listen on a CAN channel and print all signals received, as
↪specified by a database."
    )
    parser.add_argument(
        'channel', type=int, default=1, nargs='?', help=("The channel to listen on.")
    )

```

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```

parser.add_argument(
    '--db',
    default="engine_example.dbc",
    help=("The database file to look up messages and signals in."),
)
parser.add_argument(
    '--bitrate', '-b', default='500k', help=("Bitrate, one of " + ', '.join(bitrates.
↪keys()))
)
parser.add_argument(
    '--ticktime',
    '-t',
    type=float,
    default=0,
    help=("If greater than zero, display 'tick' every this many seconds"),
)
args = parser.parse_args()

monitor_channel(args.channel, args.db, bitrates[args.bitrate.upper()], args.ticktime)

```

## Description

Any CAN messages received on the specified channel will be looked up in the database using *interpret*, which allows the script to print the “phys” value of each signal instead of just printing the raw data (as *Monitor a Channel* does). The script also prints the message’s name and comment (if available), as well as the signals name and unit.

## Sample Output

```

EngineData
PetrolLevel: 0.0 l
EngPower: 12.0 kW
EngForce: 0.0 N
IdleRunning: 0.0
EngTemp: -30.0 °C
EngSpeed: 7735.0 rpm

GearBoxInfo
EcoMode: 0.0
ShiftRequest: 0.0
Gear: 0.0

EngineData
PetrolLevel: 0.0 l
EngPower: 28.0 kW
EngForce: 0.0 N
IdleRunning: 0.0
EngTemp: -30.0 °C
EngSpeed: 3467.0 rpm

GearBoxInfo

```

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EcoMode: 1.0  
ShiftRequest: 0.0  
Gear: 0.0

EngineData  
PetrolLevel: 0.0 l  
EngPower: 0.0 kW  
EngForce: 0.0 N  
IdleRunning: 0.0  
EngTemp: -50.0 °C  
EngSpeed: 1639.0 rpm

GearBoxInfo  
EcoMode: 1.0  
ShiftRequest: 0.0  
Gear: 1.0

EngineData  
PetrolLevel: 60.0 l  
EngPower: 0.0 kW  
EngForce: 0.0 N  
IdleRunning: 0.0  
EngTemp: 142.0 °C  
EngSpeed: 0.0 rpm

GearBoxInfo  
EcoMode: 0.0  
ShiftRequest: 0.0  
Gear: 0.0

EngineData  
PetrolLevel: 172.0 l  
EngPower: 51.0 kW  
EngForce: 0.0 N  
IdleRunning: 0.0  
EngTemp: -50.0 °C  
EngSpeed: 0.0 rpm

GearBoxInfo  
EcoMode: 0.0  
ShiftRequest: 0.0  
Gear: 0.0

## 1.5.4 Examine the Contents of a Database

```

# examine_db.py
"""
This script uses canlib.kvadbllib to parse a database and print its contents.
"""
import argparse
import sys

from canlib import kvadbllib

INDENT = ' ' * 4

def print_db(db):
    print('DATABASE')
    print(db.name)
    for line in db_lines(db):
        print(INDENT + line)

def adef_lines(adeft):
    yield 'type: ' + type(adeft).__name__
    yield 'definition: ' + str(adeft.definition)
    yield 'owner: ' + str(adeft.owner)

def attr_lines(attrib):
    yield str(attrib.name) + ' = ' + str(attrib.value)

def db_lines(db):
    yield 'flags: ' + str(db.flags)
    yield 'protocol: ' + str(db.protocol)
    yield ''

    yield 'ATTRIBUTE DEFINITIONS'
    for adef in db.attribute_definitions():
        yield str(adeft.name)
        for line in adef_lines(adeft):
            yield INDENT + line
    yield ''

    yield 'MESSAGES'
    for message in db:
        yield str(message.name)
        for line in msg_lines(message):
            yield INDENT + line
    yield ''

```

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```
def enum_lines(enums):
    for name, val in enums.items():
        yield str(name) + ' = ' + str(val)

def msg_lines(message):
    yield 'id: ' + str(message.id)
    yield 'flags: ' + str(message.flags)
    yield 'dlc: ' + str(message.dlc)
    yield 'comment: ' + str(message.comment)
    yield ''

    yield 'ATTRIBUTES'
    for attr in message.attributes():
        for line in attr_lines(attr):
            yield line
    yield ''

    yield 'SIGNALS'
    for signal in message:
        yield str(signal.name)
        for line in sig_lines(signal):
            yield INDENT + line
    yield ''

def sig_lines(signal):
    for name in ('type', 'byte_order', 'mode', 'size', 'scaling', 'limits', 'unit',
↳ 'comment'):
        yield name + ': ' + str(getattr(signal, name))
    yield ''

    try:
        enums = signal.enums
    except AttributeError:
        pass
    else:
        yield 'ENUMERATIONS'
        for line in enum_lines(enums):
            yield line
        yield ''

    yield 'ATTRIBUTES'
    for attr in signal.attributes():
        for line in attr_lines(attr):
            yield line
    yield ''

def examine_database(db_name):
    with kvadbllib.Dbc(filename=db_name) as db:
        print_db(db)
```

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```

if __name__ == '__main__':
    parser = argparse.ArgumentParser(description=sys.modules[__name__].__doc__)
    parser.add_argument(
        'db', type=str, metavar='<database.dbc>', help='The dbc database file to examine.
    ↪')
    args = parser.parse_args()
    examine_database(args.db)

```

## Description

The script is structured into several generator functions that take a kvadblib object and yield lines of information about it. This allows one function to add indentation to any other functions it uses.

Generally each function first yields information in the following order:

1. Any information about the object itself (e.g. `db.flags` and `db.protocol`)
2. An empty string
3. For each type of sub-object (e.g. attribute definitions):
  1. A heading (e.g. 'ATTRIBUTE\_DEFINITIONS')
  2. For each object of that type (e.g. iterating through `attribute_definitions`):
    1. The objects name
    2. All lines from the `*_lines` function for the object type (e.g. `adef_lines`), with added indentation
  3. An empty string

## Sample Output

Running this script on the database created by *Create a Database* gives the following:

```

DATABASE
engine_example
  flags: 0
  protocol: ProtocolType.CAN

ATTRIBUTE DEFINITIONS
BusType
  type: StringDefinition
  definition: DefaultDefinition(default='')
  owner: AttributeOwner.DB

MESSAGES
EngineData
  id: 100
  flags: MessageFlag.0
  dlc: 8

```

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```
comment:

ATTRIBUTES

SIGNALS
PetrolLevel
  type: SignalType.UNSIGNED
  byte_order: SignalByteOrder.INTEL
  mode: -1
  size: ValueSize(startbit=24, length=8)
  scaling: ValueScaling(factor=1.0, offset=0.0)
  limits: ValueLimits(min=0.0, max=255.0)
  unit: l
  comment:

  ATTRIBUTES

EngPower
  type: SignalType.UNSIGNED
  byte_order: SignalByteOrder.INTEL
  mode: -1
  size: ValueSize(startbit=48, length=16)
  scaling: ValueScaling(factor=0.01, offset=0.0)
  limits: ValueLimits(min=0.0, max=150.0)
  unit: kW
  comment:

  ATTRIBUTES

EngForce
  type: SignalType.UNSIGNED
  byte_order: SignalByteOrder.INTEL
  mode: -1
  size: ValueSize(startbit=32, length=16)
  scaling: ValueScaling(factor=1.0, offset=0.0)
  limits: ValueLimits(min=0.0, max=0.0)
  unit: N
  comment:

  ATTRIBUTES

IdleRunning
  type: SignalType.UNSIGNED
  byte_order: SignalByteOrder.INTEL
  mode: 0
  size: ValueSize(startbit=23, length=1)
  scaling: ValueScaling(factor=1.0, offset=0.0)
  limits: ValueLimits(min=0.0, max=0.0)
  unit:
  comment:

ENUMERATIONS
```

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```
Running = 0
Idle = 1
```

```
ATTRIBUTES
```

```
EngTemp
```

```
type: SignalType.UNSIGNED
byte_order: SignalByteOrder.INTEL
mode: -1
size: ValueSize(startbit=16, length=7)
scaling: ValueScaling(factor=2.0, offset=-50.0)
limits: ValueLimits(min=-50.0, max=150.0)
unit: °C
comment:
```

```
ATTRIBUTES
```

```
EngSpeed
```

```
type: SignalType.UNSIGNED
byte_order: SignalByteOrder.INTEL
mode: -1
size: ValueSize(startbit=0, length=16)
scaling: ValueScaling(factor=1.0, offset=0.0)
limits: ValueLimits(min=0.0, max=8000.0)
unit: rpm
comment:
```

```
ATTRIBUTES
```

```
GearBoxInfo
```

```
id: 1020
flags: MessageFlag.0
dlc: 1
comment:
```

```
ATTRIBUTES
```

```
SIGNALS
```

```
EcoMode
```

```
type: SignalType.UNSIGNED
byte_order: SignalByteOrder.INTEL
mode: -1
size: ValueSize(startbit=6, length=2)
scaling: ValueScaling(factor=1.0, offset=0.0)
limits: ValueLimits(min=0.0, max=1.0)
unit:
comment:
```

```
ATTRIBUTES
```

```
ShiftRequest
```

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```

type: SignalType.UNSIGNED
byte_order: SignalByteOrder.INTEL
mode: 0
size: ValueSize(startbit=3, length=1)
scaling: ValueScaling(factor=1.0, offset=0.0)
limits: ValueLimits(min=0.0, max=0.0)
unit:
comment:

ENUMERATIONS
Shift_Request_On = 1
Shift_Request_Off = 0

ATTRIBUTES

Gear
type: SignalType.UNSIGNED
byte_order: SignalByteOrder.INTEL
mode: 0
size: ValueSize(startbit=0, length=3)
scaling: ValueScaling(factor=1.0, offset=0.0)
limits: ValueLimits(min=0.0, max=5.0)
unit:
comment:

ENUMERATIONS
Gear_5 = 5
Gear_1 = 1
Gear_3 = 3
Idle = 0
Gear_4 = 4
Gear_2 = 2

ATTRIBUTES

```

## 1.5.5 Print Information About All Channels

```

"""list_channels.py -- List all CANlib channel

This script uses canlib.canlib to list all CANlib channels and information
about the device that is using them.

"""

import argparse

from canlib import canlib

def print_channels():
    for ch in range(canlib.getNumberOfChannels()):


```

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```

chdata = canlib.ChannelData(ch)
print(
    "{ch}. {name} ({ean} / {serial})".format(
        ch=ch,
        name=chdata.channel_name,
        ean=chdata.card_upc_no,
        serial=chdata.card_serial_no,
    )
)

if __name__ == '__main__':
    parser = argparse.ArgumentParser(
        description="List all CANlib channels and information about them."
    )
    args = parser.parse_args()

    print_channels()

```

### Sample Output

```

0. Kvaser Memorator Pro 2xHS v2 (channel 0) (73-30130-00819-9 / 10626)
1. Kvaser Memorator Pro 2xHS v2 (channel 1) (73-30130-00819-9 / 10626)

```

## 1.5.6 Monitor a Channel

```

"""monitor.py -- Print all data received on a CAN channel

This script uses canlib.canlib to listen on a channel and print all data
received.

It requires a CANlib channel with a connected device capable of receiving CAN
messages and some source of CAN messages.

The source of the messages may be e.g. the pinger.py example script.

Also see the dbmonitor.py example script for how to look up the messages
received in a database.

"""
import argparse
import shutil

from canlib import canlib

bitrates = {
    '1M': canlib.Bitrate.BITRATE_1M,
    '500K': canlib.Bitrate.BITRATE_500K,
    '250K': canlib.Bitrate.BITRATE_250K,

```

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```
'125K': canlib.Bitrate.BITRATE_125K,
'100K': canlib.Bitrate.BITRATE_100K,
'62K': canlib.Bitrate.BITRATE_62K,
'50K': canlib.Bitrate.BITRATE_50K,
'83K': canlib.Bitrate.BITRATE_83K,
'10K': canlib.Bitrate.BITRATE_10K,
}

def printframe(frame, width):
    form = '^' + str(width - 1)
    print(format(" Frame received ", form))
    print("id:", frame.id)
    print("data:", bytes(frame.data))
    print("dlc:", frame.dlc)
    print("flags:", frame.flags)
    print("timestamp:", frame.timestamp)

def monitor_channel(channel_number, bitrate, ticktime):
    ch = canlib.openChannel(channel_number, bitrate=bitrate)
    ch.setBusOutputControl(canlib.canDRIVER_NORMAL)
    ch.busOn()

    width, height = shutil.get_terminal_size((80, 20))

    timeout = 0.5
    tick_countup = 0
    if ticktime <= 0:
        ticktime = None
    elif ticktime < timeout:
        timeout = ticktime

    print("Listening...")
    while True:
        try:
            frame = ch.read(timeout=int(timeout * 1000))
            printframe(frame, width)
        except canlib.CanNoMsg:
            if ticktime is not None:
                tick_countup += timeout
                while tick_countup > ticktime:
                    print("tick")
                    tick_countup -= ticktime
        except KeyboardInterrupt:
            print("Stop.")
            break

    ch.busOff()
    ch.close()
```

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```

if __name__ == '__main__':
    parser = argparse.ArgumentParser(
        description="Listen on a CAN channel and print all frames received."
    )
    parser.add_argument('channel', type=int, default=1, nargs='?')
    parser.add_argument(
        '--bitrate', '-b', default='500k', help=("Bitrate, one of " + ', '.join(bitrates.
↪keys()))
    )
    parser.add_argument(
        '--ticktime',
        '-t',
        type=float,
        default=0,
        help=("If greater than zero, display 'tick' every this many seconds"),
    )
    parser.add_argument
    args = parser.parse_args()

    monitor_channel(args.channel, bitrates[args.bitrate.upper()], args.ticktime)

```

## Description

Any CAN frames received on the specified channel will be printed. Note that the signals contained in the frame is not be extracted, only the raw data is printed. To extract the signals, see *Monitor a Channel Using a Database*.

## Sample Output

```

Listening...
Frame received
id: 1020
data: b'\x00'
flags: MessageFlag.STD
timestamp: 939214
Frame received
id: 100
data: b'\xd1\x06\x00\x19\x00\x00\x18\x15'
flags: MessageFlag.STD
timestamp: 939215
Frame received
id: 1020
data: b'\x01'
flags: MessageFlag.STD
timestamp: 939417
Frame received
id: 100
data: b'\x00\x00\x00\x19\x00\x00\xc82'
flags: MessageFlag.STD
timestamp: 939418
Frame received

```

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```

id: 1020
data: b'\x00'
flags: MessageFlag.STD
timestamp: 939620
  Frame received
id: 100
data: b'\x00\x00\x00\x00\x00\x00\x903'
flags: MessageFlag.STD
timestamp: 939621
  Frame received
id: 1020
data: b'@'
flags: MessageFlag.STD
timestamp: 939823
  Frame received
id: 100
data: b')\x03\x17\xf5\x00\x00\x00\x00'
flags: MessageFlag.STD
timestamp: 939824
  Frame received
id: 1020
data: b'\x02'
flags: MessageFlag.STD
timestamp: 940026
  Frame received
id: 100
data: b'\x1b\xeC\x00\x00\x00\x00'
flags: MessageFlag.STD
timestamp: 940027

```

## 1.5.7 Send Random Messages on a Channel

```

"""pinger.py -- Send random CAN messages based on a database

```

*This script uses canlib.canlib and canlib.kvadbllib to send random messages from a database with random data.*

*It requires a CANlib channel a connected device capable of sending CAN messages, something that receives those messages, and a database to inspect for the messages to send.*

*Messages can be received and printed by e.g. the dbmonitor.py example script.*

```

"""
import argparse
import random
import time

from canlib import canlib, kvadbllib

```

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```

bitrates = {
    '1M': canlib.Bitrate.BITRATE_1M,
    '500K': canlib.Bitrate.BITRATE_500K,
    '250K': canlib.Bitrate.BITRATE_250K,
    '125K': canlib.Bitrate.BITRATE_125K,
    '100K': canlib.Bitrate.BITRATE_100K,
    '62K': canlib.Bitrate.BITRATE_62K,
    '50K': canlib.Bitrate.BITRATE_50K,
    '83K': canlib.Bitrate.BITRATE_83K,
    '10K': canlib.Bitrate.BITRATE_10K,
}

def set_random_framebox_signal(db, framebox, signals):
    sig = random.choice(signals)
    value = get_random_value(db, sig)
    framebox.signal(sig.name).phys = value

def get_random_value(db, sig):
    limits = sig.limits
    value = random.uniform(limits.min, limits.max)

    # round value depending on type...
    if sig.type is kvadblib.SignalType.UNSIGNED or sig.type is kvadblib.SignalType.
↳ SIGNED:
        # ...remove decimals if the signal was of type unsigned
        value = int(round(value))
    else:
        # ...otherwise, round to get only one decimal
        value = round(value, 1)

    return value

def ping_loop(channel_number, db_name, num_messages, quantity, interval, bitrate,
↳ seed=0):
    db = kvadblib.Dbc(filename=db_name)

    ch = canlib.openChannel(channel_number, bitrate=bitrate)
    ch.setBusOutputControl(canlib.canDRIVER_NORMAL)
    ch.busOn()

    random.seed(seed)

    if num_messages == -1:
        used_messages = list(db)
    else:
        used_messages = random.sample(list(db), num_messages)

    print()
    print("Randomly selecting signals from the following messages:")

```

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```

print(used_messages)
print("Seed used was " + repr(seed))
print()

while True:
    # Create an empty framebox each time, ignoring previously set signal
    # values.
    framebox = kvadblib.FrameBox(db)

    # Add all messages to the framebox, as we may use send any signal from
    # any of them.
    for msg in db:
        framebox.add_message(msg.name)

    # Make a list of all signals (which framebox has found in all messages
    # we gave it), so that set_random_framebox_signal() can pick a random
    # one.
    signals = [bsig.signal for bsig in framebox.signals()]

    # Set some random signals to random values
    for i in range(quantity):
        set_random_framebox_signal(db, framebox, signals)

    # Send all messages/frames
    for frame in framebox.frames():
        print('Sending frame', frame)
        ch.writeWait(frame, timeout=5000)

    time.sleep(interval)

if __name__ == '__main__':
    parser = argparse.ArgumentParser(description="Send random CAN message based on a
↳database.")
    parser.add_argument(
        'channel', type=int, default=0, nargs='?', help=("The channel to send messages.
↳on.")
    )
    parser.add_argument(
        '--bitrate', '-b', default='500k', help=("Bitrate, one of " + ', '.join(bitrates.
↳keys()))
    )
    parser.add_argument(
        '--db', default="engine_example.dbc", help=("The database file to base messages.
↳on.")
    )
    parser.add_argument(
        '-Q', '--quantity', type=int, default=5, help=("The number of signals to send.
↳each tick.")
    )
    parser.add_argument(
        '-I', '--interval', type=float, default=0.2, help=("The time, in seconds,
↳between ticks.")

```

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```

)
parser.add_argument(
    '-n',
    '--num-messages',
    type=int,
    default=-1,
    help=("The number of message from the database to use, or -1 to use all."),
)
parser.add_argument(
    '-s',
    '--seed',
    nargs='?',
    default='0',
    help=(
        "The seed used for choosing messages. If possible, will be converted to an
↪int. If no argument is given, a random seed will be used."
    ),
)
args = parser.parse_args()

if args.seed is None:
    seed = None
else:
    try:
        seed = int(args.seed)
    except ValueError:
        seed = args.seed

ping_loop(
    channel_number=args.channel,
    db_name=args.db,
    num_messages=args.num_messages,
    quantity=args.quantity,
    interval=args.interval,
    bitrate=bitrates[args.bitrate.upper()],
    seed=args.seed,
)

```

## Description

**Note:** There must be some process reading the messages for `pinger.py` to work (see e.g. *Monitor a Channel Using a Database*).

`ping_loop` will first extract a random list of messages (see *Randomness*), and then enter a loop that creates a new *FrameBox* before adding some random signals with random values (the quantity specified by the `quantity/--quantity` argument).

Adding random signals is done with `set_random_framebox_signal`, which picks a random signal from the framebox, and `get_random_value` which inspects the given signal and provides a random value based on the signal's definition.

Finally, the loop pauses for `interval/--interval` seconds between sending messages.

## Randomness

The random selection of messages is done with the `seed/--seed` and `num_messages/num-messages` arguments. If `num_messages` is `-1`, all messages from the database will be used. Otherwise, `num_message` specifies the number of messages to be randomly picked from the database.

The `seed` argument will be sent to `random.seed` before the messages are selected (which is done with `random.sample`), which means as long as the seed remains the same, the same messages are selected. The `seed` can also be set to `None` for a pseudo-random seed.

## Sample Output

```
Randomly selecting signals from the following messages:
[Message(name='EngineData', id=100, flags=<MessageFlag.0: 0>, dlc=8, comment=''),
 ↪Message(name='GearBoxInfo', id=1020, flags=<MessageFlag.0: 0>, dlc=1, comment='')]
Seed used was '0'

Sending frame Frame(id=1020, data=bytearray(b'\x00'), dlc=1, flags=<MessageFlag.0: 0>,
 ↪timestamp=None)
Sending frame Frame(id=100, data=bytearray(b'\x00\x00\x16]\x00\x00\x00\x00'), dlc=8,
 ↪flags=<MessageFlag.0: 0>, timestamp=None)
Sending frame Frame(id=1020, data=bytearray(b'\x00'), dlc=1, flags=<MessageFlag.0: 0>,
 ↪timestamp=None)
Sending frame Frame(id=100, data=bytearray(b'\x00\x00\x00\xdd\x00\x00\x00\x00'), dlc=8,
 ↪flags=<MessageFlag.0: 0>, timestamp=None)
Sending frame Frame(id=1020, data=bytearray(b'\x00'), dlc=1, flags=<MessageFlag.0: 0>,
 ↪timestamp=None)
Sending frame Frame(id=100, data=bytearray(b'\x00\x00\x00\xe0\x00\x00\t'), dlc=8, flags=
 ↪<MessageFlag.0: 0>, timestamp=None)
Sending frame Frame(id=1020, data=bytearray(b'\x04'), dlc=1, flags=<MessageFlag.0: 0>,
 ↪timestamp=None)
Sending frame Frame(id=100, data=bytearray(b'f\x07\n\x00\x00\x00\x00\x00'), dlc=8, flags=
 ↪<MessageFlag.0: 0>, timestamp=None)
Sending frame Frame(id=1020, data=bytearray(b'\x00'), dlc=1, flags=<MessageFlag.0: 0>,
 ↪timestamp=None)
Sending frame Frame(id=100, data=bytearray(b'\x0c\x15-\x00\x00\x00\x00\x00'), dlc=8,
 ↪flags=<MessageFlag.0: 0>, timestamp=None)
```

## 1.5.8 Validate a Memorator Configuration

```
"""validate_memo_config.py -- validate a Memorator configuration

This script uses canlib.kvamemolibxml to load and validate a Memorator
configuration in an xml file, and then prints any errors and warnings.

It requires a Memorator configuration in xml format.

"""
```

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```

import argparse

from canlib import kvamemolibxml

def validate(filename):
    # Read in the XML configuration file
    config = kvamemolibxml.load_xml_file(filename)

    # Validate the XML configuration
    errors, warnings = config.validate()

    # Print errors and warnings
    for error in errors:
        print(error)
    for warning in warnings:
        print(warning)

    if errors or warnings:
        raise Exception("Please fix validation errors/warnings.")
    else:
        print("No errors found!")

if __name__ == '__main__':
    parser = argparse.ArgumentParser(description="Validate a Memorator configuration.")
    parser.add_argument(
        'filename', default='logall.xml', nargs='?', help="The filename of the
↳ configuration.")
    )
    args = parser.parse_args()

    validate(args.filename)

```

### 1.5.9 Write a Configuration to a Memorator

```

"""write_memo_config.py -- Write a configuration to a memorator

```

*This example script uses canlib.kvamemolibxml and canlib.kvmlib to load a configuration file in .xml format, validate it, and then write it to a connected Memorator.*

*It requires a configuration xml file and a connected Memorator device.*

```

"""

```

```

import argparse

from canlib import kvamemolibxml, kvmlib

```

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```

def write_config(filename, channel_number):
    # Read in the XML configuration file
    config = kvmemolibxml.load_xml_file(filename)

    # Validate the XML configuration
    errors, warnings = config.validate()

    if errors or warnings:
        raise Exception("Errors or warnings found! Check validate_memo_config example.")

    # Open the device and write the configuration
    with kvmllib.openDevice(channel_number) as memo:
        memo.write_config(config.lif)

if __name__ == '__main__':
    parser = argparse.ArgumentParser(description="Write a configuration to a Memorator.")
    parser.add_argument(
        'filename', default='logall.xml', nargs='?', help="The filename of the
↪ configuration.")
    )
    parser.add_argument(
        'channel',
        type=int,
        default=0,
        nargs='?',
        help="The channel number of the device the configuration should be written to.
↪"),
    )
    args = parser.parse_args()

    write_config(args.filename, args.channel)

```

## 1.6 Reference

### 1.6.1 Base Exceptions

#### CanlibException

**exception** canlib.CanlibException

Base class for all exceptions in canlib

## DllException

### exception canlib.DllException

Bases: *canlib.exceptions.CanlibException*

Base class for exceptions from dll calls in canlib

All instances of this class must have a `status` attribute defined (this is enforced in the constructor). Its value is the status code that caused the exception.

#### property canERR

Deprecated name for `status`

## 1.6.2 EAN

### class canlib.EAN(*source*)

Helper object for dealing with European Article Numbers

Depending on the format the ean is in, *EAN* objects are created in different ways;

For strings:

```
EAN('73-30130-01234-5')
```

For integers:

```
EAN(7330130012345)
```

For iterables of integers:

```
EAN([7, 3, 3, 0, 1, 3, 0, 0, 1, 2, 3, 4, 5])
```

For BCD-coded bytes or bytearrays (str in python 2):

```
EAN.from_bcd(b'\x45\x23\x01\x30\x01\x33\x07')
```

For “hi-lo” format, i.e. two 32-bit integers containing half the ean each, both BCD-coded:

```
EAN.from_hilo([eanHi, eanLo])
```

The various representations can then be produced from the resulting object:

```
>>> str(ean)
'73-30130-01234-5'
>>> int(ean)
7330130012345
>>> tuple(ean) # or list(), or any other sequence type
(7, 3, 3, 0, 1, 3, 0, 0, 1, 2, 3, 4, 5)
>>> ean.bcd()
b'E#\x010\x013\x07'
>>> ean.hilo()
(805380933, 471809)
```

Sometimes it is easier to only use the last six digits of the ean, the product code and check digit. This is supported when working with string representations; the constructor supports six-digit (seven-character) input:

```
EAN('01234-5')
```

In that cases, the country and manufacturer code is assumed to be that of Kvaser AB (73-30130).

A string containing only the product code and check digit can also be retrieved:

```
ean.product()
```

Instances can also be indexed which yields specific digits as integers:

```
>>> ean[7]
0
>>> ean[7:]
(0, 1, 2, 3, 4, 5)
```

---

**Note:** The byteorder is currently always assumed to be ‘little’.

---

**bcd()**

Return a binary-coded bytes object with this EAN

**fmt** = '##-#####-#####-#'

**classmethod from\_bcd**(*bcd\_bytes*)

Create an EAN object from a binary coded bytes-like object

The EAN is automatically shortened to the correct length.

**classmethod from\_hilo**(*hilo*)

Create an EAN object from a pair of 32-bit integers, (eanHi, eanLo)

**classmethod from\_string**(*ean\_string*)

Create an EAN object from a specially formatted string

Deprecated since version 1.6: Use the constructor, EAN(*ean\_string*), instead.

**hilo()**

Return a pair of 32-bit integers, (eanHi, eanLo), with this EAN

**num\_digits** = 13

**product()**

Return only the product code and check digit of the string representation

### 1.6.3 Device

**class** canlib.Device(*ean, serial*)

Class for keeping track of a physical device

This class represents a physical device regardless of whether it is currently connected or not, and on which channel it is connected.

If the device is currently connected, *Device.find* can be used to get a *Device* object:

```
dev = Device.find(ean=EAN('67890-1'))
```

*Device.find* supports searching for devices based on a variety of information, and will return a *Device* object corresponding to the first physical device that matched its arguments. In this case, it would be the first device found with an EAN of 73-30130-67890-1.

If the device wanted is not currently connected, *Device* objects can be created with their EAN and serial number (as this is the minimal information needed to uniquely identify a specific device):

```
dev = Device(ean=EAN('67890-1'), serial=42)
```

Two *Device* objects can be checked for equality (whether they refer to the same device) and be converted to a str. *Device.probe\_info* can also be used for a more verbose string representation that queries the device (if connected) for various pieces of information.

This class also provides functions for creating the other objects of canlib:

- *canlib.Channel* – *Device.channel*
- *canlib.ChannelData* – *Device.channel\_data*
- *canlib.IOControl* – *Device.iocontrol*
- *kvmLib.Memorator* – *Device.memorator*
- *linlib.Channel* – *Device.lin\_master* and *Device.lin\_slave*

### Variables

- **ean** (*canlib.EAN*) – The EAN of this device.
- **serial** (int) – The serial number of this device.
- **last\_channel\_number** (int) – The channel number this device was last found on (used as an optimization; while the device stays on the same CANlib channel there is no need for a linear search of all channels).

New in version 1.6.

**channel**(\*args, \*\*kwargs)

A *Channel* for this device's first channel

The experimental argument `_chan_no_on_card` may be given, the int provided will be added (without any verifications) to the *channel\_number* where this device was found on, and may thus be used to open a specific local channel on this device.

---

**Note:** When using the `_chan_no_on_card` attribute, you must make sure that the card actually have the assumed number of local channels. Using this argument with a too large int could return a channel belonging to a different device.

---

Arguments to *openChannel* other than the channel number can be passed to this function.

Changed in version 1.13: Added argument `_chan_no_on_card`

Deprecated since version 1.16: Use *open\_channel* instead

**channel\_data**()

A *canlib.ChannelData* for this device's first channel

**channel\_number**()

An int with this device's CANlib channel number

**ean**

**classmethod find**(channel\_number=None, ean=None, serial=None, channel\_name=None)

Searches for a specific device

Goes through all CANlib channels (from zero and up), until one of them matches the given arguments. If an argument is omitted or `None`, any device will match it. If no devices matches a `canlib.CanNotFound` exception will be raised.

#### Parameters

- **channel\_number** (int) – Find a device on this CANlib channel (number).
- **ean** (`canlib.EAN`) – Find a device with this EAN.
- **serial** (int) – Find a device with this serial number.
- **channel\_name** (str) – Find a device with this CANlib channel name.

#### **iocontrol()**

A `canlib.IOControl` for this device's first channel

#### **isconnected()**

A bool whether this device can currently be found

#### **issubset**(*other*)

Check if device is a subset of other Device.

This can be used to see if a found device fulfills criteria specified in *other*. Setting an attribute to `None` is regarded as a `Any`. This means that e.g. any serial number will be a subset of a serial number specified as `None`.

New in version 1.9.

#### **last\_channel\_number**

#### **lin\_master**(\*args, \*\*kwargs)

A `linlib.Channel` master for this device's first channel

Arguments to `linlib.openMaster` other than the channel number can be passed to this function.

#### **lin\_slave**(\*args, \*\*kwargs)

A `linlib.Channel` slave for this device's first channel

Arguments to `linlib.openSlave` other than the channel number can be passed to this function.

#### **memorator**(\*args, \*\*kwargs)

A `kvmlib.Memorator` for this device's first channel

Arguments to `kvmlib.openDevice` other than the channel number can be passed to this function.

#### **open\_channel**(*chan\_no\_on\_card=0*, \*\*kwargs)

A `canlib.Channel` for this device's first channel

The parameter `chan_no_on_card` will be added (without any verifications) to the `channel_number` where this device was found on, and may thus be used to open a specific local channel on this device.

---

**Note:** When using the `chan_no_on_card` parameter, you must make sure that the card actually have the assumed number of local channels. Using this parameter with a too large `int` could return a channel belonging to a different device.

---

Arguments to `canlib.open_channel`, other than the channel number, can be passed to this function, but must be passed as keyword arguments.

New in version 1.16.

#### **probe\_info()**

A str with information about this device



This function is useful when the *Device*'s `str()` does not give enough information while debugging. When the device is connected various pieces of information such as the device name, firmware, and driver name is given. When the device is not connected only basic information can be given.

---

**Note:** Never inspect the return value of this function, only use it for displaying information. Exactly what is shown depends on whether the device is connected or not, and is not guaranteed to stay consistent between versions.

---

**remote**(\*args, \*\*kwargs)

A *kvrlib.RemoteDevice* for this device

Arguments to *kvrlib.openDevice* other than the channel number can be passed to this function.

**serial**

## connected\_devices()

**canlib.connected\_devices()**

Get all currently connected devices as *Device*

Returns an iterator of *Device* object, one object for every physical device currently connected.

New in version 1.6.

Changed in version 1.7: *Device.last\_channel\_number* will now be set.

## 1.6.4 Frames

### Frame

**class** canlib.**Frame**(*id\_*, *data*, *dlc=None*, *flags=0*, *timestamp=None*)

Represents a CAN message

#### Parameters

- **id\_** – Message id
- **data** – Message data, will pad zero to match dlc (if dlc is given)
- **dlc** – Message dlc, default is calculated from number of data
- **flags** (*canlib.MessageFlag*) – Message flags, default is 0
- **timestamp** – Optional timestamp

**data**

**dlc**

**flags**

**id**

**timestamp**

## LINFrame

**class** canlib.LINFrame(\*args, \*\*kwargs)

Bases: `canlib.frame.Frame`

Represents a LIN message

A `Frame` that also has an `info` attribute, which is a `linlib.MessageInfo` or `None`. This attribute is initialized via the `info` keyword-only argument to the constructor.

**data**

**dlc**

**flags**

**id**

**info**

**timestamp**

## 1.6.5 Version Numbers

### VersionNumber

**class** canlib.VersionNumber(major, minor=None, build=None, release=None)

A tuple-subclass representing a version number

Version numbers can be created using one to three positional arguments, representing the major, minor, and build number respectively:

```
v1 = VersionNumber(1)
v12 = VersionNumber(1, 2)
v123 = VersionNumber(1, 2, 3)
```

Keyword arguments can also be used:

```
v1 = VersionNumber(major=1)
v12 = VersionNumber(major=1, minor=2)
v123 = VersionNumber(major=1, minor=2, build=3)
```

A fourth number, the release number, can also be given as a keyword-only argument:

```
v1293 = VersionNumber(major=1, minor=2, release=9, build=3)
```

This release number is placed between the minor and build numbers, both for the string representation and in the tuple.

The major number is required and the other numbers are optional in the order minor, build, release.

All numbers can be accessed as attributes (`major`, `minor`, `release`, `build`). If the number is unavailable, accessing the attribute returns `None`.

**property** beta

**property** build

**property** major

**property** minor

**property release**

## BetaVersionNumber

**class** `canlib.BetaVersionNumber`(*major, minor=None, build=None, release=None*)

A tuple-subclass representing a beta (preview) version number

A *VersionNumber* that also has the attribute *beta* set to true.

New in version 1.6.

**property beta**

## 1.6.6 canlib

### Exceptions

#### CanError

**exception** `canlib.canlib.CanError`

Bases: `canlib.exceptions.DllException`

Base class for exceptions raised by the canlib class

Looks up the error text in the canlib dll and presents it together with the error code and the wrapper function that triggered the exception.

#### CanNoMsg

**exception** `canlib.canlib.CanNoMsg`

Bases: `canlib.canlib.exceptions.CanError`

Raised when no matching message was available

**status** = -2

#### CanNotFound

**exception** `canlib.canlib.CanNotFound`

Bases: `canlib.canlib.exceptions.CanError`

Specified device or channel not found

There is no hardware available that matches the given search criteria. For example, you may have specified `Open.REQUIRE_EXTENDED` but there's no controller capable of extended CAN. You may have specified a channel number that is out of the range for the hardware in question. You may have requested exclusive access to a channel, but the channel is already occupied.

New in version 1.6.

**status** = -3

## CanScriptFail

**exception** `canlib.canlib.CanScriptFail`

Bases: `canlib.canlib.exceptions.CanError`

Raised when a script call failed.

This exception represents several different failures, for example:

- Trying to load a corrupt file or not a .txe file
- Trying to start a t script that has not been loaded
- Trying to load a t script compiled with the wrong version of the t compiler
- Trying to unload a t script that has not been stopped
- Trying to use an envvar that does not exist

**status** = -39

## EnvvarException

**exception** `canlib.canlib.EnvvarException`

Bases: `canlib.exceptions.CanlibException`

Base class for exceptions related to environment variables.

## EnvvarNameError

**exception** `canlib.canlib.EnvvarNameError`(*envvar*)

Bases: `canlib.canlib.exceptions.EnvvarException`

Raised when the name of the environment variable is illegal.

## EnvvarValueError

**exception** `canlib.canlib.EnvvarValueError`(*envvar*, *type\_*, *value*)

Bases: `canlib.canlib.exceptions.EnvvarException`

Raised when the type of the value does not match the type of the environment variable.

## IoNoValidConfiguration

**exception** `canlib.canlib.IoNoValidConfiguration`

Bases: `canlib.canlib.exceptions.CanError`

I/O pin configuration is invalid

No I/O pins was found, or unknown I/O pins was discovered.

New in version 1.8.

**status** = -48

## IoPinConfigurationNotConfirmed

### exception canlib.canlib.IoPinConfigurationNotConfirmed

Bases: *canlib.canlib.exceptions.CanError*

I/O pin configuration is not confirmed

Before accessing any I/O pin value, the device I/O pin configuration must be confirmed, using e.g. *Channel.io\_confirm\_config*.

See also *iopin.Configuration*.

New in version 1.8.

**status = -45**

## TxeFileIsEncrypted

### exception canlib.canlib.TxeFileIsEncrypted

Bases: *canlib.exceptions.CanlibException*

Raised when trying to access *Txe.source* and the source and byte-code sections of the .txe binary have been encrypted.

New in version 1.6.

## Bus Parameters

### calc\_bitrate()

`canlib.canlib.busparams.calc_bitrate(target_bitrate, clk_freq)`

Calculate nearest available bitrate

#### Parameters

- **target\_bitrate** (int) – Wanted bitrate (bit/s)
- **clk\_freq** (int) – Device clock frequency (Hz)

#### Returns

The returned tuple is a (bitrate, tq) named tuple of –

1. **bitrate** (int): Available bitrate, could be a rounded value (bit/s)
2. **tq** (int): Number of time quanta in one bit

New in version 1.16.

## calc\_busparamstq()

canlib.canlib.busparams.**calc\_busparamstq**(*target\_bitrate*, *target\_sample\_point*, *target\_sync\_jump\_width*, *clk\_freq*, *target\_prop\_tq=None*, *prescaler=1*)

Calculate closest matching busparameters.

The device clock frequency, *clk\_freq*, can be obtained via [ClockInfo.frequency\(\)](#):

```
>>> chd = canlib.ChannelData(channel_number=0)
>>> clock_info = chd.clock_info
>>> clock_info.frequency()
800000000.0
```

Now call *calc\_busparamstq* with target values, and a *BusParamsTq* object will be returned:

```
>>> params = calc_busparamstq(
... target_bitrate=470_000,
... target_sample_point=82,
... target_sync_jump_width=15.3,
... clk_freq=clock_info.frequency())
>>> params
BusParamsTq(tq=170, prop=107, phase1=31, phase2=31, sjw=26, prescaler=1)
```

A target number of time quanta in the propagation segment can also be specified by the user.

The returned *BusParamsTq* may not be valid on all devices. If *Error.NOT\_IMPLEMENTED* is encountered when trying to set the bitrate with the returned *BusParamsTq*, provide a prescaler argument higher than one and retry. This will lower the total number of time quanta in the bit and thus make the *BusParamsTq* valid.

## Example

```
>>> params = calc_busparamstq(
... target_bitrate=470_000,
... target_sample_point=82,
... target_sync_jump_width=15.3,
... clk_freq=clock_info.frequency(),
... target_prop_tq=50,
... prescaler=2)
>>> params
BusParamsTq(tq=85, prop=25, phase1=44, phase2=15, sjw=13, prescaler=2)
```

---

### Note:

- Minimum sjw returned is 1, maximum sjw is min(phase1, phase2).
- 

### Parameters

- **target\_bitrate** (float) – Wanted bitrate (bit/s)
- **target\_sample\_point** (float) – Wanted sample point in percentage (0-100)
- **target\_sync\_jump\_width** (float) – Wanted sync jump width in percentage (0-100)
- **clk\_freq** (float) – Device clock frequency (Hz)

- **target\_prop\_tq** (int, Optional) – Wanted propagation segment (time quanta)
- **prescaler** (int, Optional) – Wanted prescaler (at most 2 for CAN FD)

**Returns** *BusParamsTq* – Calculated bus parameters

New in version 1.16.

Changed in version 1.17.

### calc\_sjw()

`canlib.canlib.busparams.calc_sjw(tq, target_sync_jump_width)`

Calculate sync jump width

tq: Number of time quanta in one bit target\_sync\_jump\_width: Wanted sync jump width, 0-100 (%)

Note: Minimum sjw\_tq returned is 1.

#### Returns

The returned named tuple is a (sjw\_tq, sync\_jump\_width) consisting of –

1. **sjw\_tq** (int): Size of sync jump width in number of time quanta,
2. **sync\_jump\_width** (number): Size of sync jump width in percentage (%)

New in version 1.16.

### to\_BusParamsTq()

`canlib.canlib.busparams.to_BusParamsTq(clk_freq, bus_param, prescaler=1, data=False)`

Convert *BitrateSetting* or tuple to *BusParamsTq*.

The device clock frequency, `clk_freq`, can be obtained via `ClockInfo.frequency()`:

```
>>> chd = canlib.ChannelData(channel_number=0)
>>> clock_info = chd.clock_info
>>> clock_info.frequency()
800000000.0
```

#### Parameters

- **clk\_freq** (float) – Clock frequency of device.
- **bus\_param** (*BitrateSetting* or tuple) – *BitrateSetting* object or
- **(freq, tseg1, tseg2, sjw)** `tuple` to convert.
- **prescaler** (int) – The prescaler to use in the created *BusParamsTq*
- **object.**
- **data** (bool) – Set to True if the resulting *BusParamsTq* should be
- **used for CAN FD data bitrate parameters.**

**Returns** *BusParamsTq* object with equivalent settings as the input argument.

New in version 1.17.

## to\_BitrateSetting()

canlib.canlib.busparams.to\_BitrateSetting(*clk\_freq*, *bus\_param*)

Convert *BusParamsTq* to *BitrateSetting*.

The device clock frequency, *clk\_freq*, can be obtained via *ClockInfo.frequency()*:

```
>>> chd = canlib.ChannelData(channel_number=0)
>>> clock_info = chd.clock_info
>>> clock_info.frequency()
800000000.0
```

### Parameters

- **clk\_freq** (float) – Clock frequency of device.
- **bus\_param** (*BusParamsTq*) – *BusParamsTq* object to convert.

**Returns** *BitrateSetting* object with equivalent settings as the input argument.

New in version 1.17.

## ClockInfo

**class** canlib.canlib.busparams.**ClockInfo**(*numerator*, *denominator*, *power\_of\_ten*, *accuracy*)

Information about clock a oscillator

The clock frequency is set in the form:

$$\text{frequency} = \text{numerator} / \text{denominator} * 10^{**} \text{power\_of\_ten} +/- \text{accuracy}$$

New in version 1.16.

### frequency()

Returns an approximation of the clock frequency as a float.

## BusParamsTq

**class** canlib.canlib.busparams.**BusParamsTq**(*tq*, *phase1*, *phase2*, *sjw*, *prescaler=1*, *prop=None*)

Holds parameters for busparameters in number of time quanta.

If you don't want to specify the busparameters in time quanta directly, you may use *calc\_busparamstq* which returns an object of this class.

```
>>> params = calc_busparamstq(
... target_bitrate=470_000,
... target_sample_point=82,
... target_sync_jump_width=33.5,
... clk_freq=clk_freq)
>>> params
BusParamsTq(tq=170, prop=107, phase1=31, phase2=31, sjw=57, prescaler=1)
```

You may now query for the actual Sample Point and Sync Jump Width expressed as percentages of total bit time quanta:



```
>>> params.sample_point()
81.76470588235294
```

```
>>> params.sync_jump_width()
33.52941176470588
```

If you supply the clock frequency, you may also calculate the corresponding bitrate:

```
>>> params.bitrate(clk_freq=80_000_000)
470588.23529411765
```

### Parameters

- **tq** (int) – Number of time quanta in one bit.
- **phase1** (int) – Number of time quanta in Phase Segment 1.
- **phase2** (int) – Number of time quanta in Phase Segment 2.
- **sjw** (int) – Number of time quanta in Sync Jump Width.
- **prescaler** (int) – Prescaler value (1-2 to enable auto in CAN FD)
- **prop** (int, optional) – Number of time quanta in Propagation Segment.

New in version 1.16.

### **bitrate**(*clk\_freq*)

Return bitrate assuming the given clock frequency

**Parameters** **clk\_freq** (int) – Clock frequency (in Hz)

### **sample\_point**()

Return sample point in percentage.

### **sample\_point\_ns**(*clk\_freq*)

Return sample point in ns.

New in version 1.17.

### **sync\_jump\_width**()

Return sync jump width (SJW) in percentage.

## BitrateSetting

**class** canlib.canlib.busparams.**BitrateSetting**(*freq, tseg1, tseg2, sjw, nosamp=1, syncMode=0*)

Class that holds bitrate setting.

### Parameters

- **freq** – Bitrate in bit/s.
- **tseg1** – Number of quanta from (but not including) the Sync Segment to the sampling point.
- **tseg2** – Number of quanta from the sampling point to the end of the bit.
- **sjw** – The Synchronization Jump Width.
- **nosamp** – The number of sampling points, only 1 is supported.
- **syncMode** – Unsupported and ignored.

New in version 1.17.

**classmethod** `from_predefined(bitrate)`

Create a `BitrateSetting` object using one of the `Bitrate` or `BitrateFD` enumerations.

## Channel

### `openChannel()`

`canlib.canlib.openChannel(channel, flags=0, bitrate=None, data_bitrate=None)`

Open CAN channel

Retrieves a `Channel` object for the given CANlib channel number using the supplied flags.

Example usage:

```
>>> bitrate = canlib.busparams.BusParamsTq(  
... tq=40,  
... phase1=5,  
... phase2=6,  
... sjw=4,  
... prescaler=2,  
... prop=28,  
... )  
>>> data_bitrate = canlib.busparams.BusParamsTq(  
... tq=40,  
... phase1=31,  
... phase2=8,  
... sjw=2,  
... prescaler=2,  
... )  
>>> ch = canlib.openChannel(  
... channel=0,  
... flags=canlib.Open.CAN_FD,  
... bitrate=bitrate,  
... data_bitrate=data_bitrate,  
... )
```

---

**Note:** If both `bitrate` and `data_bitrate` is given, both must be of the same type, i.e. either `BusParamsTq` or `BITRATE` flags. It is not supported to mix the two.

---

### Parameters

- **channel** (int) – CANlib channel number
- **flags** (int) – Flags, a combination of the `Open` flag values. Default is zero, i.e. no flags.
- **bitrate** (`BusParamsTq` or `Bitrate` or `BitrateFD`) – The desired bitrate. If the bitrate is not a `BusParamsTq`, the predefined `Bitrate` values are used for classic CAN and `BitrateFD` values are used for CAN FD, e.g. `canlib.Bitrate.BITRATE_1M` and `canlib.BitrateFD.BITRATE_1M_80P`. For CAN FD, this parameter gives the arbitration bitrate.

- **data\_bitrate** (*BusParamsTq* or *BitrateFD*) – The desired data bitrate for CAN FD. If not *BusParamsTq* is given, the predefined *BitrateFD* values are used, e.g. `canlib.BitrateFD.BITRATE_500K_80p`. This parameter is only used when opening a CAN FD channel.

**Returns** A *Channel* object created with channel and flags

New in version 1.6: The *bitrate* and *data\_bitrate* arguments was added.

Changed in version 1.16: The *bitrate* and *data\_bitrate* arguments now accept *BusParamsTq* objects.

Changed in version 1.17: Added support for *Bitrate* and *BitrateFD* enumerations.

## ErrorCounters

**class** `canlib.canlib.channel.ErrorCounters(tx, rx, overrun)`

Error counters returned by *Channel.read\_error\_counters*.

**property** `overrun`

Alias for field number 2

**property** `rx`

Alias for field number 1

**property** `tx`

Alias for field number 0

## Channel

**class** `canlib.canlib.Channel(channel_number, flags=0)`

Helper class that represents a CANlib channel.

This class wraps the canlib class and tries to implement a more Pythonic interface to CANlib.

Channels are automatically closed on garbage collection, and can also be used as context managers in which case they close as soon as the context exits.

**Variables** `envvar` (*EnvVar*) – Used to access *t* program environment variables

**announceIdentityEx**(*item, value*)

AnnounceIdentityEx function is used by certain OEM applications.

New in version 1.17.

**bitrate\_to\_BusParamsTq**(*freq\_a, freq\_d=None*)

Calculate bus parameters based on predefined frequencies.

This function uses the *Bitrate* and *BitrateFD* values to create bus parameters for use with the new bus parameter API.

### Parameters

- **freq\_a** (*Bitrate* or *BitrateFD*) – The bitrate for classic CAN channels specified as a *Bitrate*, or the arbitration bitrate for CAN FD channels specified as a *BitrateFD*.
- **freq\_d** (*BitrateFD*) – Data bitrate for CAN FD channels.

### Returns

(nominal, None) for classic CAN, where nominal is a *BusParamsTq* object.

(*nominal*, *data*) for CAN FD, where both *nominal* and *data* are *BusParamsTq* objects, representing the arbitration bitrate and the data bitrate, respectively.

New in version 1.17.

### **busOff()**

Takes the specified channel off-bus.

Closes the channel associated with the handle. If no other threads are using the CAN circuit, it is taken off bus. The handle can not be used for further references to the channel.

### **busOn()**

Takes the specified channel on-bus.

If you are using multiple handles to the same physical channel, for example if you are implementing a multithreaded application, you must call `busOn()` once for each handle.

### **canAccept(*envelope*, *flag*)**

Set acceptance filters mask or code.

This routine sets the message acceptance filters on a CAN channel.

Setting flag to *AcceptFilterFlag.NULL\_MASK* (0) removes the filter.

Note that not all CAN boards support different masks for standard and extended CAN identifiers.

#### **Parameters**

- **envelope** – The mask or code to set.
- **flag** – Any of *AcceptFilterFlag*

### **canSetAcceptanceFilter(*code*, *mask*, *is\_extended=False*)**

Set message acceptance filter.

This routine sets the message acceptance filters on a CAN channel. The message is accepted if `id AND mask == code` (this is actually implemented as `if ((code XOR id) AND mask) == 0`).

Using standard 11-bit CAN identifiers and setting

- `mask = 0x7f0`,
- `code = 0x080`

accepts CAN messages with standard id 0x080 to 0x08f.

Setting the *mask* to `canFILTER_NULL_MASK` (0) removes the filter.

Note that not all CAN boards support different masks for standard and extended CAN identifiers.

#### **Parameters**

- **mask** (int) – A bit mask that indicates relevant bits with '1'.
- **code** (int) – The expected state of the masked bits.
- **is\_extended** (bool) – If True, both mask and code applies to 29-bit CAN identifiers.

### **property channel\_data**

`canGetHandleData` helper object for this channel

See the documentation for *ChannelData/HandleData* for how it can be used to perform all functionality of the C function `canGetHandleData`.

New in version 1.13.

Type *HandleData*

**close()**

Close CANlib channel

Closes the channel associated with the handle. If no other threads are using the CAN circuit, it is taken off bus.

---

**Note:** It is normally not necessary to call this function directly, as the internal handle is automatically closed when the *Channel* object is garbage collected.

---

**device()**

Get a Device object from the current channel

**Returns** *Device* – Device used by this channel,

New in version 1.16.

**fileCopyFromDevice**(*deviceFileName*, *hostFileName=None*)

Copy an arbitrary file from the device to the host.

**Parameters**

- **deviceFileName** (str) – The device file name.
- **hostFileName** (str, optional) – The target host file name. Defaults to deviceFileName.

**fileCopyToDevice**(*hostFileName*, *deviceFileName=None*)

Copy an arbitrary file from the host to the () isdevice.

The filename must adhere to the FAT '8.3' naming standard, max 8 characters - a dot - max 3 characters.

**Parameters**

- **hostFileName** (str) – The target host file name.
- **deviceFileName** (str, optional) – The device file name. Defaults to the same as *hostFileName*.

**fileDelete**(*deviceFileName*)

Delete file from device.

**fileDiskFormat**()

Format the disk on the device, not supported by all devices.

New in version 1.11.

**fileGetCount**()

Get the number of files on the device.

**Returns** int – The number of files.

**fileGetName**(*fileNo*)

Get the name of the file with the supplied number.

**Parameters** **fileNo** (int) – The number of the file.

**Returns** str – The name of the file.

**flashLeds**(*action*, *timeout\_ms*)

Turn Leds on or off.

**Parameters**

- **action** (int) – One of *LEDAction*, defining which LED to turn on or off.

- **timeout\_ms** (int) – Specifies the time, in milliseconds, during which the action is to be carried out. When the timeout expires, the LED(s) will return to its ordinary function.

**getBusOutputControl()**

Get driver type

This function retrieves the current CAN controller driver type. This corresponds loosely to the bus output control register in the CAN controller, hence the name of this function.

---

**Note:** Not all CAN driver types are supported on all cards.

---

**Returns** drivertype (*canlib.Driver*) – Driver type to set.

New in version 1.11.

**getBusParams()**

Get bus timing parameters for classic CAN.

This function retrieves the current bus parameters for the specified channel.

**Returns: A tuple containing:** *freq*: Bitrate in bit/s.

*tseg1*: Number of quanta from but not including the Sync Segment to the sampling point.

*tseg2*: Number of quanta from the sampling point to the end of the bit.

*sjw*: The Synchronization Jump Width, can be 1, 2, 3, or 4.

*noSamp*: The number of sampling points, only 1 is supported.

*syncmode*: Unsupported, always read as zero.

**getBusParamsFd()**

Get bus timing parameters for BRS in CAN FD.

This function retrieves the bus current timing parameters used in BRS (Bit rate switch) mode for the current CANlib channel.

The library provides default values for *tseg1\_brs*, *tseg2\_brs* and *sjw\_brs* when *freq* is a *BitrateFD* value.

If *freq* is any other value, no default values are supplied by the library.

For finding out whether a channel is opened using *CAN\_FD* or *CAN\_FD\_NONISO* flags, see *is\_can\_fd()*

**Returns: A tuple containing:** *freq\_brs*: Bitrate in bit/s.

*tseg1\_brs*: Number of quanta from (but not including) the Sync Segment to the sampling point.

*tseg2\_brs*: Number of quanta from the sampling point to the end of the bit.

*sjw\_brs*: The Synchronization Jump Width.

**getChannelData\_CardNumber()**

Deprecated function

Deprecated since version 1.5: Use *ChannelData*; *ChannelData.card\_number*

**getChannelData\_Chan\_No\_On\_Card()**

Deprecated function

Deprecated since version 1.5: Use *ChannelData*; *ChannelData.chan\_no\_on\_card*

**getChannelData\_Cust\_Name()**

Deprecated function

Deprecated since version 1.5: Use [ChannelData](#); `ChannelData.custom_name`

**getChannelData\_DriverName()**

Deprecated function

Deprecated since version 1.5: Use [ChannelData](#); `ChannelData.driver_name`

**getChannelData\_EAN()**

Deprecated function

Deprecated since version 1.5: Use [ChannelData](#); `ChannelData.card_upc_no`

**getChannelData\_EAN\_short()****getChannelData\_Firmware()**

Deprecated function

Deprecated since version 1.5: Use [ChannelData](#); `ChannelData.card_firmware_rev`

**getChannelData\_Name()**

Deprecated function

Deprecated since version 1.5: Use [ChannelData](#); `ChannelData.device_name`

**getChannelData\_Serial()**

Deprecated function

Deprecated since version 1.5: Use [ChannelData](#); `ChannelData.card_serial_no`

**get\_bus\_params\_tq()**

Get bus timing parameters, in time quanta

This function retrieves the current bus parameters for the specified channel. Only the returned nominal parameter is valid when classic CAN is in use.

Returns: A tuple containing:

*nominal*: ([BusParamsTq](#)) Nominal bus timing parameters, also used in classic CAN.

*data*: ([BusParamsTq](#)) Bus timing parameters for data rate in CAN FD.

New in version 1.16.

**get\_bus\_statistics()**

Return bus statistics.

**Returns** [structures.CanBusStatistics](#)

**get\_io\_pin(index)**

Return I/O pin using *index*

**Returns** [iopin.IoPin](#) – io pin object for *index* (Any of [iopin.AnalogIn](#), [iopin.DigitalOut](#) etc)

New in version 1.8.

**ioCtl\_flush\_rx\_buffer()**

Deprecated function

Deprecated since version 1.5: Use [IOControl](#); `Channel.iocontrol.flush_rx_buffer()`.

**ioCtl\_get\_report\_access\_errors()**

Deprecated function

Deprecated since version 1.5: Use [IOControl](#); `Channel.iocontrol.report_access_errors`

**ioCtl\_set\_report\_access\_errors**(*on=0*)

Deprecated function

Deprecated since version 1.5: Use [IOControl](#); `Channel.iocontrol.report_access_errors = on`

**ioCtl\_set\_timer\_scale**(*scale*)

Deprecated function

Deprecated since version 1.5: Use [IOControl](#); `Channel.iocontrol.timer_scale = scale`

**io\_confirm\_config**()

Confirm current I/O configuration

It is required to confirm a configuration by calling this function before accessing any I/O pins value.

New in version 1.8.

**io\_pins**()

Generator that returns all I/O pins one by one

Returns object depending on pin type and direction: [iopin.AnalogIn](#), [iopin.AnalogOut](#), [iopin.DigitalIn](#), [iopin.DigitalOut](#) or [iopin.Relay](#).

New in version 1.8.

**property iocontrol**

canIoCtl helper object for this channel

See the documentation for [IOControl](#) for how it can be used to perform all functionality of the C function `canIoCtl`.

Example usage:

```

>>> from canlib import canlib
>>> ch = canlib.openChannel(channel=0)
>>> ch.iocontrol.timer_scale
1000
>>> ch.iocontrol.local_txecho = False
    
```

Type [IOControl](#)

**is\_can\_fd**()

Return True if the channel has been opened with the [CAN\\_FD](#) or [CAN\\_FD\\_NONISO](#) flags.

**Returns** True if CAN FD, False otherwise.

**kvDeviceGetMode**()

Read the current device's mode.

---

**Note:** The mode is device specific, which means that not all modes are implemented in all products.

---

**Returns** int – One of [DeviceMode](#), indicating which mode is in use.

**kvDeviceSetMode**(*mode*)

Set the current device's mode.



---

**Note:** The mode is device specific, which means that not all modes are implemented in all products.

---

**Parameters** `mode` (int) – One of *DeviceMode*, defining which mode to use.

**number\_of\_io\_pins()**

Return the total number of available I/O pins

New in version 1.8.

**read(*timeout=0*)**

Read a CAN message and metadata.

Reads a message from the receive buffer. If no message is available, the function waits until a message arrives or a timeout occurs.

---

**Note:** If you are using the same channel via multiple handles, the default behaviour is that the different handles will “hear” each other just as if each handle referred to a channel of its own. If you open, say, channel 0 from thread A and thread B and then send a message from thread A, it will be “received” by thread B.

This behaviour can be changed by setting `local_txecho` to `False` (using *IOControl*):

```
>>> from canlib import canlib
>>> ch = canlib.openChannel(channel=0)
>>> ch.iocontrol.local_txecho = False
```

**Parameters** `timeout` (int) – Timeout in milliseconds, -1 gives an infinite timeout.

**Returns** *canlib.Frame*

**Raises** *CanNoMsg* – No CAN message is currently available.

**readDeviceCustomerData(*userNumber=100, itemNumber=0*)**

Read customer data stored in device

**readSpecificSkip(*id\_*)**

Read a message with specified identifier

Reads a message with a specified identifier from the receive buffer. Any preceding message not matching the specified identifier will be removed in the receive buffer. If no message with the specified identifier is available, the function returns immediately with an error code.

**Returns** *canlib.Frame*

**readStatus()**

Return status for the current channel

Returns the latest status reported by the hardware in a combination of the flags *Stat* (bus on/error passive + status etc).

**Returns** *canlib.canlib.Stat*

**readSyncSpecific(*id\_, timeout=0*)**

Wait until the receive queue contains a message with the specified id

**readTimer()**

Read the hardware clock on the specified device

Returns the time value.

**read\_error\_counters()**

Read the error counters of the CAN controller

Returns the latest known values of the error counters in the specified circuit. If the error counters change values precisely when *read\_error\_counters* is called, it may not be reflected in the returned result.

Use *clear\_error\_counters* via *Channel.iocontrol* to clear the counters.

**Returns**

The returned tuple is a (rx, tx, overrun) named tuple of –

1. rx (int): Receive error counter
2. tx (int): Transmit error counter
3. overrun (int): Number of overrun errors.

New in version 1.11.

**requestChipStatus()**

Request chip status messages

Requests that the hardware report the chip status (bus on/error passive status etc.) to the driver. The chip status can later be retrieved using `canlib.Channel.readStatus`.

---

**Note:** The *requestChipStatus* function is asynchronous, that is, it completes before the answer is returned from the hardware. The time between a call to *requestChipStatus* and the point in time where the chip status is actually available via a call to *Channel.readStatus* is not defined. The *Channel.readStatus* always returns the latest data reported by the hardware.

---

**scriptEnvvarClose(envHandle)**

Low level function to close an Envvar

This should normally not be used directly, instead opening and closing of an envvar is automatically done when accessing via the *EnvVar* class through `Channel.envvar`

**scriptEnvvarGetData(envHandle, envSize)****scriptEnvvarGetFloat(envHandle)**

Low level function to read an Envvar of type float

This should normally not be used directly, instead set and get the value of an envvar using the *EnvVar* class through `Channel.envvar`

**scriptEnvvarGetInt(envHandle)**

Low level function to read an Envvar of type int

This should normally not be used directly, instead set and get the value of an envvar using the *EnvVar* class through `Channel.envvar`

**scriptEnvvarOpen(name)**

Low level function to open an Envvar

This should normally not be used directly, instead opening and closing of an envvar is automatically done when accessing via the *EnvVar* class through `Channel.envvar`

**scriptEnvvarSetData(envHandle, value, envSize)**

**scriptEnvvarSetFloat**(*envHandle, value*)

Low level function to set an Envvar of type float

This should normally not be used directly, instead set and get the value of an envvar using the [EnvVar](#) class through `Channel.envvar`

**scriptEnvvarSetInt**(*envHandle, value*)

Low level function to set an Envvar of type int

This should normally not be used directly, instead set and get the value of an envvar using the [EnvVar](#) class through `Channel.envvar`

**scriptGetText**()

Read text from subscribed script slots

Text-subscriptions must first be set up with [Channel.scriptRequestText](#).

**Returns** [ScriptText](#)

**Raises** [CanNoMsg](#) – No more text is currently available.

New in version 1.7.

**scriptLoadFile**(*slot, filePathOnPC*)

Load compiled script file from host(PC)

Loads a compiled script file (.txe) stored on the host (PC) into a script slot on the device. The scripts default channel will be the same channel used when this Channel object was created.

**Parameters**

- **slot** (int) – slot containing the running script we want to stop.
- **filePathOnPC** (str) – Path to compiled script (.txe) to load.

**scriptLoadFileOnDevice**(*slot, localFile*)

Load compiled, locally stored, script file

Loads a compiled script file (.txe) stored locally on the device (SD card) into a script slot on the device. The scripts default channel will be the same channel used when this Channel object was created.

**Parameters**

- **slot** (int) – slot containing the running script we want to stop.
- **localFile** (str) – Name of compiled script (.txe) to load.

**scriptRequestText**(*slot, request=ScriptRequest.SUBSCRIBE*)

Set up a printf subscription to a selected script slot

**Parameters**

- **slot** (int) – The script slot to subscribe/unsubscribe from.
- **request** ([ScriptRequest](#)) – Whether to subscribe or unsubscribe.

Text printed with `printf()` by a t-program that you are subscribed to is saved and can be retrieved with [Channel.scriptGetText](#).

New in version 1.7.

**scriptSendEvent**(*slotNo=0, eventType=1, eventNo=None, data=0*)

Send specified event to specified t script

Send an event with given type, event number, and associated data to a script running in a specific slot.

**scriptStart**(*slot*)

Start previously loaded script in specified slot

**scriptStatus**(*slot*)

Retreives t program status for selected slot

**Parameters** *slot* (int) – Slot number to be queried

**Returns** canlib.ScriptStatus

New in version 1.6.

**scriptStop**(*slot, mode=ScriptStop.NORMAL*)

Stop script running in specified slot

**Parameters**

- **slot** (int) – slot containing the running script we want to stop.
- **mode** (canlib.ScriptStop) – Default mode is canlib.ScriptStop.NORMAL.

**scriptUnload**(*slot*)

Unload previously stopped script in specified slot

**script\_envvar\_get\_data**(*envHandle, len, start=0*)

Low level function to read a slice of an Envvar of type char

This should normally not be used directly, instead set and get the value of an envvar using the [EnvVar](#) class through `Channel.envvar`

New in version 1.10.

**script\_envvar\_set\_data**(*envHandle, value, len, start=0*)

Low level function to write a slice of an Envvar of type char

This should normally not be used directly, instead set and get the value of an envvar using the [EnvVar](#) class through `Channel.envvar`

*value* needs to be a bytes-like object or list

New in version 1.10.

**setBusOutputControl**(*drivertype=Driver.NORMAL*)

Set driver type

This function sets the driver type for a CAN controller to e.g. silent mode. This corresponds loosely to the bus output control register in the CAN controller, hence the name of this function.

---

**Note:** Not all CAN driver types are supported on all cards.

---

**Parameters** *drivertype* ([canlib.Driver](#)) – Driver type to set.

**setBusParams**(*freq, tseg1=0, tseg2=0, sjw=0, noSamp=0, syncmode=0*)

Set bus timing parameters for classic CAN

This function sets the bus timing parameters for the specified CAN controller.

The library provides default values for *tseg1*, *tseg2*, *sjw* and *noSamp* when *freq* is a [Bitrate](#), e.g. [Bitrate.BITRATE\\_1M](#).

If *freq* is any other value, no default values are supplied by the library.

If you are using multiple handles to the same physical channel, for example if you are implementing a multithreaded application, you must call `busOn()` once for each handle. The same applies to `busOff()` - the physical channel will not go off bus until the last handle to the channel goes off bus.

#### Parameters

- **freq** – Bitrate in bit/s.
- **tseg1** – Number of quanta from (but not including) the Sync Segment to the sampling point.
- **tseg2** – Number of quanta from the sampling point to the end of the bit.
- **sjw** – The Synchronization Jump Width, can be 1, 2, 3, or 4.
- **nosamp** – The number of sampling points, only 1 is supported.
- **syncMode** – Unsupported and ignored.

Changed in version 1.17: Now accepts `Bitrate` enumerations.

**setBusParamsFd**(*freq\_brs, tseg1\_brs=0, tseg2\_brs=0, sjw\_brs=0*)

Set bus timing parameters for BRS in CAN FD

This function sets the bus timing parameters used in BRS (Bit rate switch) mode for the current CANlib channel.

The library provides default values for `tseg1_brs`, `tseg2_brs` and `sjw_brs` when `freq` is a `BitrateFD` value, e.g. `BitrateFD.BITRATE_1M_80P`.

If `freq` is any other value, no default values are supplied by the library.

For finding out whether a channel is opened using `CAN_FD` or `CAN_FD_NONISO` flags, see `is_can_fd`

#### Parameters

- **freq\_brs** – Bitrate in bit/s.
- **tseg1\_brs** – Number of quanta from (but not including) the Sync Segment to the sampling point.
- **tseg2\_brs** – Number of quanta from the sampling point to the end of the bit.
- **sjw\_brs** – The Synchronization Jump Width.

Changed in version 1.17: Now accepts `BitrateFD` enumerations.

**set\_bus\_params\_tq**(*nominal, data=None*)

Set bus timing parameters, using time quanta

This function sets the bus timing parameters for the specified CAN controller. When setting bus parameters for CAN FD, both `nominal` and `data` must be given.

If you are using multiple handles to the same physical channel, for example if you are implementing a multithreaded application, you must call `busOff()` once for each handle. The physical channel will not go off bus until the last handle to the channel goes off bus. The same applies to `busOn()`.

#### Parameters

- **nominal** (`BusParamsTq`) – Nominal Bus timing parameters, also used for classic CAN
- **data** (`BusParamsTq`) – Bus timing parameters for data rate in CAN FD.

New in version 1.16.

**set\_callback**(*function, event, context=None*)

Register callback function

This will register a callback function which is called when certain events occur. You can register at most one callback function per handle at any time.

Note:

The callback function is called in the context of a high-priority thread created by CANlib. You should take precaution not to do any time consuming tasks in the callback.

Small example of usage:

```
# Declare callback function
def callback_func(hnd, context, event):
    event = canlib.Notify(event)

    # The nonlocal statement causes the listed identifiers to refer
    # to previously bound variables in the nearest enclosing scope
    # excluding globals.
    nonlocal callback_has_been_called
    print("Callback called, context:{}, event: {!r}".format(context, event))
    # Notify the main program by setting the flag
    callback_has_been_called = True

# setup communication variable and callback
callback_has_been_called = False
callback = canlib.dll.KV CALLBACK_T(callback_func)

with canlib.openChannel(0) as ch:
    ch.set_callback(callback, context=121, event=canlib.Notify.BUSONOFF)
    # trigger the callback
    ch.busOn()
    # do something else
    time.sleep(0.5)
    # Verify that the callback was triggered
    assert callback_has_been_called
```

Note:

It is very important to make sure that you keep a reference to the callback type (callback in the sample above) for as long as any C library might call it. If it gets deleted by the garbage collector, calling it from C is likely to either cause a segfault or maybe even interpret random memory as machine language.

#### Parameters

- **function** (KVCALLBACK\_T) – A ctypes wrapped Python function
- **event** (*Notify*) – A combination of flags to indicate what events to trigger on

New in version 1.7.

**write**(*frame=None, \*args, \*\*kwargs*)

Send a CAN message.

This function sends a Frame object as a CAN message. Note that the message has been queued for transmission when this calls return. It has not necessarily been sent.

---

**Note:** If you are using the same channel via multiple handles, the default behaviour is that the different handles will “hear” each other just as if each handle referred to a channel of its own. If you open, say, channel 0 from thread A and thread B and then send a message from thread A, it will be “received” by thread B.

This behaviour can be changed by setting `local_txecho` to `False` (using `IOControl`):

```
>>> from canlib import canlib
>>> ch = canlib.openChannel(channel=0)
>>> ch.iocontrol.local_txecho = False
```

Also see `Channel.write_raw` for sending messages without constructing `canlib.Frame` objects.

Deprecated since version 1.5: Sending the `canlib.Frame` contents as separate arguments; this functionality has been taken over by `write_raw`.

**Parameters** `frame` (`canlib.Frame`)

**writeSync**(`timeout`)

Wait for queued messages to be sent

Waits until all CAN messages for the specified handle are sent, or the timeout period expires.

**Parameters** `timeout` (`int`) – The timeout in milliseconds, `None` or `0xFFFFFFFF` for an infinite timeout.

**writeWait**(`frame`, `timeout`, `*args`, `**kwargs`)

Sends a CAN message and waits for it to be sent.

This function sends a CAN message. It returns when the message is sent, or the timeout expires. This is a convenience function that combines `write()` and `writeSync()`.

Deprecated since version 1.5: Sending the `Frame` contents as separate arguments; this functionality has been taken over by `writeWait_raw`.

**Parameters**

- **frame** (`canlib.Frame`) – Frame containing the CAN data to be sent
- **timeout** (`int`) – The timeout, in milliseconds. `0xFFFFFFFF` gives an infinite timeout.

**writeWait\_raw**(`id_`, `msg`, `flag=0`, `dlc=0`, `timeout=0`)

Sends a CAN message and waits for it to be sent.

This function sends a CAN message. It returns when the message is sent, or the timeout expires. This is a convenience function that combines `write()` and `writeSync()`.

**Parameters**

- **id\_** – The identifier of the CAN message to send.
- **msg** – An array or bytearray of the message data
- **flag** – A combination of `canlib.canlib.MessageFlag`. Use this parameter e.g. to send extended (29-bit) frames.
- **dlc** – The length of the message in bytes. For Classic CAN dlc can be at most 8, unless `canlib.canlib.Open.ACCEPT_LARGE_DLC` is used. For CAN FD dlc can be one of the following 0-8, 12, 16, 20, 24, 32, 48, 64. Optional, if omitted, dlc is calculated from the `msg` array.
- **timeout** – The timeout, in milliseconds. `0xFFFFFFFF` gives an infinite timeout.

**write\_raw**(`id_`, `msg`, `flag=0`, `dlc=None`)

Send a CAN message

See docstring of `Channel.write` for general information about sending CAN messages.

The variable name `id` (as used by `canlib`) is a built-in function in Python, so the name `id_` is used instead.

### Parameters

- **id\_** – The identifier of the CAN message to send.
- **msg** – An array or bytearray of the message data
- **flag** – A combination of *MessageFlag*. Use this parameter e.g. to send extended (29-bit) frames.
- **dlc** – The length of the message in bytes. For Classic CAN dlc can be at most 8, unless *Open.ACCEPT\_LARGE\_DLC* is used. For CAN FD dlc can be one of the following 0-8, 12, 16, 20, 24, 32, 48, 64. Optional, if omitted, *dlc* is calculated from the *msg* array.

### CanBusStatistics

**class** canlib.canlib.structures.CanBusStatistics

Result from reading bus statistics using *canlib.canlib.Channel.get\_bus\_statistics*.

#### Variables

- **busLoad** (int) – The bus load, expressed as an integer in the interval 0 - 10000 representing 0.00% - 100.00% bus load.
- **errFrame** (int) – Number of error frames.
- **extData** (int) – Number of received extended (29-bit identifiers) data frames.
- **extRemote** (int) – Number of received extended (29-bit identifiers) remote frames.
- **overruns** (int) – The number of overruns detected by the hardware, firmware or driver.
- **stdData** (int) – Number of received standard (11-bit identifiers) data frames.
- **stdRemote** (int) – Number of received standard (11-bit identifiers) remote frames.

### ChannelData

**class** canlib.canlib.ChannelData(*channel\_number*)

Object for querying various information about a channel

After instantiating a *ChannelData* object with a channel number, a variety of information is available as attributes. Most attributes are named after the C constant used to retrieve the information and are found in the list below.

Other information does not follow the C implementation completely, and are documented as separate properties further down.

There is also the *raw* function, that is used internally to get all information and can also be used to interact more directly with the dll.

#### Variables

- **bus\_type** – A member of the *BusTypeGroup* enum. Not implemented in Linux.
- **card\_firmware\_rev** – A *canlib.VersionNumber* object with the version of the card's firmware.
- **card\_hardware\_rev** – A *canlib.VersionNumber* object with the version of the card's hardware.
- **card\_number** – An int with the card's number in the computer. Each card type is numbered separately.



- **card\_serial\_no** – An int with the serial number of the card, or 0 if it doesn't have a serial number.
- **card\_type** – A member of the *HardwareType* enum representing the hardware type of the card.
- **card\_upc\_no** – An *canlib.EAN* object with the EAN of the card, or None if it doesn't one.
- **chan\_no\_on\_card** – An int of the channel number on the card.
- **channel\_cap** – A *ChannelCap* object with the capabilities of the channel as flags. Also see `ChannelData.channel_cap_mask`.
- **channel\_cap\_ex** – A tuple of *ChannelCapEx* with the extended capabilities of the channel (added in v1.17).
- **channel\_cap\_mask** – A *ChannelCap* with which flags this device knows about.
- **channel\_flags** – A *ChannelFlags* object with the status of the channel as flags. Not implemented in Linux.
- **channel\_quality** – An int between 0 and 100 (inclusively) with the quality of the channel in percent of optimal quality. Not implemented in Linux.
- **clock\_info** – A *ClockInfo* object with clock characteristics for the device (added in v1.16).
- **devdescr\_ascii** – A str with the product name of the device.
- **devdescr\_unicode** – A str with the product name of the device. Not implemented in Linux.
- **device\_physical\_position** – An int with the address of the device on its underlying bus. Not implemented in Linux.
- **devname\_ascii** – A str with the current device name. Not implemented in Linux.
- **dll\_file\_version** – A *canlib.VersionNumber* with the version of the dll file.
- **dll\_filetype** – 1 if “kvalapw.dll” is used, 2 if “kvalapw2.dll”
- **dll\_product\_version** – A *canlib.VersionNumber* with the product version of the dll.
- **driver\_file\_version** – A *canlib.VersionNumber* with the version of the kernel-mode driver. Not implemented in Linux.
- **driver\_name** – A str with the name of the device driver.
- **driver\_product\_version** – A *canlib.VersionNumber* with the product version of the kernel-mode driver. Not implemented in Linux.
- **feature\_ean** – An *canlib.EAN* object with an internal EAN. This is only intended for internal use.
- **hw\_status** – Six int with hardware status codes. This is only intended for internal use.
- **is\_remote** – A bool for whether the device is currently connected as a remote device. Not implemented in Linux.
- **logger\_type** – A member of the *LoggerType* enum. Not implemented in Linux.
- **max\_bitrate** – An int with the maximum bitrate of the device. Zero means no limit on the bitrate.
- **mfgname\_ascii** – A str with the manufacturer's name.
- **mfgname\_unicode** – A str with the manufacturer's name. Not implemented in Linux.

- **remote\_host\_name** – A str with the remote host name of the device. Not implemented in Linux.
- **remote\_mac** – A str with the remote mac address of the device. Not implemented in Linux.
- **remote\_operational\_mode** – A member of the *OperationalMode* enum. Not implemented in Linux.
- **remote\_profile\_name** – A str with the remote profile name of the device. Not implemented in Linux.
- **remote\_type** – A member of the *RemoteType* enum. Not implemented in Linux.
- **roundtrip\_time** – An int with the roundtrip time measured in milliseconds. Not implemented in Linux.
- **time\_since\_last\_seen** – An int with the time in milliseconds since last communication occurred. Not implemented in Linux.
- **timesync\_enabled** – A bool for whether legacy time synchronization is enabled. Not implemented in Linux.
- **trans\_cap** – A *DriverCap* object with the capabilities of the transceiver as flags. Not implemented in Linux.
- **trans\_serial\_no** – An int with the serial number of the transceiver, or 0 if it doesn't have a serial number. Not implemented in Linux.
- **trans\_type** – A member of the *TransceiverType* enum.
- **trans\_upc\_no** – An *canlib.EAN* object with the EAN of the transceiver, or None if it doesn't have one. Not implemented in Linux.
- **ui\_number** – An int with the number associated with the device that can be displayed in the user interface. Not implemented in Linux.

**property channel\_name**

The product channel name.

Retrieves a clear text name of the channel. The name is returned as a string.

**Type** str

**property custom\_name**

The custom channel name if set, or an empty string otherwise

**Type** str

**property device\_name**

Deprecated since version 1.7.

**raw**(*item*, *ctype*=<class 'ctypes.c\_uint'>)

A raw call to `canGetChannelData`

**Parameters**

- **item** (*ChannelDataItem*) – The information to be retrieved.
- **ctype** – The ctypes type that the information should be interpreted as.

**class** `canlib.canlib.HandleData`(*channel*)

Object for querying various information about a handle

This is identical to the *ChannelData* object but it's constructor takes a `canlib.Channel` instead of a channel number.

New in version 1.13.

### Variables

- **bus\_type** – A member of the *BusTypeGroup* enum. Not implemented in Linux.
- **card\_firmware\_rev** – A *canlib.VersionNumber* object with the version of the card’s firmware.
- **card\_hardware\_rev** – A *canlib.VersionNumber* object with the version of the card’s hardware.
- **card\_number** – An int with the card’s number in the computer. Each card type is numbered separately.
- **card\_serial\_no** – An int with the serial number of the card, or 0 if it doesn’t have a serial number.
- **card\_type** – A member of the *HardwareType* enum representing the hardware type of the card.
- **card\_upc\_no** – An *canlib.EAN* object with the EAN of the card, or None if it doesn’t one.
- **chan\_no\_on\_card** – An int of the channel number on the card.
- **channel\_cap** – A *ChannelCap* object with the capabilities of the channel as flags. Also see `ChannelData.channel_cap_mask`.
- **channel\_cap\_ex** – A tuple of *ChannelCapEx* with the extended capabilities of the channel (added in v1.17).
- **channel\_cap\_mask** – A *ChannelCap* with which flags this device knows about.
- **channel\_flags** – A *ChannelFlags* object with the status of the channel as flags. Not implemented in Linux.
- **channel\_quality** – An int between 0 and 100 (inclusively) with the quality of the channel in percent of optimal quality. Not implemented in Linux.
- **clock\_info** – A *ClockInfo* object with clock characteristics for the device (added in v1.16).
- **devdescr\_ascii** – A str with the product name of the device.
- **devdescr\_unicode** – A str with the product name of the device. Not implemented in Linux.
- **device\_physical\_position** – An int with the address of the device on its underlying bus. Not implemented in Linux.
- **devname\_ascii** – A str with the current device name. Not implemented in Linux.
- **dll\_file\_version** – A *canlib.VersionNumber* with the version of the dll file.
- **dll\_filetype** – 1 if “kvalapw.dll” is used, 2 if “kvalapw2.dll”
- **dll\_product\_version** – A *canlib.VersionNumber* with the product version of the dll.
- **driver\_file\_version** – A *canlib.VersionNumber* with the version of the kernel-mode driver. Not implemented in Linux.
- **driver\_name** – A str with the name of the device driver.
- **driver\_product\_version** – A *canlib.VersionNumber* with the product version of the kernel-mode driver. Not implemented in Linux.

- **feature\_ean** – An *canlib.EAN* object with an internal EAN. This is only intended for internal use.
- **hw\_status** – Six `int` with hardware status codes. This is only intended for internal use.
- **is\_remote** – A `bool` for whether the device is currently connected as a remote device. Not implemented in Linux.
- **logger\_type** – A member of the *LoggerType* enum. Not implemented in Linux.
- **max\_bitrate** – An `int` with the maximum bitrate of the device. Zero means no limit on the bitrate.
- **mfgname\_ascii** – A `str` with the manufacturer’s name.
- **mfgname\_unicode** – A `str` with the manufacturer’s name. Not implemented in Linux.
- **remote\_host\_name** – A `str` with the remote host name of the device. Not implemented in Linux.
- **remote\_mac** – A `str` with the remote mac address of the device. Not implemented in Linux.
- **remote\_operational\_mode** – A member of the *OperationalMode* enum. Not implemented in Linux.
- **remote\_profile\_name** – A `str` with the remote profile name of the device. Not implemented in Linux.
- **remote\_type** – A member of the *RemoteType* enum. Not implemented in Linux.
- **roundtrip\_time** – An `int` with the roundtrip time measured in milliseconds. Not implemented in Linux.
- **time\_since\_last\_seen** – An `int` with the time in milliseconds since last communication occurred. Not implemented in Linux.
- **timesync\_enabled** – A `bool` for whether legacy time synchronization is enabled. Not implemented in Linux.
- **trans\_cap** – A *DriverCap* object with the capabilities of the transceiver as flags. Not implemented in Linux.
- **trans\_serial\_no** – An `int` with the serial number of the transceiver, or 0 if it doesn’t have a serial number. Not implemented in Linux.
- **trans\_type** – A member of the *TransceiverType* enum.
- **trans\_upc\_no** – An *canlib.EAN* object with the EAN of the transceiver, or `None` if it doesn’t have one. Not implemented in Linux.
- **ui\_number** – An `int` with the number associated with the device that can be displayed in the user interface. Not implemented in Linux.

**raw**(*item*, *ctype*=<class 'ctypes.c\_uint'>)

A raw call to `canGetHandleData`

#### Parameters

- **item** (*ChannelDataItem*) – The information to be retrieved.
- **ctype** – The `ctypes` type that the information should be interpreted as.

## EnvVar

```
class canlib.canlib.EnvVar(channel)
    Used to access environment variables

    class Attrib(handle=None, type_=None, size=None)

class canlib.canlib.envvar.DataEnvVar(channel, handle, name, size)
    Represent an environment variable declared as char
```

## Enumerations

### AcceptFilterFlag

```
class canlib.canlib.AcceptFilterFlag(value)
    canFILTER_SET_XXX

    NULL_MASK = 0
    SET_CODE_EXT = 5
    SET_CODE_STD = 3
    SET_MASK_EXT = 6
    SET_MASK_STD = 4
```

## Bitrate

```
class canlib.canlib.Bitrate(value)
    canBITRATE_XXX

    Predefined CAN bitrates. See BitrateFD for predefined CAN FD bitrates.

    New in version 1.17.

    BITRATE_100K = -5
        Indicate a bitrate of 100 kbit/s.

    BITRATE_10K = -9
        Indicate a bitrate of 10 kbit/s.

    BITRATE_125K = -4
        Indicate a bitrate of 125 kbit/s.

    BITRATE_1M = -1
        Indicate a bitrate of 1 Mbit/s.

    BITRATE_250K = -3
        Indicate a bitrate of 250 kbit/s.

    BITRATE_500K = -2
        Indicate a bitrate of 500 kbit/s.

    BITRATE_50K = -7
        Indicate a bitrate of 50 kbit/s.

    BITRATE_62K = -6
        Indicate a bitrate of 62 kbit/s.
```

**BITRATE\_83K = -8**

Indicate a bitrate of 83 kbit/s.

## BitrateFD

**class** canlib.canlib.**BitrateFD**(*value*)

canFD\_BITRATE\_XXX

Predefined CAN FD bitrates. Used when setting bitrates using the CAN FD protocol, see *Bitrate* for predefined CAN bitrates.

New in version 1.17.

**BITRATE\_1M\_80P = -1001**

Indicates a bitrate of 1 Mbit/s and sampling point at 80%.

**BITRATE\_2M\_80P = -1002**

Indicates a bitrate of 2 Mbit/s and sampling point at 80%.

**BITRATE\_4M\_80P = -1003**

Indicates a bitrate of 4 Mbit/s and sampling point at 80%.

**BITRATE\_500K\_80P = -1000**

Indicates a bitrate of 500 kbit/s and sampling point at 80%.

**BITRATE\_8M\_60P = -1004**

Indicates a bitrate of 8 Mbit/s and sampling point at 60%.

**BITRATE\_8M\_80P = -1005**

Indicates a bitrate of 8 Mbit/s and sampling point at 80%.

## BusTypeGroup

**class** canlib.canlib.**BusTypeGroup**(*value*)

kvBUSTYPE\_GROUP\_XXX

Bus type group. This is a grouping of the individual kvBUSTYPE\_XXX.

**INTERNAL = 4**

kvBUSTYPE\_PCI, kvBUSTYPE\_PCMCIA, ...

**LOCAL = 2**

kvBUSTYPE\_USB

**REMOTE = 3**

kvBUSTYPE\_WLAN, kvBUSTYPE\_LAN

**VIRTUAL = 1**

## ChannelCap

```

class canlib.canlib.ChannelCap(value)
    canCHANNEL_CAP_XXX

    Channel capabilities.

    Changed in version 1.8.

    BUS_STATISTICS = 2
        Can report busload etc.

    CAN_FD = 524288
        CAN-FD ISO compliant channel.

    CAN_FD_NONISO = 1048576
        CAN-FD NON-ISO compliant channel.

    DIAGNOSTICS = 268435456
        Channel has diagnostic capabilities.

    ERROR_COUNTERS = 4
        Can return error counters.

    EXTENDED_CAN = 1
        Can use extended identifiers.

    GENERATE_ERROR = 16
        Can send error frames.

    GENERATE_OVERLOAD = 32
        Can send CAN overload frame.

    IO_API = 134217728
        Channel has diagnostic capabilities.

    LIN_HYBRID = 67108864
        Channel has LIN capabilities.

    LOGGER = 8388608
        Channel has logger capabilities.

    REMOTE_ACCESS = 16777216
        Channel has remote capabilities.

    RESERVED_1 = 262144

    RESERVED_2 = 8
        Obsolete, only used by LAPcan driver

    SCRIPT = 33554432
        Channel has script capabilities.

    SILENT_MODE = 2097152
        Channel supports Silent mode.

    SIMULATED = 131072
        Simulated CAN channel.

    SINGLE_SHOT = 4194304
        Channel supports Single Shot messages.

    TXACKNOWLEDGE = 128
        Can report when a CAN messages has been transmitted.

```

**TXREQUEST = 64**  
Can report when a CAN message transmission is initiated.

**VIRTUAL = 65536**  
Virtual CAN channel.

## ChannelDataItem

**class** canlib.canlib.ChannelDataItem(*value*)

Low level helper object representing canCHANNELDATA\_XXX.

See the properties of [ChannelData](#) for how to get retrieve this data.

**BUS\_PARAM\_LIMITS = 45**

**BUS\_TYPE = 30**  
see ChannelData.bus\_type

**CARD\_FIRMWARE\_REV = 9**  
firmware revision number on the card, see ChannelData.card\_firmware\_rev

**CARD\_HARDWARE\_REV = 10**  
version of the card's hardware, see ChannelData.card\_hardware\_rev

**CARD\_NUMBER = 5**  
the card's number in the computer, see ChannelData.card\_number

**CARD\_SERIAL\_NO = 7**  
serial number of the card, or 0, see ChannelData.card\_serial\_no

**CARD\_TYPE = 4**  
hardware type of the card, see ChannelData.card\_type

**CARD\_UPC\_NO = 11**  
EAN of the card, see ChannelData.card\_upc\_no

**CHANNEL\_CAP = 1**  
capabilities of the CAN controller, see ChannelData.channel\_cap

**CHANNEL\_CAP\_EX = 47**  
see ChannelData.channel\_cap\_ex

**CHANNEL\_CAP\_MASK = 38**  
see ChannelData.channel\_cap\_mask

**CHANNEL\_FLAGS = 3**  
status of the channel as flags, see ChannelData.channel\_flags

**CHANNEL\_NAME = 13**  
Deprecated

**CHANNEL\_QUALITY = 28**  
see ChannelData.channel\_quality

**CHAN\_NO\_ON\_CARD = 6**  
local channel number on the card, see ChannelData.chan\_no\_on\_card

**CLOCK\_INFO = 46**  
see ChannelData.clock\_info

**CUST\_CHANNEL\_NAME = 39**  
see ChannelData.cust\_channel\_name



**DEVDESCR\_ASCII = 26**  
product name of the device, see `ChannelData.devdescr_ascii`

**DEVDESCR\_UNICODE = 25**  
product name of the device, see `ChannelData.devdescr_unicode`

**DEVICE\_PHYSICAL\_POSITION = 18**  
see `ChannelData.device_physical_position`

**DEVNAME\_ASCII = 31**  
see `ChannelData.devname_ascii`

**DLL\_FILETYPE = 16**  
see `ChannelData.dll_filetype`

**DLL\_FILE\_VERSION = 14**  
version of the dll file, see `ChannelData.dll_file_version`

**DLL\_PRODUCT\_VERSION = 15**  
version of the CANlib, see `ChannelData.dll_product_version`

**DRIVER\_FILE\_VERSION = 21**  
version of the driver, see `ChannelData.driver_file_version`

**DRIVER\_NAME = 27**  
device driver name, see `ChannelData.driver_name`

**DRIVER\_PRODUCT\_VERSION = 22**  
version of the CANlib, see `ChannelData.driver_product_version`

**FEATURE\_EAN = 44**  
see `ChannelData.feature_ean`

**HW\_STATUS = 43**  
see `ChannelData.hw_status`

**IS\_REMOTE = 40**  
see `ChannelData.is_remote`

**LOGGER\_TYPE = 42**  
see `ChannelData.logger_type`

**MAX\_BITRATE = 37**  
see `ChannelData.max_bitrate`

**MFGNAME\_ASCII = 24**  
manufacturer's name, see `ChannelData.mfgname_ascii`

**MFGNAME\_UNICODE = 23**  
manufacturer's name, see `ChannelData.mfgname_unicode`

**REMOTE\_HOST\_NAME = 35**  
see `ChannelData.remote_host_name`

**REMOTE\_MAC = 36**  
see `ChannelData.remote_mac`

**REMOTE\_OPERATIONAL\_MODE = 33**  
see `ChannelData.remote_operational_mode`

**REMOTE\_PROFILE\_NAME = 34**  
see `ChannelData.remote_profile_name`

**REMOTE\_TYPE = 41**  
see `ChannelData.remote_type`

**ROUNDTRIP\_TIME = 29**  
see `ChannelData.roundtrip_time`

**TIMESYNC\_ENABLED = 20**  
see `ChannelData.timesync_enabled`

**TIME\_SINCE\_LAST\_SEEN = 32**  
see `ChannelData.time_since_last_seen`

**TRANS\_CAP = 2**  
capabilities of the CAN transceiver, see `ChannelData.trans_cap`

**TRANS\_SERIAL\_NO = 8**  
serial number of the transceiver, or 0, see `ChannelData.trans_serial_no`

**TRANS\_TYPE = 17**  
transceiver type, see `ChannelData.trans_type`

**TRANS\_UPC\_NO = 12**  
EAN of the transceiver, see `ChannelData.trans_upc_no`

**UI\_NUMBER = 19**  
see `ChannelData.ui_number`

## ChannelFlags

**class** `canlib.canlib.ChannelFlags`(*value*)  
`canCHANNEL_IS_XXX`

These channel flags are used in conjunction with `ChannelDataItem.channel_flags`.

**IS\_CANFD = 4**  
Channel has been opened as CAN FD.

**IS\_EXCLUSIVE = 1**  
Channel is opened exclusively.

**IS\_LIN = 16**  
Channel has been opened as LIN.

**IS\_LIN\_MASTER = 32**  
Channel has been opened as a LIN master.

**IS\_LIN\_SLAVE = 64**  
Channel has been opened as a LIN slave.

**IS\_OPEN = 2**  
Channel is active, either opened in LIN mode or on-bus in CAN mode.

## DeviceMode

```
class canlib.canlib.DeviceMode(value)
    kvDEVICE_MODE_XXX

    INTERFACE = 0
        Device is running or should be running in interface mode.

    LOGGER = 1
        Device is running or should be running in logger mode.
```

## Driver

```
class canlib.canlib.Driver(value)
    An enumeration.

    NORMAL = 4
        The "normal" driver type (push-pull). This is the default.

    OFF = 0
        The driver is turned off. Not implemented in all types of hardware.

    SELFRECEPTION = 8
        Self-reception. Not implemented.

    SILENT = 1
        Sets the CAN controller in Silent Mode.
```

## DriverCap

```
class canlib.canlib.DriverCap(value)
    canDRIVER_CAP_XXX

    Driver (transceiver) capabilities.

    HIGHSPEED = 1
```

## EnvVarType

```
class canlib.canlib.EnvVarType(value)
    kvENVVAR_TYPE_XXX

    FLOAT = 2
        The type of the envvar is C float.

    INT = 1
        The type of the envvar is C int.

    STRING = 3
        The type of the envvar is C string.
```

## Error

**class** canlib.canlib.**Error**(*value*)

canERR\_XXX

**BUFFER\_TOO\_SMALL = -43**

Buffer provided was not large enough.

**CONFIG = -37**

Configuration Error.

**CRC = -36**

CRC error.

**DEVICE\_FILE = -33**

Device File error.

**DISK = -35**

Disk error.

**DRIVER = -12**

Driver type not supported

**DRIVERFAILED = -24**

DeviceIOControl failed, use Win32 GetLastError() to learn more

**DRIVERLOAD = -23**

Can't find or load kernel driver

**DYNAINIT = -18**

Error when initializing a DLL

**DYNALIB = -17**

A DLL seems to have wrong version

**DYNALOAD = -16**

A driver DLL can't be found or loaded

**HARDWARE = -15**

A hardware error has occurred

**HOST\_FILE = -34**

Host File error.

**INIFILE = -11**

Error in the ini-file (16-bit only)

**INTERNAL = -30**

Internal error in the driver.

**INTERRUPTED = -6**

Interrupted by signals.

**INVALID\_PASSWORD = -128**

**INVALID\_SESSION = -131**

**INVHANDLE = -10**

Handle is invalid

**IO\_CONFIG\_CHANGED = -46**

The I/O pin configuration has changed after last confirmation.

**IO\_NOT\_CONFIRMED = -45**  
The I/O pin configuration is not confirmed.

**IO\_NO\_VALID\_CONFIG = -48**  
There is no valid I/O pin configuration.

**IO\_PENDING = -47**  
The previous I/O pin value has not yet changed the output.

**IO\_WRONG\_PIN\_TYPE = -44**  
I/O pin doesn't exist or the I/O pin type doesn't match.

**LICENSE = -29**  
The license is not valid.

**MEMO\_FAIL = -38**  
Memo Error.

**NOCARD = -26**  
The card was removed or not inserted

**NOCHANNELS = -5**  
No channels available.

**NOCONFIGMGR = -25**  
Can't find req'd config s/w (e.g. CS/SS)

**NOHANDLES = -9**  
Out of handles

**NOMEM = -4**  
Out of memory.

**NOMSG = -2**  
There were no messages to read.

**NOTFOUND = -3**  
Specified device or channel not found.

**NOTINITIALIZED = -8**  
The library is not initialized.

**NOT\_AUTHORIZED = -130**

**NOT\_IMPLEMENTED = -32**  
Not implemented.

**NOT\_SUPPORTED = -19**  
Operation not supported by hardware or firmware

**NO\_ACCESS = -31**  
Access denied.

**NO\_SUCH\_FUNCTION = -129**

**PARAM = -1**  
Error in one or more parameters.

**REGISTRY = -28**  
Error (missing data) in the Registry

**RESERVED\_2 = -22**  
Reserved

**RESERVED\_5 = -20**  
Reserved

**RESERVED\_6 = -21**  
Reserved

**RESERVED\_7 = -27**  
Reserved

**SCRIPT\_FAIL = -39**  
Script Fail.

**SCRIPT\_WRONG\_VERSION = -40**  
Unsupported t program version.

**TIMEOUT = -7**  
Timeout occurred.

**TXBUFOFL = -13**  
Transmit buffer overflow

**TXE\_CONTAINER\_FORMAT = -42**  
Parsing t program failed.

**TXE\_CONTAINER\_VERSION = -41**  
Unsupported txe version.

## HardwareType

**class** canlib.canlib.**HardwareType**(*value*)  
canHWTYPE\_XXX

The following constants can be returned from *ChannelData*, using the `card_type` property. They identify the hardware type for the current channel.

---

**Note:** The members indicate a hardware type, but not necessarily a specific product. For example, `canHWTYPE_LAPCAN` is returned both for LAPcan and LAPcan II. (Use the `card_upc_no` property of *ChannelData* to obtain the UPC/EAN code for the device. This number uniquely identifies the product.)

---

**ACQUISITOR = 46**  
Kvaser Acquisitor (obsolete).

**BAGEL = 64**  
Obsolete name, use *BLACKBIRD\_V2* instead.

**BLACKBIRD = 58**  
Kvaser BlackBird.

**BLACKBIRD\_V2 = 64**  
Kvaser BlackBird v2.

**CANLINHYBRID = 84**  
Kvaser Hybrid CAN/LIN.

**CANPARI = 3**  
CANpari (obsolete).

**DINRAIL = 86**  
Kvaser DIN Rail SE400S and variants

**EAGLE = 62**  
Kvaser Eagle family.

**ETHERCAN = 70**  
Kvaser Ethercan.

**IRIS = 58**  
Obsolete name, use *BLACKBIRD* instead.

**LAPCAN = 2**  
LAPcan Family.

**LEAF = 48**  
Kvaser Leaf Family.

**LEAF2 = 80**  
Kvaser Leaf Pro HS v2 and variants.

**MEMORATOR\_II = 54**  
Kvaser Memorator Professional family.

**MEMORATOR\_LIGHT = 60**  
Kvaser Memorator Light.

**MEMORATOR\_PRO = 54**  
Kvaser Memorator Professional family.

**MEMORATOR\_PRO2 = 78**  
Kvaser Memorator Pro 5xHS and variants.

**MEMORATOR\_V2 = 82**  
Kvaser Memorator (2nd generation)

**MINIHYDRA = 62**  
Obsolete name, use *EAGLE* instead.

**MINIPCIE = 66**  
Kvaser Mini PCI Express.

**NONE = 0**  
Unknown or undefined.

**PC104\_PLUS = 50**  
Kvaser PC104+.

**PCCAN = 8**  
PCcan Family.

**PCICAN = 9**  
PCIcan Family.

**PCICANX\_II = 52**  
Kvaser PCIcanx II.

**PCICAN\_II = 40**  
PCIcan II family.

**PCIE\_V2 = 76**  
Kvaser PCIEcan 4xHS and variants.

**SIMULATED = 44**  
Simulated CAN bus for Kvaser Creator (obsolete).

**U100 = 88**  
Kvaser U100 and variants

**USBCAN = 11**  
USBcan (obsolete).

**USBCAN\_II = 42**  
USBcan II, USBcan Rugged, Kvaser Memorator.

**USBCAN\_KLINE = 68**  
USBcan Pro HS/K-Line.

**USBCAN\_LIGHT = 72**  
Kvaser USBcan Light.

**USBCAN\_PRO = 56**  
Kvaser USBcan Professional.

**USBCAN\_PRO2 = 74**  
Kvaser USBcan Pro 5xHS and variants.

**VIRTUAL = 1**  
The virtual CAN bus.

## IOControlItem

**class** canlib.canlib.IOControlItem(*value*)  
An enumeration used in [Channel.iocontrol](#).

**CLEAR\_ERROR\_COUNTERS = 5**  
Clear the CAN error counters.

**CONNECT\_TO\_VIRTUAL\_BUS = 22**  
Windows only

**DISCONNECT\_FROM\_VIRTUAL\_BUS = 23**  
Windows only

**FLUSH\_RX\_BUFFER = 10**  
Discard contents of the RX queue.

**FLUSH\_TX\_BUFFER = 11**  
Discard contents of the TX queue.

**GET\_BUS\_TYPE = 36**  
Windows only.

**GET\_CHANNEL\_QUALITY = 34**  
Read remote channel quality.

**GET\_DEVNAME\_ASCII = 37**  
Retrieve device name.

**GET\_DRIVERHANDLE = 17**  
Windows only.

**GET\_EVENTHANDLE = 14**  
Windows only.

**GET\_REPORT\_ACCESS\_ERRORS = 21**  
Current setting of access error reporting



**GET\_ROUNDTRIP\_TIME = 35**  
Round trip time in ms, for remote channel.

**GET\_RX\_BUFFER\_LEVEL = 8**  
Current receive queue, RX, level.

**GET\_THROTTLE\_SCALED = 42**  
Windows only

**GET\_TIMER\_SCALE = 12**  
Current time-stamp clock resolution in microseconds.

**GET\_TIME\_SINCE\_LAST\_SEEN = 38**  
For WLAN devices, this is the time since the last keep-alive message.

**GET\_TREF\_LIST = 39**  
Unsupported

**GET\_TXACK = 31**  
Status of Transmit Acknowledge.

**GET\_TX\_BUFFER\_LEVEL = 9**  
Current transmitt queue, TX, level.

**GET\_USB\_THROTTLE = 29**  
For internal use only.

**GET\_USER\_IOPORT = 25**  
Read IO port value.

**GET\_WAKEUP = 19**  
For internal use only.

**LIN\_MODE = 45**  
For internal use only.

**MAP\_RXQUEUE = 18**  
For internal use only.

**PREFER\_EXT = 1**  
Tells CANlib to “prefer” extended identifiers.

**PREFER\_STD = 2**  
Tells CANlib to “prefer” standard identifiers.

**RESET\_OVERRUN\_COUNT = 44**  
Reset overrun count and flags

**SET\_BRLIMIT = 43**  
Max bitrate limit can be overridden with this IOCTL.

**SET\_BUFFER\_WRAPAROUND\_MODE = 26**  
For internal use only.

**SET\_BUSON\_TIME\_AUTO\_RESET = 30**  
Enable/disable time reset at bus on.

**SET\_BYPASS\_MODE = 15**  
Not implemented.

**SET\_ERROR\_FRAMES\_REPORTING = 33**  
Windows only

**SET\_LOCAL\_TXECHO = 32**  
Turn on/off local transmit echo.

**SET\_REPORT\_ACCESS\_ERRORS = 20**  
Turn access error reporting on/off.

**SET\_RX\_QUEUE\_SIZE = 27**  
Windows only.

**SET\_THROTTLE\_SCALED = 41**  
Windows only

**SET\_TIMER\_SCALE = 6**  
Set time-stamp clock resolution in microseconds, default 1000.

**SET\_TXACK = 7**  
Enable/disable Transmit Acknowledge.

**SET\_TXRQ = 13**  
Turn transmit requests on or off.

**SET\_USB\_THROTTLE = 28**  
For internal use only.

**SET\_USER\_IOPORT = 24**  
Set IO port to value.

**SET\_WAKEUP = 16**  
For internal use only.

**TX\_INTERVAL = 40**  
Minimum CAN message transmit interval

## LEDAction

**class** canlib.canlib.LEDAction(*value*)

kvLED\_ACTION\_XXX

The following can be used together with *canlib.canlib.Channel.flashLeds*.

Changed in version 1.18: Added LEDs 4 through 11 (needs CANlib v5.19+)

**ALL\_LEDS\_OFF = 1**  
Turn all LEDs off.

**ALL\_LEDS\_ON = 0**  
Turn all LEDs on.

**LED\_0\_OFF = 3**  
Turn LED 0 off.

**LED\_0\_ON = 2**  
Turn LED 0 on.

**LED\_10\_OFF = 23**  
Turn LED 10 off.

**LED\_10\_ON = 22**  
Turn LED 10 on.

**LED\_11\_OFF = 25**  
Turn LED 11 off.

**LED\_11\_ON = 24**  
Turn LED 11 on.

**LED\_1\_OFF = 5**  
Turn LED 1 off.

**LED\_1\_ON = 4**  
Turn LED 1 on.

**LED\_2\_OFF = 7**  
Turn LED 2 off.

**LED\_2\_ON = 6**  
Turn LED 2 on.

**LED\_3\_OFF = 9**  
Turn LED 3 off.

**LED\_3\_ON = 8**  
Turn LED 3 on.

**LED\_4\_OFF = 11**  
Turn LED 4 off.

**LED\_4\_ON = 10**  
Turn LED 4 on.

**LED\_5\_OFF = 13**  
Turn LED 5 off.

**LED\_5\_ON = 12**  
Turn LED 5 on.

**LED\_6\_OFF = 15**  
Turn LED 6 off.

**LED\_6\_ON = 14**  
Turn LED 6 on.

**LED\_7\_OFF = 17**  
Turn LED 7 off.

**LED\_7\_ON = 16**  
Turn LED 7 on.

**LED\_8\_OFF = 19**  
Turn LED 8 off.

**LED\_8\_ON = 18**  
Turn LED 8 on.

**LED\_9\_OFF = 21**  
Turn LED 9 off.

**LED\_9\_ON = 20**  
Turn LED 9 on.

## LoggerType

```
class canlib.canlib.LoggerType(value)
    kvLOGGER_TYPE_XXX

    Logger type, returned when using ChannelData.logger_type.

    NOT_A_LOGGER = 0
    V1 = 1
    V2 = 2
```

## MessageFlag

```
class canlib.canlib.MessageFlag(value)
    Message information flags

    The following flags can be returned from Channel.read et al, or passed to Channel.write.

    This enum is a combination of flags for messages, CAN FD messages, and message errors. Normal messages
    flags are the flags covered by MSG_MASK, CAN FD message flags are those covered by FDMSG_MASK, and message
    errors are those covered by MSGERR_MASK.
```

---

**Note:** *DFD*, *BRS*, and *ESI* require CAN FD.

*RTR* cannot be set for CAN FD messages.

Not all hardware platforms can detect the difference between hardware overruns and software overruns, so your application should test for both conditions. You can use the symbol *OVERRUN* for this purpose.

---

```
ABL = 67108864
    Single shot message was not sent because arbitration was lost.

BIT = 49152
    Any bit error.

BIT0 = 16384
    Sent dominant bit, read recessive bit

BIT1 = 32768
    Sent recessive bit, read dominant bit

BRS = 131072
    Message is sent/received with bit rate switch (CAN FD)

BUSERR = 63488
    Any RX error.

CRC = 8192
    CRC error.

EDL = 65536
    obsolete

ERROR_FRAME = 32
    Message represents an error frame.

ESI = 262144
    Sender of the message is in error passive mode (CAN FD)
```

**EXT = 4**  
Message has an extended (29-bit) identifier.

**FDL = 65536**  
Message is a CAN FD message.

**FDMSG\_MASK = 16711680**  
obsolete

**FORM = 4096**  
Form error.

**HW\_OVERRUN = 512**  
Hardware buffer overrun.

**MSGERR\_MASK = 65280**  
Used to mask the non-error bits

**MSG\_MASK = 255**  
Used to mask the non-info bits.

**NERR = 16**  
NERR was active during the message (TJA1054 hardware)

**OVERRUN = 1536**  
Any overrun condition.

**RTR = 1**  
Message is a remote request.

**SINGLE\_SHOT = 16777216**  
Message is Single Shot, try to send once, no retransmission.

**STD = 2**  
Message has a standard (11-bit) identifier.

**STUFF = 2048**  
Stuff error.

**SW\_OVERRUN = 1024**  
Software buffer overrun.

**TXACK = 64**  
Message is a TX ACK (msg has really been sent)

**TXNACK = 33554432**  
Message is a failed Single Shot, message was not sent.

**TXRQ = 128**  
Message is a TX REQUEST (msg was transferred to the chip)

**WAKEUP = 8**  
Message is a WAKEUP message, Single Wire CAN.

## Notify

**class** canlib.canlib.**Notify**(*value*)

canNOTIFY\_XXX

These notify flags are used in *Channel.set\_callback* to indicate different kind of events.

**BUSONOFF = 32**

Notify on bus on/off status changed

**ENVVAR = 16**

An environment variable was changed by a script. Note that you will not be notified when an environment variable is updated from the Canlib API.

**ERROR = 4**

CAN bus error notification

**NONE = 0**

Turn notifications off.

**REMOVED = 64**

Notify on device removed

**RX = 1**

CAN message reception notification

**STATUS = 8**

CAN chip status change

**TX = 2**

CAN message transmission notification

## Open

**class** canlib.canlib.**Open**(*value*)

Flags used in the flags argument to *canlib.openChannel()*.

**ACCEPT\_LARGE\_DLC = 512**

DLC can be greater than 8.

The channel will accept CAN messages with DLC (Data Length Code) greater than 8. If this flag is not used, a message with DLC > 8 will always be reported or transmitted as a message with DLC = 8. When the *ACCEPT\_LARGE\_DLC* flag is used, the message will be sent and/or received with the true DLC, which can be at most 15. The length of the message is always at most 8.

**ACCEPT\_VIRTUAL = 32**

Allow opening of virtual channels as well as physical channels.

**CAN\_FD = 1024**

The channel will use the CAN FD protocol, ISO compliant.

This also means that messages with *MessageFlag.FDF*, *MessageFlag.BRS* and *MessageFlag.ESI* can now be used.

**CAN\_FD\_NONISO = 2048**

The channel will use the CAN FD NON-ISO protocol.

Use this if you want to configure the can controller to be able to communicate with a can controller designed prior to the release of the CAN FD ISO specification.

Non ISO mode implies:

1. The stuff bit counter will not be included in the frame format.
2. Initial value for CRC17 and CRC21 will be zero.

This also means that messages with *MessageFlag.FDF*, *MessageFlag.BRS* and *MessageFlag.ESI* can now be used.

#### **EXCLUSIVE = 8**

Don't allow sharing of this CANlib channel between applications.

Two or more applications can share the same CAN channel. You can, for example, have one application send messages on the bus and another application that just monitors the bus. If this is not desired (for performance or other reasons) you can open an exclusive handle to a channel. This means that no other application can open a handle to the same channel.

#### **NOFLAG = 0**

#### **NO\_INIT\_ACCESS = 256**

Don't open the handle with init access.

Note: A handle opened without init access will still set default bitrate when going on bus, if no other handle has opened the channel with init access at the time of the buson.

#### **OVERRIDE\_EXCLUSIVE = 64**

Open the channel even if it is opened for exclusive access already.

#### **REQUIRE\_EXTENDED = 16**

This flag causes two things to happen:

1. The call will fail if the specified circuit doesn't allow extended CAN (CAN 2.0B).
2. If no frame-type flag is specified in a call to *Channel.write()*, it is assumed that extended CAN should be used.

#### **REQUIRE\_INIT\_ACCESS = 128**

Fail the call if the channel cannot be opened with init access.

Init access means that the CAN handle can set bit rate and CAN driver mode. At most one CAN handle may have init access to any given channel. If you try to set the bit rate or CAN driver mode for a handle to which you don't have init access, the call will silently fail (i.e. *canOK* is returned although the call had no effect), unless you enable "access error reporting" by using *Channel.IOControlItem.SET\_REPORT\_ACCESS\_ERRORS*. Access error reporting is by default off. Init access is the default.

## OperationalMode

**class** canlib.canlib.**OperationalMode**(value)

canCHANNEL\_OPMODE\_XXX

Current WLAN operational mode.

#### **ADH = 4**

Adhoc mode

#### **INFRASTRUCTURE = 2**

Infrastructure mode

#### **NONE = 1**

Not applicable, or unknown mode.

#### **RESERVED = 3**

Reserved

## RemoteType

```
class canlib.canlib.RemoteType(value)
    kvREMOTE_TYPExxx

    Remote type, returned when using canCHANNELDATA_REMOTE_TYPE

    LAN = 2
    NOT_REMOTE = 0
    WLAN = 1
```

## ScriptRequest

```
class canlib.canlib.ScriptRequest(value)
    kvSCRIPT_REQUEST_TEXT_xxx

    These defines are used in kvScriptRequestText() for printf message subscribe/unsubscribe.

    ALL_SLOTS = 255
    SUBSCRIBE = 2
    UNSUBSCRIBE = 1
```

## ScriptStatus

```
class canlib.canlib.ScriptStatus(value)
    Status of t program

    New in version 1.6.

    Changed in version 1.7: Is now based on IntFlag instead of IntEnum

    IDLE = 0
    LOADED = 1
    RUNNING = 2
```

## ScriptStop

```
class canlib.canlib.ScriptStop(value)
    An enumeration.

    FORCED = -9
    NORMAL = 0
```



## Stat

**class** canlib.canlib.Stat(*value*)

canSTAT\_XXX

The following circuit status flags are returned by *Channel.readStatus*. Note that more than one flag might be set at any one time.

---

**Note:** Usually both canSTAT\_HW\_OVERRUN and canSTAT\_SW\_OVERRUN are set when overrun has occurred. This is because the kernel driver can't see the difference between a software overrun and a hardware overrun. So the code should always test for both types of overrun using the flag.

---

**BUS\_OFF = 2**

The circuit is Off Bus

**ERROR\_ACTIVE = 8**

The circuit is error active.

**ERROR\_PASSIVE = 1**

The circuit is error passive

**ERROR\_WARNING = 4**

At least one error counter > 96

**HW\_OVERRUN = 512**

There has been at least one HW buffer overflow

**OVERRUN = 1536**

For convenience.

**RESERVED\_1 = 64**

**RXERR = 256**

There has been at least one RX error of some sort

**RX\_PENDING = 32**

There are messages in the receive buffer

**SW\_OVERRUN = 1024**

There has been at least one SW buffer overflow

**TXERR = 128**

There has been at least one TX error

**TX\_PENDING = 16**

There are messages pending transmission

## TransceiverType

**class** canlib.canlib.TransceiverType(*value*)

Transceiver (logical) types

The following constants can be returned from *canGetChannelData()*, using the *canCHANNEL-DATA\_TRANS\_TYPE* item code. They identify the bus transceiver type for the channel specified in the call to *canGetChannelData*.

---

**Note:** If the type starts with a number T\_ has been prepended to the name.

They indicate a hardware type, but not necessarily a specific circuit or product.

---

**CANFD = 22**

**CANFD\_LIN = 24**

HYBRID CAN-FD/LIN

**DNOPTO = 3**

Optoisolated 82C251

**EVA = 7**

**FIBER = 8**

82c251 with fibre extension

**K = 10**

K-line, without CAN.

**K251 = 9**

K-line + 82c251

**KONE = 20**

**LIN = 19**

**LINX\_J1708 = 66**

**LINX\_K = 68**

**LINX\_LIN = 64**

**LINX\_LS = 72**

**LINX\_SWC = 70**

**RS485(i.e. J1708) = 18**

RS485 (i.e. J1708)

**SWC = 6**

AU5790

**SWC\_OPTO = 12**

AU5790 with optical isolation

**SWC\_PROTO = 5**

AU5790 prototype

**TT = 13**

B10011S Truck-And-Trailer

**T\_1041 = 16**

TJA1041

**T\_1041\_OPTO = 17**

TJA1041 with optical isolation

**T\_1050 = 14**

TJA1050

**T\_1050\_OPTO = 15**

TJA1050 with optical isolation

**T\_1054\_OPTO = 11**

TJA1054 with optical isolation

**T\_251 = 1**  
82c251

**T\_252 = 2**  
82c252, TJA1053, TJA1054

**UNKNOWN = 0**  
Unknown or undefined

**W210 = 4**

## TxeDataItem

**class** canlib.canlib.**TxeDataItem**(*value*)

An enumeration.

**COMPILER\_VERSION = 2**

The three part version number of the compiler used to create the compiled script file (.txe).

**DATE = 3**

Compilation date in Coordinated Universal Time (UTC) of the compiled script file (.txe).

Contents: 0. Year, 1. Month, 2. Day, 3. Hour, 4. Minute, 5. Second.

**DESCRIPTION = 4**

Description of the compiled script file (.txe).

**FILE\_VERSION = 1**

The three part version number of the compiled script file (.txe) file format.

**IS\_ENCRYPTED = 7**

Non-zero value if the compiled script file (.txe) contents is encrypted.

**SIZE\_OF\_CODE = 6**

The size of the compiled code in the .txe file.

**SOURCE = 5**

The name followed by the content of each unencrypted source file

## IOControl

**class** canlib.canlib.**IOControl**(*channel*)

Helper object for using canIoCtl

Provides a variety of functionality, some of which are represented as attributes of this object and some as functions. See the respective entries below for more information.

### Variables

- **brlimit** – An `int` with the hardware bitrate limit, or zero for the device's default. Write-only.
- **bus\_type** – A member of the `BusTypeGroup` enum. Not implemented in Linux. Read-only.
- **buson\_time\_auto\_reset** – A `bool` for whether the CAN clock is reset at bus-on. Not implemented in Linux. Write-only.
- **channel\_quality** – An `int` between 0 and 100 (inclusively) with the quality of the channel in percent. Not implemented in Linux. Read-only.

- **devname\_ascii** – A str with the current device name. Not implemented in Linux. Read-only.
- **driverhandle** – The windows handle related to the CANlib handle. Not implemented in Linux. Read-only.
- **error\_frames\_reporting** – A bool for whether error frames are reported. Not implemented in Linux. Write-only.
- **eventhandle** – An int with the windows event handle. Not implemented in Linux. Read-only.
- **local\_txecho** – A bool for whether local transmit echo is turned on. Write-only.
- **report\_access\_errors** – A bool for whether Access Reporting is turned on
- **roundtrip\_time** – An int with the roundtrip time in milliseconds. Not implemented in Linux. Read-only.
- **rx\_buffer\_level** – An int with the approximate receive queue level. Read-only.
- **rx\_queue\_size** – An int with the size of the receive buffer. Can only be used off-bus. Not implemented in Linux. Write-only.
- **throttle\_scaled** – An int between 0 and 100 (inclusively) where 0 means the device is very responsive but generates more CPU load and 100 means the device is less responsive with less CPU load. Note that not all devices support setting this. Some hardware will accept this command but neglect it. Not implemented in Linux.
- **time\_since\_last\_seen** – An int with the time in milliseconds since the last communication occurred. Not implemented in Linux. Read-only.
- **timer\_scale** – An int with the time-stamp clock resolution in microseconds.
- **tx\_buffer\_level** – An int with the approximate transmit queue level. Read-only.
- **tx\_interval** – An int with the number of microseconds with the minimum CAN message transmit interval.
- **txack** – 0 for Transmit Acknowledges off, 1 for Transmit Acknowledges on, and 2 for Transmit Acknowledges off, even for the driver’s internal usage (this will break parts of the library).
- **txrq** – A bool for whether Transmit Requests are turned on. Write-only.

**clear\_error\_counters()**

Tells CANlib to clear the CAN error counters. CAN error counters on device side are NOT updated. It is recommended to use [reset\\_overrun\\_count](#) to reset overrun status. Not implemented in Linux.

**connect\_to\_virtual\_bus(value)**

Connects the channel to the virtual bus number value.

**disconnect\_from\_virtual\_bus(value)**

Disconnects the channel from the virtual bus number value.

**flush\_rx\_buffer()**

Discard the current contents of the RX queue.

**flush\_tx\_buffer()**

Discard the current contents of the TX queue.

**prefer\_ext()**

Tells CANlib to assume [MessageFlag.EXT](#) when sending messages if neither [MessageFlag.EXT](#) or [MessageFlag.STD](#) is specified. Not implemented in Linux.

**prefer\_std()**

Tells CANlib to assume *MessageFlag.STD* when sending messages if neither *MessageFlag.EXT* or *MessageFlag.STD* is specified. Not implemented in Linux.

**reset\_overrun\_count()**

Resets overrun count and flags.

**raw(item, value=None, ctype=<class 'ctypes.c\_uint'>)**

A raw call to `canIoctl`

**Parameters**

- **item** (*IOControlItem*) – The “function code” to be passed to `canIoctl`.
- **value** – The value sent to `canIoctl` or `None` if no value should be given. Must be compatible with the `ctype` argument.
- **ctype** – The `ctypes` type that should be used to when sending the value argument and when interpreting the result of `canIoctl`.

**I/O pin**

Experimental support for accessing IO-pins on sub modules of the Kvaser DIN Rail SE 400S and variants that was added to CANlib v5.26.

New in version 1.8.

**AddonModule**

**class** `canlib.canlib.iopin.AddonModule`(*module\_type, fw\_version=None, serial=None, first\_pin\_index=None*)

Contains information about one add-on module

**Parameters**

- **module\_type** (*ModuleType*) – The type of the add-on module.
- **sw\_version** (*canlib.VersionNumber*) – The software version in the add-on module.
- **serial** (*int*) – The serial number of the add-on module.
- **first\_index** (*int*) – The index of the add-on modules first pin.

New in version 1.9.

**issubset(spec)**

Check if current attributes are fulfilling attributes in *spec*.

Any attribute in *spec* that is set to `None` is automatically considered fulfilled.

The `fw_version` attribute is considered fulfilled when `self.fw_version >= spec.fw_version`.

This can be used to check if a specific module fulfills a manually created specification:

```
>>> module_spec = [iopin.AddonModule(module_type=iopin.ModuleType.DIGITAL)]
... config = iopin.Configuration(channel)
>>> config.modules
[AddonModule(module_type=<ModuleType.DIGITAL: 1>, fw_
↪version=VersionNumber(major=2, minor=5, release=None, build=None), ↪
↪serial=2342), first_pin_index=0]
```

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```
>>> config.issubset(module_spec)
True

>>> module_spec = [iopin.AddonModule(
    module_type=iopin.ModuleType.DIGITAL,
    fw_version=VersionNumber(major=3, minor=1),
    serial=2342)]

>>> config.issubset(module_spec)
False

>>> module_spec = [
    iopin.AddonModule(module_type=iopin.ModuleType.ANALOG),
    iopin.AddonModule(module_type=iopin.ModuleType.DIGITAL,
        fw_version=VersionNumber(major=3, minor=1),
        serial=2342)]

>>> config.issubset(module_spec)
False
```

## AnalogIn

**class** canlib.canlib.iopin.**AnalogIn**(*channel, pin*)

Bases: *canlib.canlib.iopin.IoPin*

**property hysteresis**

The hysteresis in Volt for analog input pin

**property lp\_filter\_order**

The low-pass filter order for analog input pin

**property value**

Voltage level on the Analog input pin

## AnalogOut

**class** canlib.canlib.iopin.**AnalogOut**(*channel, pin*)

Bases: *canlib.canlib.iopin.IoPin*

**property value**

Voltage level on the Analog output pin

## Configuration

**class** `canlib.canlib.iopin.Configuration(channel)`

Contains I/O pins and the `canlib.Channel` to find them on

Creating this object may take some time depending on the number of I/O pins available on the given `canlib.Channel`.

**Parameters** `channel (Channel)` – The channel where the discovery of I/O pins should take place.

### Variables

- **io\_pins** (list(`IoPin`)) – All discovered I/O pins.
- **modules** (list(`AddonModule`)) – All included add-on-modules.
- **pin\_names** (list(`str`)) – List of label I/O pin names.
- **(dict(str (pin\_index) – int))**: Dictionary with I/O pin label name as key, and pin index as value.

To create an `iopin.Configuration` you need to supply the `canlib.Channel`, which is where we look for I/O pins:

```
>>> from canlib.canlib import iopin
... from canlib import canlib, Device, EAN
... device = Device.find(ean=EAN('01059-8'), serial=225)
... channel = canlib.openChannel(device.channel_number(), canlib.Open.EXCLUSIVE)
... config = iopin.Configuration(channel)
```

Now we can investigate a specific pin by index:

```
>>> config.pin(index=80)
Pin 80: <PinType.ANALOG: 2> <Direction.OUT: 8> bits=12 range=0.0-10.0 (<ModuleType.
↳ANALOG: 2>)
```

It is also possible to find the label name from the index and vice versa for a pin, as well as access the pin using the label name:

```
>>> config.name(80)
'4:A01'

>>> config.index('4:A01')
80

>>> config.pin(name='4:A01')
Pin 80: <PinType.ANALOG: 2> <Direction.OUT: 8> bits=12 range=0.0-10.0 (<ModuleType.
↳ANALOG: 2>)
```

**Note:** A configuration needs to be confirmed using `iopin.Configuration.confirm` (which calls `Channel.io_confirm_config`) before accessing pin values:

```
>>> config.pin(name='4:A01').value = 4
Traceback (most recent call last):
  File "<stdin>", line 1, in <module>
  File "...\\canlib\\canlib\\iopin.py", line 271, in value
  File "...\\canlib\\canlib\\dll.py", line 94, in _error_check
```

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```

    raise can_error(result)
canlib.canlib.exceptions.IoPinConfigurationNotConfirmed: I/O pin configuration is
↪not confirmed (-45)
I/O pin configuration is not confirmed (-45)

>>> config.confirm()

>>> config.pin(name='4:A01').value = 4

```

A *Configuration* may be compared with an expected ordered list of *AddonModule* before confirming using *AddonModule.issubset*

Changed in version 1.9: *Configuration.modules* is now an attribute, containing an ordered list of *AddonModule* objects.

**confirm()**

Confirm current configuration

Convenience function that calls *Channel.io\_confirm\_config*.

**index(name)**

Return index for pin with the given label name

**issubset(spec)**

Check if attributes of modules in self is fulfilled by given spec

This is a convenience method that calls *AddonModule.issubset* on all modules given by *self.modules* which can be used to check if the current configuration fulfills a manually created specification:

```

>>> config = iopin.Configuration(channel)
>>> config_spec = [iopin.AddonModule(module_type=iopin.ModuleType.ANALOG),
                  iopin.AddonModule(module_type=iopin.ModuleType.DIGITAL,
                                     fw_version=VersionNumber(major=3, minor=1),
                                     serial=2342)]

>>> config.issubset(config_spec)
False

```

New in version 1.9.

**name(index)**

Return label name for pin with given index

**pin(index=None, name=None)**

Return *IoPin* object using index or name

Either *index* or *name* must be given, if both are given, the name will be used.

**Parameters**

- **index** (*int*) – I/O pin index
- **name** (*str*) – I/O pin name



## DigitalIn

**class** canlib.canlib.iopin.**DigitalIn**(*channel, pin*)

Bases: [canlib.canlib.iopin.IoPin](#)

**property high\_low\_filter**

Filter time in micro seconds when a digital pin goes from HIGH to LOW

**property low\_high\_filter**

Filter time in micro seconds when a digital pin goes from LOW to HIGH

**property value**

Value on digital input pin (0 or 1)

## DigitalOut

**class** canlib.canlib.iopin.**DigitalOut**(*channel, pin*)

Bases: [canlib.canlib.iopin.IoPin](#)

**property value**

Value on digital output pin (0 or 1)

## DigitalValue

**class** canlib.canlib.iopin.**DigitalValue**(*value*)

Enum used digital values

**HIGH** = 1

**LOW** = 0

## Direction

**class** canlib.canlib.iopin.**Direction**(*value*)

Enum used for values in [Info](#)

**IN** = 4

Input

**OUT** = 8

Output

## Info

**class** canlib.canlib.iopin.**Info**(*value*)

Enum used internally in [IoPin](#) for calls to [kvIoPinGetInfo](#) and [kvIoPinSetInfo](#)

**AI\_HYSTERESIS** = 11

The hysteresis in volt.

The hysteresis in volt for an analog input pin, i.e. the amount the input have to change before the sampled value is updated.

0.0 - 10.0, default 0.3

**AI\_LP\_FILTER\_ORDER = 10**

The low-pass filter order for an analog input pin.

0 - 16, default 3 (sample time is 1 ms)

**DIRECTION = 2**

One of *Direction*

**DI\_HIGH\_LOW\_FILTER = 9**

Time when a digital input pin goes from LOW to HIGH.

Filter time in micro seconds when a digital input pin goes from LOW to HIGH.

Range: 0 - 65000, Default 5000 us

**DI\_LOW\_HIGH\_FILTER = 8**

Time when a digital input pin goes from HIGH to LOW.

Filter time in micro seconds when a digital input pin goes from HIGH to LOW. Range: 0 - 65000, Default 5000 us

**FW\_VERSION = 16**

Software version number of the submodule the pin belongs to. Read-only.

**MODULE\_NUMBER = 14**

The module number the pin belongs to. The number starts from 0. Read-only.

**MODULE\_TYPE = 1**

One of *ModuleType*

**NUMBER\_OF\_BITS = 5**

Resolution in number of bits. Read-only.

**PIN\_TYPE = 4**

One of *PinType*

**RANGE\_MAX = 7**

A float that contains the upper range limit in volts. Read-only.

**RANGE\_MIN = 6**

A float that contains the lower range limit in volts. Read-only.

**SERIAL\_NUMBER = 15**

Serial number of the submodule the pin belongs to. Read-only.

## IoPin

```
class canlib.canlib.iopin.IoPin(channel, pin)
```

Base class of I/O ports

**property direction**

Pin direction (Read-only)

Type *Direction*

**property fw\_version**

Firmware version in module (Read-only)

Type *VersionNumber*

**property hysteresis**

Base class does not implement hysteresis attribute

**property lp\_filter\_order**  
Base class does not implement lp\_filter\_order attribute

**property module\_type**  
Type of module (Read-only)  
Type *ModuleType*

**property number\_of\_bits**  
Resolution in number of bits (Read-only)  
Type int

**property pin\_type**  
Type of pin (Read-only)  
Type *PinType*

**property range\_max**  
Upper range limit in volts (Read-only)  
Type float

**property range\_min**  
Lower range limit in volts (Read-only)  
Type float

**property serial**  
Module serial number (Read-only)  
Type int

**property value**  
Base class does not implement value attribute

## ModuleType

**class** canlib.canlib.iopin.**ModuleType**(*value*)  
Enum used for return values in kvIoPinGetInfo

**ANALOG = 2**  
Analog Add-on (4 inputs, 4 outputs).

**DIGITAL = 1**  
Digital Add-on (16 inputs, 16 outputs).

**INTERNAL = 4**  
Internal Digital module (1 input, 1 output).

**RELAY = 3**  
Relay Add-on (8 inputs, 8 outputs).

## PinType

```
class canlib.canlib.iopin.PinType(value)
    Enum used for values in Info

    ANALOG = 2
    DIGITAL = 1
    RELAY = 3
```

## Relay

```
class canlib.canlib.iopin.Relay(channel, pin)
    Bases: canlib.canlib.iopin.IoPin

    property value
        Value on relay, 0 for off, 1 for on
```

## Script Container

### SourceElement

```
class canlib.canlib.SourceElement(name, contents)

    property contents
        Alias for field number 1

    property name
        Alias for field number 0
```

## Txe

```
class canlib.canlib.Txe(path)
    The Txe class provides an interface to compiled t programs (.txe) files.
    New in version 1.6.

    property compiler_version
        t compiler version number.
        Type VersionNumber

    property date
        Compilation date and time.
        Type datetime.datetime

    property description
        t program description.
        Type str

    property file_version
        .txe binary format version number.
        Type VersionNumber
```

**property is\_encrypted**

true if the source and byte-code sections of the .txe binary have been encrypted.

**Type** bool

**property path**

Path of compiled t program (.txe) file.

**Type** str

**property size\_of\_code**

Size in bytes of byte-code section.

**Type** int

**property source**

Yields name and content of the source files used to create the .txe binary file.

If the t source files used to create the .txe binary was included at compilation time, then this attribute will yield *SourceElement* tuples containing the name and content of the individual source files.

Sample usage:

```
for name, contents in txe.source:
    print('file name:{}'.format(name, contents))
```

If the source and byte-code sections of the .txe binary have been encrypted then it's not possible to parse the source list and a *TxeFileIsEncrypted* exception will be raised.

If no source files have been included in the .txe binary then an empty iterator is returned.

**Yields** *SourceElement* – Name and contents tuple.

**Raises** *TxeFileIsEncrypted* – If the source and byte-code sections of the .txe binary have been encrypted.

**Miscellaneous****dllversion()**

canlib.canlib.dllversion()

Get the CANlib DLL version number

**Parameters** None

Returns a *canlib.BetaVersionNumber* if the CANlib DLL is marked as beta (preview), otherwise returns *canlib.VersionNumber*.

Changed in version 1.6.

### getErrorText()

`canlib.canlib.getErrorText(error_code)`  
Return error text for supplied error\_code

### getNumberOfChannels()

`canlib.canlib.getNumberOfChannels(driver=False)`  
Get number of available CAN channels.

Returns the number of available CAN channels in the computer. The virtual channels are included in this number.

In order to manually re-enumerate connected devices when a device has been added or removed, use [enumerate\\_hardware](#).

**Parameters** None

**Returns** *chanCount (int)* – Number of available CAN channels

### getVersion()

`canlib.canlib.getVersion()`  
Get the CANlib DLL version number as a str  
Deprecated since version 1.5: Use [dllversion](#) instead.

### prodversion()

`canlib.canlib.prodversion()`  
Get the CANlib Product version number

**Parameters** None

Returns a [canlib.BetaVersionNumber](#) if the CANlib driver/DLL is marked as beta (preview), otherwise returns [canlib.VersionNumber](#).

New in version 1.6.

### initializeLibrary()

`canlib.canlib.initializeLibrary()`  
Initialize CANlib library

---

**Note:** This initializes the driver and must be called before any other function in the CANlib DLL is used. This is handled in most cases by the Python wrapper. If you want to trigger a re-enumeration of connected devices, you should call [enumerate\\_hardware](#) instead.

---

Any errors encountered during library initialization will be “silent” and an appropriate error code will be returned later on when an API call that requires initialization is called.

## reinitializeLibrary()

canlib.canlib.**reinitializeLibrary**()

Reinitializes the CANlib driver.

Convenience function that calls *unloadLibrary* and *initializeLibrary* in succession.

**Warning:** Calling *reinitializeLibrary* invalidates every canlib-object. Use at your own risk. You most likely would like to call *enumerate\_hardware*() instead.

## enumerate\_hardware()

canlib.canlib.**enumerate\_hardware**()

Enumerate connected Kvaser devices and rebuild list of available channels

**Returns** The number of CAN channels enumerated.

New in version 1.13.

## ScriptText

**class** canlib.canlib.**ScriptText**(*text, slot, time, flags*)

Text returned by *Channel.scriptGetText*

Subclass of built-in `str`, so it can be used just like a normal string.

It also has the following attributes:

### Parameters

- **text** (`str`) – Text content.
- **slot** (`int`) – Which script-slot the text came from.
- **time** (`int`) – Timestamp of when the text was printed.
- **flags** (*Stat*) – Any status flags associated with the text.

New in version 1.7.

## translateBaud()

canlib.canlib.**translateBaud**(*freq*)

Translate bitrate constant

This function translates the *canlib.Bitrate* and *canlib.BitrateFD* enums to their corresponding bus parameter values.

**Parameters** `freq` – Any of the predefined *canlib.Bitrate* or *canlib.BitrateFD*.

**Returns** A *BitrateSetting* object containing the actual values of frequency, tseg1, tseg2 etc.

## unloadLibrary()

canlib.canlib.unloadLibrary()

Unload CANlib

Unload canlib and release all internal handles.

**Warning:** Calling *unloadLibrary* invalidates every canlib-object. Use at your own risk.

## 1.6.7 kvadblib

### Exceptions

#### KvdError

**exception** canlib.kvadblib.KvdError

Base class for exceptions raised by the kvadblib dll

#### KvdBufferTooSmall

**exception** canlib.kvadblib.KvdBufferTooSmall

Bases: *canlib.kvadblib.exceptions.KvdError*

The buffer provided was not large enough to contain the requested data.

New in version 1.10.

**status = -14**

#### KvdDbFileParse

**exception** canlib.kvadblib.KvdDbFileParse

Bases: *canlib.kvadblib.exceptions.KvdError*

The database file could not be parsed.

More information can be obtained by running *get\_last\_parse\_error*.

New in version 1.10.

**status = -15**

#### KvdErrInParameter

**exception** canlib.kvadblib.KvdErrInParameter

Bases: *canlib.kvadblib.exceptions.KvdError*

One or more of the parameters in call is erroneous.

**status = -3**



### KvdInUse

**exception** canlib.kvadblib.KvdInUse

Bases: *canlib.kvadblib.exceptions.KvdError*

An item is in use.

**status** = -13

### KvdNoAttribute

**exception** canlib.kvadblib.KvdNoAttribute

Bases: *canlib.kvadblib.exceptions.KvdNotFound*

No attribute found.

**status** = -10

### KvdNoMessage

**exception** canlib.kvadblib.KvdNoMessage

Bases: *canlib.kvadblib.exceptions.KvdNotFound*

No message was found.

**status** = -4

### KvdNoSignal

**exception** canlib.kvadblib.KvdNoSignal

Bases: *canlib.kvadblib.exceptions.KvdNotFound*

No signal was found.

**status** = -5

### KvdNoNode

**exception** canlib.kvadblib.KvdNoNode

Bases: *canlib.kvadblib.exceptions.KvdNotFound*

Could not find the database node.

**status** = -9

## KvdNotFound

**exception** canlib.kvadblib.KvdNotFound

Bases: *canlib.kvadblib.exceptions.KvdError*

## KvdOnlyOneAllowed

**exception** canlib.kvadblib.KvdOnlyOneAllowed

Bases: *canlib.kvadblib.exceptions.KvdError*

An identical kvaDbLib structure already exists.

Only one database at a time can be used).

**status = -11**

## SignalNotFound

**exception** canlib.kvadblib.SignalNotFound(*text*)

Bases: *canlib.exceptions.CanlibException*

## Attribute

**class** canlib.kvadblib.Attribute(*db, handle*)

Factory for creating different types of attributes.

This class is also the base class and thus contains all common properties.

**property name**

Name of attribute.

**Type** str

**property value**

Attribute value

## Attribute Definitions

### AttributeDefinition

**class** canlib.kvadblib.AttributeDefinition(*db, handle, definition=None*)

Factory for creating different types of attribute definitions.

This class is also the base class and thus contains all common properties.

**property name**

Name of attribute definition.

**Type** str

**property owner**

Return attribute owner

**Type** *AttributeOwner*

## DefaultDefinition

**class** canlib.kvadblib.**DefaultDefinition**(*default*)  
 Attribute definition for attributes defined using only default.

**property default**  
 Alias for field number 0

## EnumDefaultDefinition

**class** canlib.kvadblib.**EnumDefaultDefinition**(*default, enums*)  
 Attribute definition for enumeration attributes.

Holds a definition using default and key-value pairs.

**property default**  
 Alias for field number 0

**property enums**  
 Alias for field number 1

## EnumDefinition

**class** canlib.kvadblib.**EnumDefinition**(*db, handle, definition=None*)  
 Definition of an enum attribute.

**Parameters**

- **db** (*Dbc*) – Database that holds attribute definitions
- **definition** (*EnumDefaultDefinition*) – default value and enums

**add\_enum\_definition**(*enums*)  
 Add enum definitions.

**Parameters** *enums* (*dict*) – key - value pair(s), example: {'empty': 0}

**property definition**  
 Return attribute definition

Changed in version 1.6.

**Type** *EnumDefaultDefinition*

## FloatDefinition

**class** canlib.kvadblib.**FloatDefinition**(*db, handle, definition=None*)  
 Definition of a float attribute.

**Parameters**

- **db** (*Dbc*) – Database that holds attribute definitions
- **definition** (*MinMaxDefinition*) – Min, max and default values

**property definition**  
 Attribute definition

**Type** *MinMaxDefinition*

## IntegerDefinition

**class** canlib.kvadbllib.**IntegerDefinition**(*db, handle, definition=None*)

Definition of an integer attribute.

### Parameters

- **db** (*Dbc*) – Database that holds attribute definitions
- **definition** (*MinMaxDefinition*) – Min, max and default values

**property definition**

Return attribute definition

Type *MinMaxDefinition*

## MinMaxDefinition

**class** canlib.kvadbllib.**MinMaxDefinition**(*default, min, max*)

Attribute definition for attributes defined using default, min and max.

**property default**

Alias for field number 0

**property max**

Alias for field number 2

**property min**

Alias for field number 1

## StringDefinition

**class** canlib.kvadbllib.**StringDefinition**(*db, handle, definition=None*)

Definition of a string attribute.

### Parameters

- **db** (*Dbc*) – Database that holds attribute definitions
- **definition** (*DefaultDefinition*) – default value

**property definition**

Return attribute definition

Type *DefaultDefinition*

## dbc

dbc.DATABASE\_FLAG\_J1939 = 1

## Dbc

**class** canlib.kvadbllib.Dbc(*filename=None, name=None, protocol=None*)

Holds a dbc database.

There are three ways to create a database:

1. To load data from an existing database file, only set filename to the database filename.
2. To add an empty database, set only name.
3. To load data from an existing database file and give it a new name, set name to the new name and filename to the existing database filename.

Either a name or a filename must be given.

### Parameters

- **filename** (*str, optional*) – The existing database file is read.
- **name** (*str, optional*) – The database name will be set.

**Raises** *KvdDbFileParse* – If the database file can't be parsed.

When parsing a database file fails, *get\_last\_parse\_error* can be called:

```
try:
    kvadbllib.Dbc(filename="database.dbc")
except kvadbllib.KvdDbFileParse:
    print(kvadbllib.get_last_parse_error())
```

Changed in version 1.10: *Dbc* now raises specific errors depending on the situation.

### attribute\_definitions()

Return a generator over all database attribute definitions.

### attributes()

Return a generator over all database attributes.

New in version 1.6.

### close()

Close an open database handle.

### delete\_attribute(*name*)

Delete attribute from database.

New in version 1.6.

### delete\_attribute\_definition(*name*)

Delete attribute definition from database.

New in version 1.7.

### delete\_message(*message*)

Delete message from database.

**Parameters** *message* (*Message*) – message to be deleted

### delete\_node(*node*)

Delete node from database.

**Parameters** *node* (*Node*) – node to be deleted

**property flags**

Get the database flags.

E.g. DATABASE\_FLAG\_J1939

**get\_attribute\_definition\_by\_name**(*name*)

Find attribute definition using name.

**Parameters** *name* (*str*) – name of attribute definition

Returns an attribute definition object depending on type, e.g. if the type is `AttributeType.INTEGER`, an `IntegerAttributeDefinition` is returned.

**get\_attribute\_value**(*name*)

Return attribute value

If the attribute is not set on the database, we return the attribute definition default value.

New in version 1.6.

**get\_message**(*id=None, name=None*)

Find message by id or name

If both id and name is given, both must match.

Note that bit 31 of the id indicates if the message has an extended id or not.

**Parameters**

- **id** (*int*) – message id to look for
- **name** (*str*) – message name to look for

**Returns** *Message*

**Raises** *KvdNoMessage* – If no match was found, or if none of *id* and *name* were given.

**get\_message\_by\_id**(*id, flags*)

Find message by id.

**Parameters**

- **id** (*int*) – message id to look for
- **flags** (*int*) – message flags, e.g. `kvadblib.MessageFlag.EXT` (Note that `kvadblib.MessageFlag.EXT != canlib.MessageFlag.EXT`)

**Returns** *Message*

**Raises** *KvdNoMessage* – If no match was found.

**get\_message\_by\_name**(*name*)

Find message by name

**Parameters** *name* (*str*) – message name to look for

**Returns** *Message*

**Raises** *KvdNoMessage* – If no match was found.

**get\_message\_by\_pgn**(*can\_id*)

Find message using the PGN part of the given CAN id.

---

**Note:** The *can\_id* must have the *MessageFlag.EXT* flag bit set (bit 31, 0x80000000)

```
dbc = kvadblib.Dbc("My_j1939_database.dbc")
can_id = 0xff4200
can_id |= kvadblib.MessageFlag.EXT
dbc.get_message_by_pgn(can_id)
```

**Parameters** `can_id` (*int*) – CAN id containing PGN to look for

**Returns** *Message*

**Raises** *KvdNoMessage* – If no match was found.

New in version 1.18.

**get\_node\_by\_name** (*name*)

Find node by name

**Parameters** `name` (*str*) – node name to look for

**Returns** *Node*

**Raises** *KvdNoNode* – If no match was found.

**interpret** (*frame*, *j1939=False*)

Interprets a given *canlib.Frame* object, returning a *BoundMessage*.

**messages** (*show\_all=True*)

Return a generator of all database messages.

If you would like to omit the special message ‘VECTOR\_\_INDEPENDENT\_SIG\_MSG’, which is used to collect removed signals under, set `show_all` to `False` or use the *Dbc* iterator directly:

```
db = kvadblib.Dbc(filename='mydb.dbc')
for message in db:
    print(msg)
```

**Parameters** `show_all` (*bool*) – If true, all messages, including any special message such as ‘VECTOR\_\_INDEPENDENT\_SIG\_MSG’ will be returned

Changed in version 1.8: Added argument `show_all`.

**property name**

The current database name (read-only)

**Type** *str*

**new\_attribute\_definition** (*name*, *owner*, *type*, *definition*)

Create a new attribute definition in the database.

The owner specify where the attribute is applicable, e.g. *AttributeOwner.MESSAGE* specifies that this attribute is only applicable on messages (*Message*).

**Parameters**

- **name** (*str*) – a unique name.
- **owner** (*AttributeOwner*) – the owner type

**Returns** *AttributeDefinition*

**new\_message** (*name*, *id*, *flags=0*, *dlc=None*, *comment=None*)

Create a new message in the database.

**Parameters**

- **name** (*str*) – name of message
- **id** (*int*) – message id
- **flags** (*int, optional*) – message flags, e.g. `kvadblib.MessageFlag.EXT`

**Returns** *Message*

**new\_node**(*name, comment=None*)

Create a new node in the database.

**Parameters**

- **name** (*str*) – name of message
- **comment** (*str, optional*) – message comment

**Returns** *Node*

**node\_in\_signal**(*node, signal*)

Check if signal has been added to node.

**Returns** *True* – signals contains node *False*: otherwise

**nodes**()

Return a generator containing all database nodes.

**property protocol**

The database protocol

**Type** *ProtocolType*

**set\_attribute\_value**(*name, value*)

Set value of attribute *name* on database.

If no attribute called *name* is set on database, attach a database attribute from the database attribute definition first.

New in version 1.6.

**write\_file**(*filename*)

Write a database to file.

**Parameters** **filename** (*str*) – file to write database to

**get\_last\_parse\_error()**

`canlib.kvadblib.get_last_parse_error()`

Can be used to get the specific reason why *KvdDbFileParse* was raised.

**Returns** *str* – Error message from the parser.

New in version 1.10.



## Enumerations

### AttributeOwner

```

class canlib.kvadblib.AttributeOwner(value)
    An enumeration.

    DB = 1
        Database owner

    ENV = 5
        Environment owner

    INVALID = 0
        Invalid owner

    MESSAGE = 2
        Message owner

    NODE = 3
        Node owner

    SIGNAL = 4
        Signal owner

```

### AttributeType

```

class canlib.kvadblib.AttributeType(value)
    An enumeration.

    ENUM = 4

    FLOAT = 3

    INTEGER = 1

    INVALID = 0

    STRING = 5

```

### Error

```

class canlib.kvadblib.Error(value)
    kvaDbErr_xxx

    BUFFER_TOO_SMALL = -14
        The buffer provided was not large enough to contain the requested data.

    DATABASE_INTERNAL = -8
        An internal error occurred in the database handler.

    DB_FILE_OPEN = -7
        Could not open the database file.

    DB_FILE_PARSE = -15
        Could not parse the database file

    FAIL = -1
        General failure.

```

**INTERNAL = -6**  
An internal error occurred in the library.

**IN\_USE = -13**  
An item is in use

**NO\_ATTRIB = -10**  
No attribute found

**NO\_DATABASE = -2**  
No database was found.

**NO\_MSG = -4**  
No message was found.

**NO\_NODE = -9**  
Could not find the database node.

**NO\_SIGNAL = -5**  
No signal was found.

**ONLY\_ONE\_ALLOWED = -11**  
An identical kvaDbLib structure already exists (and only one database at a time can be used).

**PARAM = -3**  
One or more of the parameters in call is erroneous.

**WRONG\_OWNER = -12**  
Wrong owner for attribute

## MessageFlag

**class** canlib.kvadblib.**MessageFlag**(*value*)  
An enumeration.

**EXT = 2147483648**  
Message is an extended CAN message

**J1939 = 1**  
Message uses J1939 protocol

**WAKEUP = 2**  
Message is a wakeup frame, currently not used

## ProtocolType

**class** canlib.kvadblib.**ProtocolType**(*value*)  
An enumeration.

**AFDX = 7**

**BEAN = 5**

**CAN = 0**

**CANFD = 9**

**ETHERNET = 6**

**FLEXRAY = 4**

**J1708 = 8**  
**LIN = 2**  
**MOST = 3**  
**UNKNOWN = 10**  
 Unknown or not specified protocol  
**VAN = 1**

### SignalByteOrder

**class** canlib.kvadblib.**SignalByteOrder**(*value*)  
 An enumeration.  
**INTEL = 0**  
**MOTOROLA = 1**

### SignalMultiplexMode

**class** canlib.kvadblib.**SignalMultiplexMode**(*value*)  
 An enumeration.  
**MUX\_INDEPENDENT = -1**  
 Multiplex mode value of an independent signal  
**MUX\_SIGNAL = -2**  
 Multiplex mode value of a multiplexer signal  
**SIGNAL = 0**

### SignalType

**class** canlib.kvadblib.**SignalType**(*value*)  
 An enumeration.  
**DOUBLE = 4**  
 Double, strictly 64 bit long  
**ENUM\_SIGNED = 101**  
**ENUM\_UNSIGNED = 102**  
**FLOAT = 3**  
 Float, strictly 32 bit long  
**INVALID = 0**  
 Invalid representation  
**SIGNED = 1**  
 Signed integer  
**UNSIGNED = 2**  
 Unsigned integer

## Frame Box

### FrameBox

**class** canlib.kvadbllib.**FrameBox**(db, messages=())

Helper class for sending signals

This class allows sending signals without worrying about what message they are defined in. It does this by binding a message and all its signals to the same *canlib.Frame* object.

Objects are created by giving them a *Dbc* database, and optionally a list of messages (either names or *Message* objects):

```
db = Dbc(...)
framebox = FrameBox(db, messages=('Msg0', 'Msg1'))
```

Messages can also be added after instantiation with *add\_message*:

```
framebox.add_message('Msg0', 'Msg1')
```

Then setting signal values for any added message is done with:

```
framebox.signal('Sig0').phys = 7
framebox.signal('Sig1').phys = 20
```

Once all values are set, they can easily be sent via the channel *channel* with:

```
for frame in framebox.frames():
    channel.write(frame)
```

Any *Framebox* methods that return messages requires the message to have been added to the *framebox*, either with the *messages* constructor argument or with *add\_message*. Likewise, any methods that return signals require the signal's message to have been added.

**add\_message**(*message*)

Add a message to the *framebox*

The message will be available for all future uses of *FrameBox.message* and *FrameBox.messages*, and all its signals will be available for uses of *FrameBox.signal* and *FrameBox.signals*.

The message argument can either be a message name, or a *canlib.kvadbllib.Message* object.

**frames**()

Iterate over all frames of the signals/messages from this *FrameBox*

**message**(*name*)

Retrieves a message by name

Returns a *BoundMessage* that shares its *canlib.Frame* object with its child signals.

**messages**()

Iterator over all messages that this *FrameBox* is aware of

**signal**(*name*)

Retrieves a signal by name

Returns a *BoundSignal* that shares its *canlib.Frame* object with its parent message and sibling signals.

**signals**()

Iterator over all signals that this *FrameBox* is aware of

## BoundMessage

**class** canlib.kvadbllib.**BoundMessage**(*message, frame*)  
 A CAN data object that manipulates data through signals.

## BoundSignal

**class** canlib.kvadbllib.**BoundSignal**(*signal, frame*)

**property is\_enum**

Whether this signal is an enum-signal

New in version 1.7.

**Type** bool

**property name**

Signal's name string

**Type** str

**property phys**

Signal's physical value

**Type** int or float

**property raw**

Signal's raw value

**Type** int

**property unit**

Signal's unit string

**Type** str

**property value**

Signal's value

If the signal is an enum-signal (i.e. the signal has a defined value table), then the enum name is returned if found, otherwise the signals raw value (*raw*) is returned. If the signal is not an enum-signal, the signals physical value (*phys*) is returned.

New in version 1.7.

## Message

**class** canlib.kvadbllib.**Message**(*db, handle, name=None, id=None, flags=None, dlc=None, comment=None*)  
 Database message, holds signals.

**asframe()**

Creates a Frame object with empty data matching this message

**attributes()**

Return a generator over all message attributes.

**bind**(*frame=None*)

Bind this message to a frame

Creates a new BoundMessage object representing this message bound to the given Frame object, or a new Frame object if `frame` is `None`.

**property comment**

Comment message

**Type** `str`

**delete\_attribute**(*name*)

Delete attribute from message.

**delete\_signal**(*signal*)

Delete signal from message.

**Parameters** `signal` (*Signal*) – signal to be deleted

**property dlc**

The message dlc

**Type** `int`

**property flags**

The message flags

**Type** *MessageFlag*

**get\_attribute\_value**(*name*)

Return attribute value

If the attribute is not set on the message, we return the attribute definition default value.

Changed in version 1.18: When an EnumAttribute is not set, the default value will now be returned as `int` (instead of `EnumValue` with empty *name*).

**get\_signal**(*name*)

Find signal in message by name.

**get\_signal\_by\_name**(*name*)

Find signal in message by name.

**property id**

The message identifier

**Type** `int`

**property name**

The message name

**Type** `str`

**new\_signal**(*name*, *type*=*SignalType.UNSIGNED*, *byte\_order*=*SignalByteOrder.INTEL*,  
*mode*=*SignalMultiplexMode.SIGNAL*, *representation*=*None*, *size*=*None*, *scaling*=*None*,  
*limits*=*None*, *unit*=*None*, *comment*=*None*, *enums*=*None*)

Create and add a new signal to the message.

**property qualified\_name**

The qualified message name

Returns database and message names separated by a dot.

**Type** `str`

**property send\_node**

The send node for this message.

**Type** *Node*

**set\_attribute\_value**(*name, value*)

Set value of attribute 'name' on message.

If no attribute called 'name' is set on message, attach a message attribute from the database attribute definition first.

**signals**()

Return a generator of all signals in message.

## Node

**class** canlib.kvadbllib.**Node**(*db, handle, name=None, comment=None*)

Database Node

**attributes**()

Return a generator over all message attributes.

**property comment**

The node's comment

**Type** str

**delete\_attribute**(*name*)

Delete attribute from node.

**get\_attribute\_value**(*name*)

Return attribute value

If the attribute is not set on the message, we return the attribute definition default value.

**property name**

The node's name

**Type** str

**set\_attribute\_value**(*name, value*)

Set value of attribute 'name' on node.

If no attribute called 'name' is set on node, attach a node attribute from the database attribute definition first.

## Signals

### EnumSignal

**class** canlib.kvadbllib.**EnumSignal**(*db, message, sh, name=None, type=None, byte\_order=None, mode=None, size=None, scaling=None, limits=None, unit=None, comment=None, enums=None*)

Database signal of type enum, holds meta data about a signal.

Changed in version 1.17: default settings `byte_order=SignalByteOrder.INTEL` and `mode=SignalMultiplexMode.SIGNAL` chaged to `None`.

**add\_enum\_definition**(*enums*)

Add enums dictionary to definition.

**property enums**

Signal enum definition dictionary

**Type** dict

## Signal

**class** canlib.kvadbllib.**Signal**(*db, message, sh, name=None, type=None, byte\_order=None, mode=None, representation=None, size=None, scaling=None, limits=None, unit=None, comment=None*)

Database signal, holds meta data about a signal

**add\_node**(*node*)

Add receiving node to signal.

**attributes**()

Return a generator over all signal attributes.

**bind**(*frame=None*)

Bind this signal to a frame

Creates a new BoundSignal object representing this signal bound to the given Frame object, or a new Frame object if *frame* is None..

**property byte\_order**

Get the signal byte order encoding.

**Type** *SignalByteOrder*

**property comment**

Get the signal comment.

**Type** *str*

**data\_from**(*can\_data, phys=None, raw=None*)

Convert a raw or physical value into CAN data bytes.

**delete\_attribute**(*name*)

Delete attribute from signal.

**get\_attribute\_value**(*name*)

Return attribute value

If the attribute is not set on the signal, we return the attribute definition default value.

**property limits**

Get message min and max values

**Type** *ValueLimits*

**property mode**

**property name**

Get the signal name.

**Type** *str*

**nodes**()

Return a generator over all receiving nodes of the signal.

**phys\_from**(*can\_data*)

Return signals physical value from data

**property qualified\_name**

Get the qualified signal name.

Returns database, message and signal names separated by dots.

**Type** *str*



**raw\_from**(*can\_data*)

Return signals raw value from data

**remove\_node**(*node*)

Remove receiving node from signal.

**property scaling**

Get the signals factor and offset

Type *ValueScaling*

**set\_attribute\_value**(*name, value*)

Set value of attribute 'name' on signal.

If no attribute called 'name' is set on signal, attach a signal attribute from the database attribute definition first.

**property size**

Get the signals startbit and length

Type *ValueSize*

**property type**

Get the signal representation type.

Type *SignalType*

**property unit**

Get the signal unit

Type *str*

## ValueLimits

**class** canlib.kvadblib.**ValueLimits**(*min, max*)

**property max**

Alias for field number 1

**property min**

Alias for field number 0

## ValueScaling

**class** canlib.kvadblib.**ValueScaling**(*factor, offset*)

**property factor**

Alias for field number 0

**property offset**

Alias for field number 1

## ValueSize

**class** canlib.kvadblib.**ValueSize**(*startbit, length*)

**property length**

Alias for field number 1

**property startbit**

Alias for field number 0

## Miscellaneous

### bytes\_to\_dlc()

canlib.kvadblib.**bytes\_to\_dlc**(*num\_bytes, protocol*)  
Convert number of bytes to DLC for given protocol.

### dlc\_to\_bytes()

canlib.kvadblib.**dlc\_to\_bytes**(*dlc, protocol*)  
Convert DLC to number of bytes for given protocol.

### dllversion()

canlib.kvadblib.**dllversion**()  
Get the kvaDbLib DLL version number as a `VersionNumber`

### get\_protocol\_properties()

canlib.kvadblib.**get\_protocol\_properties**(*prot*)  
Get the signal protocol\_properties.

## 1.6.8 kvamemolibxml

### Exceptions

#### KvaError

**exception** canlib.kvamemolibxml.**KvaError**

Base class for exceptions raised by the kvamemolibxml library

Looks up the error text in the kvamemolibxml dll and presents it together with the error code.

## Confiurations

### Configuration

**class** canlib.kvameolibxml.**Configuration**(*xml=None, lif=None*)

Configuration data for Kvaser devices

It is usually preferred to create objects of this class with one of the functions:

- `load_xml`
- `load_xml_file`
- `load_lif`
- `load_lif_file`

The XML and param.lif representation of this configuration can be accessed with the `xml` and `lif` attributes, respectively.

Two `Configuration` objects can be tested for equality:

```
config1 == config2
```

This will test whether the objects are equivalent: whether they have the same param.lif representation.

Finally, the configuration can be validated with `Configuration.validate`:

```
errors, warnings = configuration.validate()
for error in errors:
    print(error)
for warning in warnings:
    print(warning)
if errors:
    raise ValueError("Invalid configuration")
```

#### **property** lif

The param.lif representation of this configuration

**Type** bytes

#### **validate**()

Validate this configuration

Validates the XML representation of this configuration, and returns a tuple (`errors`, `warnings`) where `errors` is a list of `ValidationError` and `warnings` is a list `ValidationWarning`.

#### **property** xml

The XML representation of this configuration

**Type** str

### load\_lif()

canlib.kvamemolibxml.load\_lif(lif\_bytes)

Create a *Configuration* from a param.lif bytes

**Parameters** lif\_bytes (bytes) – Binary configuration in param.lif format

### load\_lif\_file()

canlib.kvamemolibxml.load\_lif\_file(filepath)

Like *load\_lif* but takes a path to a file containing the lif configuration

### load\_xml()

canlib.kvamemolibxml.load\_xml(xml\_string)

Create a *Configuration* from an xml string

**Parameters** xml\_string (str) – XML configuration

### load\_xml\_file()

canlib.kvamemolibxml.load\_xml\_file(filepath)

Like *load\_lif* but takes a path to a file containing the XML configuration

## ValidationMessage

**class** canlib.kvamemolibxml.ValidationMessage(code, text)

Validation code and message.

#### Parameters

- **code** (int) – Validation status code.
- **text** (str) – Validation message.

#### property code

Alias for field number 0

#### property text

Alias for field number 1

## ValidationErrorMessage

**class** canlib.kvamemolibxml.ValidationErrorMessage(code, text)

An error found during validation

## ValidationWarningMessage

**class** canlib.kvamemolibxml.**ValidationWarningMessage**(*code, text*)  
 A warning found during validation

## Enumerations

### Error

**class** canlib.kvamemolibxml.**Error**(*value*)  
 An enumeration.

**ATTR\_NOT\_FOUND** = -3

Failed to find an attribute in a node

**ATTR\_VALUE** = -4

The attribute value is not correct, e.g. whitespace after a number.

**DTD\_VALIDATION** = -11

The XML settings do not follow the DTD.

**ELEM\_NOT\_FOUND** = -5

Could not find a required element

**FAIL** = -1

Generic error

**INTERNAL** = -20

Internal errors, e.g. null pointers.

**OK** = 0

OK

**POSTFIXEXPR** = -9

The trigger expression could not be parsed

**SCRIPT\_ERROR** = -12

t-script related errors, e.g. file not found.

**VALUE\_CONSECUTIVE** = -8

The values are not consecutive; usually idx attributes

**VALUE\_RANGE** = -6

The value is outside the allowed range

**VALUE\_UNIQUE** = -7

The value is not unique; usually idx attributes

**XML\_PARSER** = -10

The XML settings contain syntax errors.

**classmethod from\_number**(*number*)

Create *Error* object from number.

If the number is not defined in the class, return the number instead. This is used in order to be forward compatible with new codes in the dll.

New in version 1.19.

## ValidationError

**class** canlib.kvameolibxml.ValidationError(*value*)

An enumeration.

**ABORT** = -2

Too many errors, validation aborted.

**DISK\_FULL\_STARTS\_LOG** = -7

A trigger on disk full starts the logging.

**ELEMENT\_COUNT** = -13

Too many or too few elements of this type.

**EXPRESSION** = -16

A general trigger expression found during parsing.

**FAIL** = -1

Generic error.

**MULTIPLE\_EXT\_TRIGGER** = -5

There are more than one external trigger defined.

**MULTIPLE\_START\_TRIGGER** = -6

There are more than one start up trigger defined.

**NUM\_OUT\_OF\_RANGE** = -8

A numerical value is out of range.

**OK** = 0

OK

**PARSER** = -14

A general error found during parsing.

**SCRIPT** = -15

A general t-script error found during parsing.

**SCRIPT\_CONFLICT** = -12

More than one active script is set as 'primary'.

**SCRIPT\_NOT\_FOUND** = -9

A t-script file could not be opened.

**SCRIPT\_TOO\_LARGE** = -10

A t-script is too large for the configuration.

**SCRIPT\_TOO\_MANY** = -11

Too many active t-scripts for selected device.

**SILENT\_TRANSMIT** = -3

Transmit lists used in silent mode.

**UNDEFINED\_TRIGGER** = -4

An undefined trigger is used in an expression.

**classmethod** from\_number(*number*)

Create *ValidationError* object from number.

If the number is not defined in the class, return the number instead. This is used in order to be forward compatible with new codes in the dll.

New in version 1.19.

## ValidationWarning

**class** canlib.kvamemolibxml.**ValidationWarning**(*value*)

An enumeration.

**ABORT = -100**

Too many warnings, validation aborted.

**DISK\_FULL\_AND\_FIFO = -102**

A trigger on disk full used with FIFO mode.

**IGNORED\_ELEMENT = -103**

This XML element was ignored.

**MULTIPLE\_EXT\_TRIGGER = -104**

Using more than one external trigger requires firmware version 3.7 or better.

**NO\_ACTIVE\_LOG = -101**

No active logging detected.

**classmethod** **from\_number**(*number*)

Create *ValidationWarning* from number.

If the number is not defined in the class, return the number instead. This is used in order to be forward compatible with new codes in the dll.

New in version 1.19.

## Miscellaneous

### dllversion()

canlib.kvamemolibxml.**dllversion**()

Get the kvaMemoLibXML DLL version number.

**Returns** *canlib.VersionNumber*

### kvaBufferToXml()

canlib.kvamemolibxml.**kvaBufferToXml**(*conf\_lif*)

Convert a buffer containing param.lif to XML settings.

Scripts from the param.lif will be written to current working directory.

**Parameters** **conf\_lif** (str) – Buffer containing param.lif to convert.

**Returns** str – Buffer containing converted XML settings.

### **kvaXmlToBuffer()**

`canlib.kvamemolibxml.kvaXmlToBuffer(conf_xml)`

Convert XML settings to param.lif buffer.

**Parameters** `conf_xml` (str) – XML settings to convert.

**Returns** str – Buffer containing converted param.lif.

### **kvaXmlToFile()**

`canlib.kvamemolibxml.kvaXmlToFile(xml_filename, binary_filename)`

Convert XML file to binary configuration file.

**Parameters**

- `xml_filename` (str) – Filename of file containing the XML settings.
- `binary_filename` (str) – Filename of binary configuration.

### **kvaXmlValidate()**

`canlib.kvamemolibxml.kvaXmlValidate(conf_xml)`

Validate a buffer with XML settings.

**Parameters** `conf_xml` (str) – string containing the XML settings to validate.

**Returns**

tuple – containing

- int: Number of XML validation errors.
- int: Number of XML validation warnings.

### **xmlGetLastError()**

`canlib.kvamemolibxml.xmlGetLastError()`

Get the last error message (if any).

**Returns**

tuple – containing

- str: Error message associated with the error code.
- *Error*: Error code.

Changed in version 1.19: Returned error code is now an enum.



## xmlGetValidationError()

canlib.kvamemolibxml.xmlGetValidationError()

Get validation errors (if any).

Call after kvaXmlValidate() until return status is KvaXmlValidationStatusOK.

### Returns

tuple – containing

- **int**: Validation error status code.
- **str**: Validation error status message.

Changed in version 1.19: Returned status code is now an enum.

## xmlGetValidationStatusCount()

canlib.kvamemolibxml.xmlGetValidationStatusCount()

Get the number of validation statuses (if any).

Call after kvaXmlValidate().

### Returns

tuple – containing

- **int**: Number of XML validation errors.
- **int**: Number of XML validation warnings.

## xmlGetValidationWarning()

canlib.kvamemolibxml.xmlGetValidationWarning()

Get validation warnings (if any).

Call after kvaXmlValidate() until return status is KvaXmlValidationStatusOK.

### Returns

tuple – containing

- **int**: Validation warning status code.
- **str**: Validation warning status message.

Changed in version 1.19: Returned status code is now an enum.

## 1.6.9 kvllib

### Exceptions

#### KvlibError

**exception** canlib.kvllib.KvlibError

Bases: *canlib.exceptions.DllException*

Base class for exceptions raised by the kvllib module.

Looks up the error text in the kvllib dll and presents it together with the error code and the wrapper function that triggered the exception.

### KvlcEndOfFile

**exception** canlib.kvllib.KvlcEndOfFile

Bases: *canlib.kvllib.exceptions.KvlcError*

Exception used when kvllib returns *Error.EOF*.

Exception used when end of file is reached on input file.

**status** = -3

### KvlcFileExists

**exception** canlib.kvllib.KvlcFileExists

Bases: *canlib.kvllib.exceptions.KvlcError*

Exception used when kvllib returns *Error.FILE\_EXISTS*.

File exists, set *Property.OVERWRITE* to overwrite

New in version 1.17.

**status** = -6

### KvlcNotImplemented

**exception** canlib.kvllib.KvlcNotImplemented

Bases: *canlib.kvllib.exceptions.KvlcError*, *NotImplementedError*

Exception used when kvllib returns *Error.NOT\_IMPLEMENTED*.

**status** = -4

### Converter

**class** canlib.kvllib.Converter(*filename, file\_format*)

A kvllib converter

This class wraps all kvllib functions related to converters, and saves you from keeping track of a handle and passing that to the functions.

*kvlibCreateConverter* and *kvlibDeleteConverter* are not wrapped as they are called when Converter objects are created and deleted, respectively. However, if it is necessary to force the converter to write its files, *flush* can be used to simulate destroying and recreating the converter object.

#### Parameters

- **filename** (*string*) – Name of output file
- **file\_format** (*FileFormat* | *WriterFormat*) – A supported output format

---

**Note:** No more than 128 converters can be open at the same time.

---

Changed in version 1.18: The `file_format` parameter now accepts *WriterFormat* as well.

**IsDataTruncated()**

**IsOutputFilenameNew()**

**IsOverrunActive()**

**addDatabaseFile**(*filename, channel\_mask*)

Add a database file.

Converters with the property *Property.SIGNAL\_BASED* will match events against all entries in the database and write signals to the output file.

**attachFile**(*filename*)

Attach file to be included in the output file.

E.g. used to add a database or a movie to the output.

Note that the output format must support the property *Property.ATTACHMENTS*.

**convertEvent()**

Convert next event.

Convert one event from input file and write it to output file.

**eventCount()**

Get estimated number of events left.

Get the estimated number of remaining events in the input file. This can be useful for displaying progress during conversion.

**feedLogEvent**(*event*)

Feed one event to the converter.

Used when reading log files directly from device.

**feedNextFile()**

Prepare for new file

Notify the converter that next event in `kvlcFeedLogEvent()` will come from another file. Used when reading log files directly from device.

E.g. use this function with `KVLC_FILE_FORMAT_MEMO_LOG` when using `KVMLIB` to read events from a Kvaser Memorator connected to USB.

New in version 1.18.

**flush()**

Recreate the converter so changes are saved to disk

Converters do not write changes to disk until they are deleted. This method deletes and recreates the underlying C converter, without needing to recreate the Python object.

**getDlcMismatch()**

Return a dictionary with id, DLC with number of mismatched messages

If any DLC mismatch occurred during conversion (which can be seen using *isDlcMismatch*) this function returns a dictionary with the tuple message id and message DLC as key, and the number of times that triggered the mismatch as value.

**getOutputFilename()**

Get the filename of the current output file.

**getProperty**(*wr\_property*)

Get current value for a writer property.

**Parameters** `wr_property` (*Property*) – Writer property to be set

**getPropertyDefault**(*wr\_property*)

Get default value for a writer property.

**isDataTruncated**()

Get truncation status.

Truncation occurs when the selected output converter can't write all bytes in a data frame to file. This can happen if CAN FD data is extracted to a format that only supports up to 8 data bytes, e.g. *FileFormat.KME40*.

Truncation can also happen if *Property.LIMIT\_DATA\_BYTES* is set to limit the number of data bytes in output.

Returns True if data has been truncated

**isDlcMismatch**()

Get DLC mismatch status.

DLC mismatch occurs when a CAN id is found in the database but the DLC differs from the DLC in the message.

**isOutputFilenameNew**()

Check if the converter has created a new file.

This is only true once after a new file has been created. Used when splitting output into multiple files.

**isOverrunActive**()

Get overrun status.

Overruns can occur during logging with a Memorator if the bus load exceeds the logging capacity. This is very unusual, but can occur if a Memorator runs complex scripts and triggers.

**isPropertySupported**(*wr\_property*)

Check if specified `wr_property` is supported by the current format.

Returns True if the property is supported by the current format.

**Parameters** `wr_property` (*int*) – Any one of the defined `PROPERTY_XXX`

**nextInputFile**(*filename*)

Select next input file.

**resetDlcMismatch**()

Reset DLC mismatch status.

**resetOverrunActive**()

Reset overrun status.

**resetStatusTruncated**()

Reset data truncation status.

**setInputFile**(*filename*, *file\_format*)

Select input file.

**Parameters**

- **filename** (*string*) – Name of input file
- **file\_format** (*FileFormat | ReaderFormat*) – A supported input format

Changed in version 1.16: The `file_format` parameter now accepts *ReaderFormat* as well.

Changed in version 1.18: If `filename` is `None`, the format for *feedLogEvent* is set.

**setProperty**(*wr\_property*, *value*)

Set a property value.

**Parameters** *wr\_property* (*Property*) – Writer property to be set

## Enumerations

### ChannelMask

**class** canlib.kvlclib.**ChannelMask**(*value*)

Masking channels

The *ChannelMask* is used in *Converter.addDatabaseFile* to indicate which channels to use.

**FIVE** = 16

**FOUR** = 8

**ONE** = 1

**THREE** = 4

**TWO** = 2

## Error

**class** canlib.kvlclib.**Error**(*value*)

An enumeration.

**BUFFER\_SIZE** = -15

Supplied buffer too small to hold the result.

**CONVERTING** = -14

Call failed since conversion is running.

**EOF** = -3

End of input file reached.

**FAIL** = -1

Generic error.

**FILE\_ERROR** = -5

File I/O error.

**FILE\_EXISTS** = -6

Output file already exists.

**FILE\_TOO\_LARGE** = -10

File size too large for specified format.

**INTERNAL\_ERROR** = -7

Unhandled internal error.

**INVALID\_LOG\_EVENT** = -30

Event is unknown to converter.

**MIXED\_ENDIANESS** = -33

Wrong data type in MDF.

**NOT\_IMPLEMENTED** = -4

Not implemented.

**NO\_FREE\_HANDLES = -12**  
Too many open KvlcHandle handles.

**NO\_INPUT\_SELECTED = -13**  
Missing call to `kvlcSetInputFile` or `kvlcFeedSelectFormat`.

**NO\_TIME\_REFERENCE = -31**  
Required timestamp missing.

**NULL\_POINTER = -8**  
Unexpected null pointer.

**PARAM = -2**  
Error in supplied parameters.

**RESULT\_TOO\_BIG = -34**  
Result is too big for an out-parameter

**TIME\_DECREASING = -32**  
Decreasing time between files.

**TYPE\_MISMATCH = -11**  
Supplied parameter has incorrect type.

## FileFormat

**class** `canlib.kvclib.FileFormat`(*value*)  
`FILE_FORMAT_XXX`  
Format used for input and output, used in `Converter.setInputFile()`.

---

**Note:** Not all formats are valid as both output and input format.

---

**CSV = 4**  
Output file format.

**CSV\_SIGNAL = 100**  
Output file format.

**DEBUG = 1000**  
Reserved for debug.

**FAMOS = 105**  
Output file format.

**FAMOS\_XCP = 201**  
Output file format.

**INVALID = 0**  
Invalid file format

**J1587 = 103**  
Output file format.

**J1587\_ALT = 104**  
Obsolete.

**KME24 = 1**  
Input and output file format.

**KME25 = 2**  
Input and output file format.

**KME40 = 7**  
Input and output file format.

**KME50 = 9**  
Input and output file format.

**MATLAB = 102**  
Output file format.

**MDF = 101**  
Output file format.

**MDF\_4X = 107**  
Output file format.

**MDF\_4X\_SIGNAL = 108**  
Output file format.

**MDF\_SIGNAL = 106**  
Output file format.

**MEMO\_LOG = 6**  
Input (internal device logfile format).

**PLAIN\_ASC = 5**  
Output file format.

**VECTOR\_ASC = 3**  
Output file format.

**VECTOR\_BLF = 8**  
Output file format.

**VECTOR\_BLF\_FD = 109**  
Input and output format.

**XCP = 200**  
Output file format.

## Property

**class** canlib.kvlclib.**Property**(*value*)

An enumeration.

**ATTACHMENTS = 1003**

Can attach files to converted data.

It is possible to use *Converter.attachFile()* to add a file. Used only with *WriterFormat.isPropertySupported()* and *ReaderFormat.isPropertySupported()*.

**CALENDAR\_TIME\_STAMPS = 7**

Write calendar time stamps.

**CHANNEL\_MASK = 5**

Bitmask of the channels that should be used during conversion.

**COMPRESSION\_LEVEL = 32**

ZLIB compression level for writers that use ZLIB for compression. [-1, 9].

**CREATION\_DATE = 27**

File creation date/time as seconds in standard UNIX format. Used in file headers if not zero.

**CROP\_PRETRIGGER = 22**

Crop pre-triggers.

**DATA\_IN\_HEX = 12**

Write data in hexadecimal format.

**DECIMAL\_CHAR = 10**

Use token as decimal separator.

**ENUM\_VALUES = 23**

Replace integer values in signals with strings from database.

**FILL\_BLANKS = 15**

Propagate values down to next row in csv-files.

**FIRST\_TRIGGER = 2**

Use first trigger as time reference.

**FULLY\_QUALIFIED\_NAMES = 30**

Write fully qualified signal names

**HLP\_J1939 = 6**

Interpret events as J1939.

**ID\_IN\_HEX = 11**

Write id in hexadecimal format.

**ISO8601\_DECIMALS = 17**

Number of time decimals (0-9) to print in the calendar timestamps using ISO8601.

**LIMIT\_DATA\_BYTES = 26**

Number of data bytes that a converter will write.

**MERGE\_LINES = 18**

Merge two lines if their signal values are equal.

**NAME\_MANGLING = 14**

Make signal names safe for use in Matlab.

**NUMBER\_OF\_DATA\_DECIMALS = 31**

Number of data decimals (0-50)

**NUMBER\_OF\_TIME\_DECIMALS = 13**

Number of time decimals (0-9).

**OFFSET = 4**

Time reference offset.

**OVERWRITE = 28**

Overwrite existing output files

**RESAMPLE\_COLUMN = 19**

Only print a line when the given column has been accessed.

**SEPARATOR\_CHAR = 9**

Use token as separator.

**SHOW\_COUNTER = 21**

Add a counter to the output.



**SHOW\_SIGNAL\_SELECT = 1002**

Format requires a database.

Used only with `WriterFormat.isPropertySupported()` and `ReaderFormat.isPropertySupported()`.

**SHOW\_UNITS = 16**

Show units on their own row.

**SIGNAL\_BASED = 1001**

Writes signals and not data frames.

Used only with `WriterFormat.isPropertySupported()` and `ReaderFormat.isPropertySupported()`.

**SIZE\_LIMIT = 24**

Maximum file size in megabytes before starting a new output file.

**START\_OF\_MEASUREMENT = 1**

Use start of measurement as time reference.

**TIMEZONE = 29**

Timezone for absolute timestamps

**TIME\_LIMIT = 25**

Maximum delta time in seconds between first and last event before starting a new output file.

**USE\_OFFSET = 3**

Use offset as time reference.

**VERSION = 20**

File format version.

**WRITE\_HEADER = 8**

Write informational header.

## Reader Formats

### reader\_formats()

#### canlib.kvlclib.reader\_formats()

Return a generator of all reader formats.

You may list available Readers using:

```
>>> from canlib import kvlclib
>>> for format in kvlclib.reader_formats():
...     print(format)
KME24 (.kme): Reader, Kvaser binary format (KME 2.4)
KME25 (.kme25): Reader, Kvaser binary format (KME 2.5)
KME40 (.kme40): Reader, Kvaser binary format (KME 4.0)
KME50 (.kme50): Reader, Kvaser binary format (KME 5.0)
MDF (.log): Reader, CAN frames in Vector Mdf
MDF_4X (.mf4): Reader, CAN frames in MDF v4.1 for Vector CANalyzer
PLAIN_ASC (.txt): Reader, CAN frames in plain text format
VECTOR_ASC (.asc): Reader, CAN frames in Vector ASCII format
VECTOR_BLF_FD (.blf): Reader, CAN frames in Vector BLF format
CSV (.csv): Reader, CAN frames in CSV format
...

```

---

**Note:** CANlib before v5.37 incorrectly reported `.mke` as the file suffix for KME 2.4.

---

New in version 1.7.

## ReaderFormat

**class** canlib.kvlclib.**ReaderFormat**(*id\_*)

Helper class that encapsulates a Reader.

You may use `reader_formats()` to list available Readers.

New in version 1.7.

Changed in version 1.19: Updated formatting in `__str__`.

**getPropertyDefault**(*rd\_property*)

Get default value for property.

**isPropertySupported**(*rd\_property*)

Check if specified read property is supported.

Returns True if the property is supported by input format.

**Parameters** *rd\_property* (*Property*) – Reader property

## Writer Formats

### `writer_formats()`

canlib.kvlclib.**writer\_formats**()

Return a generator of all writer formats.

You may list available Writers using:

```
>>> from canlib import kvlclib
>>> for format in kvlclib.writer_formats():
...     print(format)
CSV (.csv): Writer, CAN frames in CSV format
CSV_SIGNAL (.csv): Writer, Selected signals in CSV format
XCP (.csv): Writer, CCP/XCP calibration in CSV format
MATLAB (.mat): Writer, Selected signals in Matlab format for ATI Vision
KME24 (.kme): Writer, Kvaser binary format (KME 2.4) - used for Vector CANalyzer
KME25 (.kme25): Writer, Kvaser binary format (KME 2.5)
KME40 (.kme40): Writer, Kvaser binary format (KME 4.0)
KME50 (.kme50): Writer, Kvaser binary format (KME 5.0)
PLAIN_ASC (.txt): Writer, CAN frames in plain text format
...
```

New in version 1.7.

## WriterFormat

**class** canlib.kvllib.**WriterFormat**(*id\_*)

Helper class that encapsulates a Writer.

You may use `writer_formats()` to list available Writers.

Changed in version 1.19: Updated formatting in `__str__`.

**classmethod** `getFirstWriterFormat()`

Get the first supported output format.

**classmethod** `getNextWriterFormat(previous_id)`

Get the next supported output format.

**getPropertyDefault**(*wr\_property*)

Get default value for property.

**isPropertySupported**(*wr\_property*)

Check if specified write property is supported.

Returns True if the property is supported by output format.

**Parameters** *wr\_property* (*Property*) – Writer property

**Returns** bool

## Miscellaneous

### dllversion

canlib.kvllib.**dllversion**()

Get the kvllib version number as a *canlib.VersionNumber*

## 1.6.10 kvmlib

### Exceptions

#### KvmError

**exception** canlib.kvmlib.**KvmError**

Base class for exceptions raised by the kvmlib dll

#### KvmDiskError

**exception** canlib.kvmlib.**KvmDiskError**

General disk error

**status** = -24

### KvmDiskNotFormatted

**exception** canlib.kvmlib.KvmDiskNotFormatted

Disk not formatted

**status** = -34

### KvmNoDisk

**exception** canlib.kvmlib.KvmNoDisk

No disk found

**status** = -13

### KvmNoLogMsg

**exception** canlib.kvmlib.KvmNoLogMsg

No log message found

**status** = -10

### LockedLogError

**exception** canlib.kvmlib.LockedLogError

Raised when trying to mount a log file to a locked log

Only one log file can be “mounted” internally at time. When a *LogFile* object requires its log file to be kept mounted for an extended period of time (such as when iterating over it) it will lock its containing *MountedLog* object. If during this time an attempt is made to mount a log file, this error will be raised.

## Enumerations

### Device

**class** canlib.kvmlib.Device(*value*)

kvmDEVICE\_XXX

Device type, used to connect to a Memorator device.

**MHYDRA** = 0

Kvaser Memorator (2nd generation)

**MHYDRA\_EXT** = 1

Kvaser Memorator (2nd generation) with extended data capabilities.

## Error

**class** canlib.kvmlib.**Error**(*value*)

An enumeration.

**CONFIG\_ERROR** = -41

Configuration error.

**CRC\_ERROR** = -21

CRC check failed.

**DEVICE\_COMM\_ERROR** = -37

Device communication error.

**DISKFULL\_DATA** = -26

Disk full (data).

**DISKFULL\_DIR** = -25

Disk full (directory).

**DISK\_ERROR** = -24

General disk error.

**EOF** = -12

End of file found.

**FAIL** = -1

Generic error.

**FATAL\_ERROR** = -31

Fatal error.

**FILE\_ERROR** = -23

File I/O error.

**FILE\_NOT\_FOUND** = -33

File not found.

**FILE\_SYSTEM\_CORRUPT** = -28

File system corrupt.

**FIRMWARE** = -40

Firmware error.

**ILLEGAL\_REQUEST** = -32

Illegal request.

**LOGFILEOPEN** = -8

Can't find/open log file.

**LOGFILEREAD** = -14

Error while reading log file.

**LOGFILEWRITE** = -11

Error writing log file.

**NOLOGMSG** = -10

No log message found.

**NOSTARTTIME** = -9

Start time not found.

**NOT\_FORMATTED** = -34

Disk not formatted.

**NOT\_IMPLEMENTED = -30**  
Not implemented.

**NO\_DISK = -13**  
No disk found.

**OCCUPIED = -38**  
Device occupied.

**OK = 0**  
OK!

**PARAM = -3**  
Error in supplied parameters.

**QUEUE\_FULL = -20**  
Queue is full.

**RESULT\_TOO\_BIG = -43**  
Result is too big for an out-parameter.

**SECTOR\_ERASED = -22**  
Sector unexpectedly erased.

**SEQ\_ERROR = -27**  
Unexpected sequence.

**TIMEOUT = -36**  
Timeout.

**UNSUPPORTED\_VERSION = -29**  
Unsupported version.

**USER\_CANCEL = -39**  
User abort.

**WRITE\_PROT = -42**  
Disk is write protected.

**WRONG\_DISK\_TYPE = -35**  
Wrong disk type.

## FileType

**class** canlib.kvmlib.**FileType**(*value*)  
kvmFILE\_XXX  
KME file type, a binary file format representing log data.

**KME24 = 0**  
Deprecated format, use KME40

**KME25 = 1**  
Deprecated format, use KME40

**KME40 = 2**  
Kvaser binary format (KME 4.0)

**KME50 = 3**  
Kvaser binary format (KME 5.0)

## LoggerDataFormat

```
class canlib.kvmlib.LoggerDataFormat(value)
    kvmLDF_MAJOR_XXX
    Logged data format (LDF) version.
    MAJOR_CAN = 3
        Used in Kvaser Memorator (2nd generation)
    MAJOR_CAN64 = 5
        Used in Kvaser Memorator (2nd generation) with extended data capabilities.
```

## LogFileType

```
class canlib.kvmlib.enums.LogFileType(value)
    kvmLogFileType_XXX
    New in version 1.11.
    ALL = 1
        A log file containing all frames.
    ERR = 0
        A log file containing only error frames with frames before and after.
```

## SoftwareInfoItem

```
class canlib.kvmlib.enums.SoftwareInfoItem(value)
    kvm_SWINFO_XXX
    Different types of version information that can be extracted using kvmDeviceGetSoftwareInfo(), used internally
    by Memorator.
    CONFIG_VERSION_NEEDED = 5
        Returns the version of the binary format the device requires (param.lif).
    CPLD_VERSION = 6
        Obsolete.
    DRIVER = 2
        Returns the used driver version information.
    DRIVER_PRODUCT = 4
        Obsolete. Returns the product version information.
    FIRMWARE = 3
        Returns the device firmware version information.
    KVMLIB = 1
        Returns the version of kvmlib.
```

## Events

### MessageEvent

**class** canlib.kvmlib.**MessageEvent**(*id=None, channel=None, dlc=None, flags=None, data=None, timestamp=None*)

Bases: *canlib.kvmlib.events.LogEvent*

A CAN message recorded by a Memorator

**asframe**()

Convert this event to a *canlib.Frame*

Creates a new *canlib.Frame* object with the same contents as this event.

### LogEvent

**class** canlib.kvmlib.**LogEvent**(*timestamp=None*)

The base class for events recorded by a Memorator.

### RTCEvent

**class** canlib.kvmlib.**RTCEvent**(*calendartime=None, timestamp=None*)

Bases: *canlib.kvmlib.events.LogEvent*

An real-time clock message recorded by a Memorator

### TriggerEvent

**class** canlib.kvmlib.**TriggerEvent**(*type=None, timestamp=None, pretrigger=None, posttrigger=None, trigno=None*)

Bases: *canlib.kvmlib.events.LogEvent*

A trigger message recorded by a Memorator

### VersionEvent

**class** canlib.kvmlib.**VersionEvent**(*lioMajor, lioMinor, fwMajor, fwMinor, fwBuild, serialNumber, eanHi, eanLo*)

Bases: *canlib.kvmlib.events.LogEvent*

A version message recorded by a Memorator



## memoLogEventEx

```

class canlib.kvmlib.memoLogEventEx
    Low level c type class holding a log event.

    MEMOLOG_TYPE_CLOCK = 1
        The event type used in kvmLogRtcClockEx

    MEMOLOG_TYPE_INVALID = 0
        Invalid MEMOLOG event type

    MEMOLOG_TYPE_MSG = 2
        The event type used in kvmLogMsgEx

    MEMOLOG_TYPE_TRIGGER = 3
        The event type used in kvmLogTriggerEx

    MEMOLOG_TYPE_VERSION = 4
        The event type used in kvmLogVersionEx

    createMemoEvent()
        Convert event to LogEvent.

    event
        Structure/Union member

```

## Log files

### UnmountedLog

```

class canlib.kvmlib.UnmountedLog(memorator)
    The log area of a Memorator before mounting

```

Before the log area of a *Memorator* object has been mounted, its `log` attribute is set to an instance of this class.

This class has all the functionality available even when the log area has not been mounted – this functionality is still present after the log area has been mounted (or if the area is always mounted – see *Kmf*).

The number of log files can be read as the `len()` of this object (container is either a *Memorator* or *Kmf* object):

```
num_log_files = len(container.log)
```

All log files can also be deleted:

```
container.log.delete_all()
```

New in version 1.6.

```

delete_all()
    Delete all log files

```

## MountedLog

**class** canlib.kvmlib.MountedLog(*memorator, ldf\_version*)

Bases: [canlib.kvmlib.log.UnmountedLog](#)

The log area of a Memorator once mounted

Once a *Memorator* object has been mounted, its `log` attribute is set to an instance of this class. This is the preferred way of using this class.

For *Kmf* objects, the `log` attribute is always an instance of this class as they are by definition mounted.

In the following examples `container` can be either a *Memorator* object that has been mounted, or a *Kmf* object.

The files within the log can be accessed via indexing:

```
container.log[index]
```

or all files can be iterated over:

```
for log_file in container.log:  
    ...
```

The log area can also be validated:

```
container.log.validate()
```

Also see the super class [UnmountedLog](#) for functionality this class has inherited.

New in version 1.6.

**validate()**

Raises the corresponding exception if any errors are detected

## LogFile

**class** canlib.kvmlib.LogFile(*container, index*)

A log file read from a *MountedLog* object

This class is normally not directly instantiated but retrieved from a *MountedLog* object.

The most common use of this class is iterating through it to get the individual events as *LogEvent* subclasses:

```
for event in logfile:  
    ...
```

---

**Note:** While iterating over a *LogFile*, accessing any other *LogFile* will result in a *LockedLogError*. Make sure to finish the loop (or when using iteration objects directly call the `close` method) before interacting with any other log files.

---

A fast approximation of the number of events is given by *event\_count\_estimation*, the exact number of events can be calculated using:

```
num_events = len(list(logfile))
```

Finally this class has several read-only properties for getting information about the log file itself.

---

**Note:** Before any data is fetched from the dll, this class will make sure that the correct file has been mounted on the underlying `kvmHandle`.

Manually mounting or unmounting log files by calling the dll directly is not supported.

---

New in version 1.6.

**property creator\_serial**

The serial number of the interface that created the log file

**Type** `int`

**property end\_time**

The time of the last event in the log file

**Type** `datetime.datetime`

**event\_count\_estimation()**

Returns an approximation of the number of events

The number is a rough estimation because it is calculated from the number of blocks allocated by the log file on the disk as an optimization.

New in version 1.7.

**property log\_type**

The type of the log file

New in version 1.11.

**Type** `LogFileTypes`

**property start\_time**

The time of the first event in the log file

**Type** `datetime.datetime`

## kme files

### createKme()

`canlib.kvmlib.createKme(path, filetype=FileType.KME50)`

Create a KME file on the host computer

**Parameters**

- **path** (`str`) – The full filepath for the .KME file (e.g. "data/mylog.kme50").
- **filetype** (`FileType`) – The KME file type

**Returns** `Kme`

New in version 1.7.

## openKme()

canlib.kvmlib.**openKme**(*path*, *filetype=FileType.KME50*)

Open a KME file on the host computer

### Parameters

- **path** (str) – The full filepath for the .KME file (e.g. "data/mylog.kme50").
- **filetype** (*FileType*) – The KME file type

### Returns

*Kme*

New in version 1.7.

## Kme

**class** canlib.kvmlib.**Kme**(*handle*)

A kme file

A class representing a KME file. The main use is twofold:

Either we create a KME file using *createKme* and would like to write events using *Kme.write\_event*:

```
with kvmlib.createKme('out/data.kme50') as kme:
    ...
    kme.write_event(my_logevent)
```

Or we read events from an existing KME file:

```
with kvmlib.openKme('in/data.kme50') as kme:
    event = kme.read_event()
    ...
    print(event)
```

Note that only KME files of type KME50 may currently be written to.

New in version 1.7.

### close()

### estimate\_events()

Estimate how many events the KME file contains

**Returns:** int: Approximate number of events in KME file.

New in version 1.7.

Deprecated since version 1.11.

### event\_count\_estimation()

Returns an approximation of the number of events contained in the KME file.

**Returns:** int: Approximate number of events in KME file.

New in version 1.11.

### events()

### read\_event()

Read logevent from KME file

**Returns:** *memoLogEventEx*

New in version 1.7.

**write\_event**(*logevent*)

## kme\_file\_type()

`canlib.kvmlib.kme_file_type(path)`

Scan KME file and report version

Open and read the file *path* and try to decode what version of KME it contains. Returns type as `kvmFILE_XXX`.

**Parameters** *path* (str) – The full filepath for the .KME file (e.g. "data/mylog.kme").

**Returns** *FileType* – The KME file type

New in version 1.7.

## kmf files

### openKmf()

`canlib.kvmlib.openKmf(path, device_type=Device.MHYDRA_EXT)`

Open a kmf file from disk

**Parameters**

- **path** (str) – The filepath to the .KMF file (e.g. "data/kmf/LOG000000.KMF").
- **device\_type** (*Device*) – The type of the memorator that created the .KMF file(s) (defaults to *Device.MHYDRA\_EXT*)

**Returns** *Kmf*

New in version 1.6.

## Kmf

**class** `canlib.kvmlib.Kmf(handle, ldf_version)`

A kmf file opened with *openKmf*

The main use of this class is using its `log` attribute, which is a *MountedLog* object (see its documentation for how to use it).

Also see the base class *KmfSystem* for inherited functionality.

**Variables** `log` (*MountedLog*) – Object representing the log of log files within the kmf container-file.

New in version 1.6.

## KmfSystem

**class** canlib.kvmlib.**KmfSystem**(*handle*)

The base class of *Kmf* and *Memorator*

The *Kmf* and *Memorator* classes are very similar, they are different ways of reading log files (*LogFile*) created by a memorator. This class represents the common ground between all ways of accessing log files.

All subclasses should have a `log` attribute which is an *UnmountedLog* or subclass thereof.

This class automatically closes its internal handle when garbage collected.

New in version 1.6.

**class** **DiskUsage**(*used, total*)

**property** **total**

Alias for field number 1

**property** **used**

Alias for field number 0

**close**()

Close the internal handle

**Warning:** Closing invalidates the object.

**property** **disk\_usage**

The disk usage

**Returns**

namedtuple – containing

- **used** (int): Used disk space in megabytes.
- **total** (int): Total disk space in megabytes.

**Type** namedtuple

## Memorator

**openDevice**()

canlib.kvmlib.**openDevice**(*channel\_number, mount=False, device\_type=Device.MHYDRA\_EXT*)

Open a Memorator device

**Parameters**

- **channel\_number** (int) – A channel number of the Memorator to be opened.
- **mount** (bool) – Whether the memorator log area should be mounted before returned.
- **device\_type** (*Device*) – The type of the memorator to be opened (defaults to *Device.MHYDRA\_EXT*)

**Returns** *Memorator*

New in version 1.6.

## Memorator

**class** canlib.kvmlib.**Memorator**(*handle, channel\_number, device\_type*)

A Memorator device opened with *openDevice*

This class should not be instantiated directly, instead call *openDevice*.

A device opened as *Memorator* can be configured from XML using *kvamemolibxml.load\_xml\_file* and *write\_config*:

```
# Read the original XML file (config.xml)
config = kwamemolibxml.load_xml_file("config.xml")

# Validate the XML
errors, warnings = config.validate()
if errors or warnings:
    print(errors)
    print(warnings)
    raise Exception("One or more errors/warnings in xml configuration")

# Write the configuration in binary
memorator.write_config(config.lif)
```

The configuration can then be read back (in binary):

```
dev.read_config()
```

The log files on the device can be accessed via the *log* attribute. By default, the log area is not mounted so only a few operations are allowed, such as getting the number of log files:

```
num_log_files = len(memorator.log)
```

For a full list of allowed operations, see *UnmountedLog* (the type of *.log* before a mount).

The log area can be mounted either with *openDevice*'s *mount* argument set to True, or later with the *Memorator.mount* function. Once this is done the log attribute is a *MountedLog* which supports getting log files as *LogFile* objects:

```
# We can index the Memorator object if we know what file we want
log_file_number_two = memorator.log[2]

# Although usually we want to loop through all log files
for log_file in memorator.log:
    ...
```

See the documentation of *MountedLog* for all available operations.

### Variables

- **channel\_number** (int) – The channel number that was used to connect to this memorator.
- **device\_type** (*Device*) – The device type that was used to connect to this memorator.
- **mounted** (bool) – Whether the device's memory card has been mounted.

New in version 1.6.

### property **config\_version\_needed**

The version of param.lif that the connected device expects

Type *canlib.VersionNumber*

**property disk\_size**

The disk size in megabytes

**Warning:** This is not necessarily the amount of space available for allocation; `Memorator.format_disk(reserved_space=Memorator.disk_size)` is not guaranteed to succeed.

The most reliable way of calculating reserved space is to first format the disk with `reserved_space` set to 0, and then use `Memorator.disk_usage.total`.

Type `int`

**property driver\_version**

The used driver version information

Type *canlib.VersionNumber*

**property firmware\_version**

The device firmware version information

Type *canlib.VersionNumber*

**flash\_leds()**

Flash all LEDs on the Memorator

**format\_disk(reserved\_space=10, database\_space=2, fat32=True)**

Format the SD memory card in the Memorator

**Parameters**

- **reserved\_space** (`int`) – Space to reserve for user files, in MB.
- **database\_space** (`int`) – Space to reserve for database files, in MB.
- **fat32** (`bool`) – Whether the filesystem should be formatted as fat32 (defaults to `True`)

Changed in version 1.9: Will now reopen the internal handle if the log is mounted in order to refresh `Memorator.log.ldf_version`

**property kvmlib\_version**

Returns the version of kvmlib

Type *canlib.VersionNumber*

**mount()**

Mount the Memorator's log area

This replaces the object `log` attribute with a *MountedLog*, which allows access to log files.

If the log has already been mounted (`self.mounted == True`), this is a no-op.

**mounted = None**

**read\_config()**

Read the configuration of the Memorator

The configuration is returned as a `bytes` object with the binary configuration data (`param.lif`).

If a *kvamemolibxml.Configuration* is desired, the returned `bytes` can be parsed using *kvamemolibxml.load\_lif*:



```
config_object = kvamemolibxml.load_lif(memorator.read_config())
```

**reopen**(*device\_type=None, mount=False*)  
Closes and then reopens the internal handle

**property rtc**  
The value of the real-time clock  
**Type** datetime.datetime

**property serial\_number**  
The serial number of the Memorator  
**Type** int

**write\_config**(*config\_lif*)  
Writes configuration to the Memorator  
The configuration should be given as a bytes object with the binary configuration data (param.lif).  
Given a *kvamemolibxml.Configuration* object, pass its *lif* attribute to this function:

```
memorator.write_config(config_object.lif)
```

## Miscellaneous

### dllversion()

canlib.kvmlib.dllversion()  
Get the kvmlib version number as a *canlib.VersionNumber*

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### Exceptions

#### KvrError

**exception** canlib.kvrlib.KvrError  
Bases: *canlib.exceptions.DllException*

#### KvrGeneralError

**exception** canlib.kvrlib.exceptions.KvrGeneralError(*status*)  
Bases: *canlib.kvrlib.exceptions.KvrError*  
A kvrlib error that does not (yet) have its own Exception

**Warning:** Do not explicitly catch this error, instead catch *KvrError*. Your error may at any point in the future get its own exception class, and so will no longer be of this type. The actual status code that raised any *KvrError* can always be accessed through a *status* attribute.

### KvrBlank

**exception** `canlib.kvrlib.exceptions.KvrBlank`  
Bases: `canlib.kvrlib.exceptions.KvrError`  
List was not set or no more results.  
**status** = -6

### KvrNoAnswer

**exception** `canlib.kvrlib.exceptions.KvrNoAnswer`  
Bases: `canlib.kvrlib.exceptions.KvrError`  
No answer arrived within given timeout.  
**status** = -8

### KvrParameterError

**exception** `canlib.kvrlib.exceptions.KvrParameterError`  
Bases: `canlib.kvrlib.exceptions.KvrError`  
Error in supplied in parameters.  
**status** = -4

### KvrPasswordError

**exception** `canlib.kvrlib.exceptions.KvrPasswordError`  
Bases: `canlib.kvrlib.exceptions.KvrError`  
Supplied password was wrong.  
**status** = -5

### KvrUnreachable

**exception** `canlib.kvrlib.exceptions.KvrUnreachable`  
Bases: `canlib.kvrlib.exceptions.KvrError`  
Remote device is unreachable.  
**status** = -7

## DeviceNotInSetError

**exception** canlib.kvrlib.DeviceNotInSetError

Bases: `KeyError`, `canlib.exceptions.CanlibException`

## Discovery

### Address

**class** canlib.kvrlib.Address(*type, address*)

An IP or MAC address

#### Variables

- **type** (*AddressType*) – Address type.
- **address** (`list[int]`) – A list of integers, the numbers in the address.

**classmethod** from\_c(*c\_addr*)

Create an *Address* object from a *kvrAddress* object

**to\_c()**

Create a *kvrAddress* from this object

## DeviceInfo

**class** canlib.kvrlib.DeviceInfo(*device\_info=None*)

Information about a device that can be written to the registry

See *DeviceInfoSet* for information about how to get *DeviceInfo* objects, process them, and then write them to the registry.

**property** accessibility

The accessibility of this device

**Type** *Accessibility*

**property** availability

The availability of this device

**Type** *Availability*

**property** base\_station\_id

Address of the base station

**Type** *Address*

**property** client\_address

Address of connected client

**Type** *Address*

**property** connect

Whether the service should connect to this device

**Type** `bool`

**property** device\_address

Address of remote device

**Type** *Address*

**property ean**

EAN of device

Type *EAN*

**property encryption\_key**

The encryption key to use when encrypting communication

---

**Note:** This attribute is write-only.

---

Type bytes

**property firmware\_version**

Firmware version

Type *VersionNumber*

**property hostname**

DNS hostname if available, otherwise an empty string

Type str

**info()**

Create a string with information about the *DeviceInfo*

To be used when the `str()` representation is not detailed enough.

**property name**

User-defined name of device

Type str

**property password**

The accessibility password to use when connecting to a device

---

**Note:** This attribute is write-only.

---

Type str

**property serial**

The serial number of the device

Type int

**property service\_status**

A tuple with the service status of the device

The returned tuple has the format (state, start\_info, text), where state is a *ServiceState*, start\_info is a *StartInfo*, and text is a str with local connection status.

Type *ServiceStatus*

**property stored**

Whether this *DeviceInfo* was read from the registry

Type bool

**update(*other*)**

Update the attributes of this instance

This function takes a `dict`, and will set the attributes given by the keys to the corresponding value (on this object).

**property usage**

Usage status (Free/Remote/USB/Config)

Type *DeviceUsage*

**Discovery****class** `canlib.kvrlib.Discovery`(*handle*)

A kvrlib “Discovery” process

Most of the time the discovery process can be handled by *discover\_info\_set*, which returns the results of the discovery as a *DeviceInfoSet*.

Even when interacted with directly, instances of this class are normally not instantiated directly, but created using *start\_discovery*, or sometimes using *openDiscovery*.

Instances of this class can be used as context handlers, in which case the discovery will be closed when the context is exited. The discovery will also be closed when the instance is garbage collected, if it hasn’t already.

**property addresses**

The list of addresses to use for discovery

---

**Note:** This attribute is write-only.

---

This attribute should be a list of *Address* objects.

If the *Discovery* object was created by *start\_discovery*, the addresses are automatically set. Otherwise, they must be assigned before *Discovery.start* can be called.

**close()**

Close the discovery process

This function is called when the *Discovery* object is garbage-collected.

If the *Discovery* object is used as a context handler, this function will be called when the context exits.

**results()**

Return an iterator of the result from the discovery

The results are yielded as *DeviceInfo* objects.

**start**(*delay*, *timeout*, *report\_stored=True*)

Run the discovery

If the *Discovery* object was created by *start\_discovery*, the discovery has already been run, and this function does not need to be called.

After the discovery has been run, its results can be retrieved using *Discovery.results*.

**Parameters**

- **delay** (int) – The millisecond delay between sending discovery messages to addresses in the address list.

- **timeout** (int) – The millisecond timeout after all discovery messages have been sent, before returning.
- **report\_stored** (bool) – if True (the default), stored devices will be discovered.

### **get\_default\_discovery\_addresses()**

`canlib.kvrlib.get_default_discovery_addresses(broadcast=True, stored=False)`

Retrieve the default discovery addresses

#### **Parameters**

- **broadcast** (bool) – If True (the default), then the returned list will contain broadcast addresses.
- **stored** (bool) – If True (defaults to False), then the returned list will contain earlier stored addresses.

If both arguments are False, a `ValueError` will be raised.

Returns a list of `Address` objects.

### **openDiscovery()**

`canlib.kvrlib.openDiscovery()`

Creates and returns a `Discovery` object

Device discovery is normally done using `discover_info_set`.

### **ServiceStatus**

`class canlib.kvrlib.ServiceStatus(state, start_info, text)`

**property start\_info**

Alias for field number 1

**property state**

Alias for field number 0

**property text**

Alias for field number 2

### **set\_clear\_stored\_devices\_on\_exit()**

`canlib.kvrlib.set_clear_stored_devices_on_exit(val)`

Sets whether kvrlib should clear stored devices when the application exist

## start\_discovery()

`canlib.kvrlib.start_discovery(delay, timeout, addresses=None, report_stored=True)`

Start and return a *Discovery*

Device discovery is normally done using *discover\_info\_set*.

The returned object should usually be used as a context handler:

```

with kvrlib.start_discovery(delay=100, timeout=1000) as disc:
    for result in disc.results():
        # process the discovery result
        print(result)

```

## store\_devices()

`canlib.kvrlib.store_devices(devices)`

Store a collection of *DeviceInfo* objects in the registry

See *DeviceInfoSet* for a simpler way of dealing with device infos and the registry.

---

**Note:** Previously stored devices are cleared.

---

## stored\_devices()

`canlib.kvrlib.stored_devices()`

Read the devices stored in the registry as a tuple of *DeviceInfo* objects

## Enumerations

### Accessibility

`class canlib.kvrlib.Accessibility(value)`

`kvrAccessibility_XXX`

Remote device accessibility status.

**PRIVATE = 3**

Private (invisible, password needed to connect).

**PROTECTED = 2**

Protected (visible for all, password needed to connect).

**PUBLIC = 1**

Public (visible for all, no password required to connect).

**UNKNOWN = 0**

Unknown (e.g., no reply from device).

## AddressType

**class** canlib.kvrlib.**AddressType**(*value*)

kvrAddressType\_XXX

Type of device address.

---

**Note:** Ports are currently not used.

---

**IPV4 = 1**

IP v.4 address.

**IPV4\_PORT = 3**

IP v.4 address with tcp-port.

**IPV6 = 2**

IP v.6 address.

**MAC = 4**

Ethernet MAC address.

**UNKNOWN = 0**

Unknown (e.g., no reply from device).

## AddressTypeFlag

**class** canlib.kvrlib.**AddressTypeFlag**(*value*)

kvrAddressTypeFlag\_XXX

Flags for setting what addresses that should be returned by *get\_default\_discovery\_addresses*.

**ALL = 255**

All defined below

**BROADCAST = 1**

Broadcast addresses

**STORED = 2**

Previously stored addresses

## Availability

**class** canlib.kvrlib.**Availability**(*value*)

kvrAvailability\_XXX

Device availability flags.

**FOUND\_BY\_SCAN = 1**

Device was found by scan.

**NONE = 0**

Manually added.

**STORED = 2**

Device was stored.



## BasicServiceSet

```
class canlib.kvrlib.BasicServiceSet(value)
    kvrBss_XXX
    Basic Service Set.

    ANY = 2
        Any.

    INDEPENDENT = 1
        Ad-hoc network.

    INFRASTRUCTURE = 0
        Network with AP.
```

## ConfigMode

```
class canlib.kvrlib.ConfigMode(value)
    kvrConfigMode_XXX
    Configuration mode.

    ERASE = 2
        Erase and write.

    R = 0
        Read only.

    RW = 1
        Read/write.
```

## DeviceUsage

```
class canlib.kvrlib.DeviceUsage(value)
    kvrDeviceUsage_XXX
    Remote device usage status.

    CONFIG = 4
        Device is being configured via USB.

    FREE = 1
        Not in use.

    REMOTE = 2
        Connected to a PC (as a remote device).

    UNKNOWN = 0
        Unknown (e.g., no reply from device).

    USB = 3
        Connected via USB cable.
```

## Error

**class** canlib.kvrlib.**Error**(*value*)

An enumeration.

**BLANK** = -6

List was not set or no more results.

**BUFFER\_TOO\_SMALL** = -15

The buffer provided was not large enough to contain the requested data.

**CHECKSUM** = -3

Checksum problem.

**DUPLICATED\_DEVICE** = -13

There are duplicates in the device list.

**GENERIC** = -2

Generic error.

**NOT\_IMPLEMENTED** = -9

Function is not yet implemented.

**NOT\_INITIALIZED** = -1

kvrlib has not been initialized.

**NO\_ANSWER** = -8

No answer arrived within given timeout.

**NO\_DEVICE** = -7

Remote device is unreachable.

**NO\_SERVICE** = -12

The helper service is not running.

**OK** = 0

OK!

**OUT\_OF\_SPACE** = -11

Out of space, eg. too many open handles, too small buffer.

**PARAMETER** = -4

Error in supplied in parameters.

**PASSWORD** = -5

Supplied password was wrong.

**PERMISSION\_DENIED** = -10

Permission denied.

**XML\_VALIDATION** = -14

XML-file validation failed.

## NetworkState

```

class canlib.kvrlib.NetworkState(value)
    kvrNetworkState_XXX

    States for network connection.

    AUTHENTICATING = 8
        EAPOL handshake ongoing.

    AUTHENTICATION_FAILED = 9
        Authentication have failed.

    CONNECTED = 7
        Network is reached.

    CONNECTING = 6
        Waiting for connections (ad-hoc).

    CONNECTION_DELAY = 5
        Delay during connection (ad-hoc).

    FAILED_MIC = 11
        MIC verification (EAPOL-key) failed.

    INITIALIZING = 3
        Started, waiting for initialization.

    INVALID = 1
        Network hardware has been disabled.

    NOT_CONNECTED = 4
        No connection (may auto-connect).

    ONLINE = 10
        Authentication completed.

    STARTUP = 2
        Configuring network hardware.

    UNKNOWN = 0
        Bad state, should never be reported.

```

## RegulatoryDomain

```

class canlib.kvrlib.RegulatoryDomain(value)
    kvrRegulatoryDomain_XXX

    Regulatory domain.

    CHINA_MII = 4
        MII

    EUROPE_ETSI = 1
        ETSI

    JAPAN_TELEC = 0
        TELEC

    NORTH_AMERICA_FCC = 2
        FCC

```

**WORLD = 3**  
WORLD

## RemoteState

```
class canlib.kvrlib.RemoteState(value)
    kvrRemoteState_XXX
    State of connection to device.
    AVAILABLE = 1
        Tries to ping known device.
    CLOSING = 10
        Will stop communication.
    CONFIG_CHANGED = 13
        Same as UNWILLING.
    CONNECTION_DOWN = 5
        Will try and restore connection.
    CONNECTION_UP = 6
        Device connected, heartbeat up.
    DISCOVERED = 2
        Currently not used.
    INSTALLING = 15
        Driver installation is in progress.
    REDISCOVER = 7
        Trying to talk to device.
    REDISCOVER_PENDING = 9
        Will do rediscover in a moment.
    REMOVE_ME = 11
        Device removed, it will be stopped.
    STANDBY = 12
        Known device, but unused.
    STARTED = 4
        Currently not used.
    STARTING = 3
        Initializes for new device.
    STOPPING = 14
        Tries to stop device.
    UNWILLING = 8
        Device turned down connection req.
    VOID = 0
        Marked as not in list.
```

## ServiceState

**class** canlib.kvrlib.**ServiceState**(*value*)

kvrServiceState\_XXX

Current service state.

**AVAILABLE = 1**

Device available

**CLOSING = 10**

Closing device

**CONFIG\_CHANGED = 13**

Configuration has changed

**CONNECTION\_DOWN = 5**

Connection is currently down

**CONNECTION\_UP = 6**

Connection is currently up. The device should be showing up in Kvaser Hardware and be ready to be used from CANlib.

**DISCOVERED = 2**

Device discovered

**INSTALLING = 15**

Device is currently being installed

**REDISCOVER = 7**

We've lost the device - rediscover it

**REDISCOVER\_PENDING = 9**

Rediscover is pending

**REMOVE\_ME = 11**

Removing the device

**STANDBY = 12**

Standby, the service is not taking any actions against this device

**STARTED = 4**

Device is started

**STARTING = 3**

Device is starting, other devices may inhibit this device from being started at the moment (e.g. by installing).

**STOPPING = 14**

Stopping device

**UNWILLING = 8**

Unwilling, see sub state for reason

**VOID = 0**

Void

## StartInfo

```
class canlib.kvrlib.StartInfo(value)
    kvrStartInfo_xxx

    Current start information.

    ERR_CONFIGURING = 5
        I'm being configured so won't start

    ERR_ENCRYPTION_PWD = 7
        Wrong encryption password.

    ERR_IN_USE = 2
        Already connected to someone else

    ERR_NOTME = 4
        This start is not for me

    ERR_PARAM = 6
        Invalid parameters in QRV (non matching versions)

    ERR_PWD = 3
        Wrong connection pwd

    NONE = 0
        No information available

    START_OK = 1
        Started OK
```

## Device Info Set

### discover\_info\_set()

```
canlib.kvrlib.discover_info_set(delay=100, timeout=1000, addresses=None, report_stored=True)
```

### empty\_info\_set()

```
canlib.kvrlib.empty_info_set()
```

### stored\_info\_set()

```
canlib.kvrlib.stored_info_set()
```

## DeviceInfoSet

**class** canlib.kvrlib.**DeviceInfoSet**(*iterable=None*)

A mutable set of *DeviceInfo* objects that can be written to the registry

There are three different functions for creating *DeviceInfoSet* objects:

- *empty\_info\_set*: Creates an empty set.
- *stored\_info\_set*: Creates a set from the device information stored in the registry.
- *discover\_info\_set*: Create a set from the results of a *Discovery*.

Once a *DeviceInfoSet* has been created it can be modified as a normal set, and the *DeviceInfo* elements can also be modified. Once all modification is done, the set can be written to the registry with *DeviceInfoSet.store*.

The main difference between *DeviceInfoSet* and normal sets is that it can only contain one *DeviceInfo* with a specific combination of EAN and serial number, even if they otherwise are not equal. This means that even if `info in infoset` evaluates to true, that exact object may not be in the set, and modifying it may not change the set.

To retrieve a specific *DeviceInfo* from the set use *DeviceInfoSet.find*:

```
info = infoset.find(ean='01234-5', serial=42)
```

Modifying the resulting *DeviceInfo* will then change the contents of the set.

Instances of this class can also be used as context managers, in which case they will write their content to the registry when the context exists.

**add**(*info*)

Add a *DeviceInfo* to this *DeviceInfoSet*

**Parameters** *info* (*DeviceInfo*) – The element to add to this set

If the set already contains a *DeviceInfo* with the same EAN and serial number as *info*, the previous *DeviceInfo* will be discarded and replaced by *info*.

**discard**(*info*)

Remove an element. Do not raise an exception if absent.

**find**(*ean, serial*)

Find and return a specific *DeviceInfo* in this set

**Parameters**

- **ean** (*EAN*) – The EAN to search for
- **serial** (*int*) – The serial number to search for

If no *DeviceInfo* with the EAN and serial number is found in this set, *DeviceNotInSetError* is raised.

Note that there can never be more than one *DeviceInfo* with the same EAN and serial number in a *DeviceInfoSet*.

**find\_remove**(*ean, serial*)

Find a specific *DeviceInfo* and remove it from this set

Like *DeviceInfoSet.find* but immediately removes the *DeviceInfo* found from the set.

**Parameters**

- **ean** (*EAN*) – The EAN to search for

- **serial** (int) – The serial number to search for

**has**(*ean*, *serial*)

Check whether the set contains a specific *DeviceInfo*

Similar to *DeviceInfoSet.find* but instead of returning a *DeviceInfo* or raising an exception, this function returns True or False.

**Parameters**

- **ean** (*EAN*) – The EAN to search for
- **serial** (int) – The serial number to search for

**new\_info**(*ean*, *serial*, *\*\*attrs*)

Create and return new *DeviceInfo* in this set

Any attribute of the *DeviceInfo* that should have a specific value can be passed as keyword arguments to this function.

The EAN and serial number must be provided.

**Parameters**

- **ean** (*EAN*) – The EAN of the info (*DeviceInfo.ean*)
- **serial** (int) – The serial number of the info (*DeviceInfo.serial*)
- **attrs** – Any other attributes to be set on the *DeviceInfo*

If the set already contains a *DeviceInfo* with the EAN *ean* and serial number *serial*, the previous *DeviceInfo* will be discarded and replaced by the new *DeviceInfo* created by this function.

**store**()

Store this set's *DeviceInfo* objects in the registry

**update**(*\*others*)

Update the set, adding elements from all others

All *others* must contain nothing but *DeviceInfo* objects, or this function will raise *TypeError* without modifying this *DeviceInfoSet*.

## Remote Device

### AddressInfo

```
class canlib.kvrlib.AddressInfo(address1, address2, netmask, gateway, is_dhcp)
```

**property address1**

Alias for field number 0

**property address2**

Alias for field number 1

**property gateway**

Alias for field number 3

**property is\_dhcp**

Alias for field number 4

**property netmask**

Alias for field number 2



## ConfigProfile

**class** canlib.kvrlib.**ConfigProfile**(*device*, *profile\_number*)

A configuration profile of a remote-capable device

The active profile for a *RemoteDevice*, *rdev*, is accessed with:

```
profile = rdev.active_profile
```

Other profiles are accessed with `profiles`:

```
first = rdev.profiles[0]
```

See the documentation for *RemoteDevice* for more information on how to get *ConfigProfile* objects.

The specific configuration of a profile can be read:

```
xml_string = profile.read()
```

And it can also be written back:

```
profile.write(xml_string)
```

The password used by this object is taken from its parent *RemoteDevice* object. See that documentation for how to set the password.

**XML\_BUFFER\_SIZE = 2046**

**property channel\_number**

The CANlib channel number used to communicate with the device

**Type** int

**clear()**

Clear the configuration

This will also clear any previously set device password.

---

**Note:** This method requires the parent *RemoteDevice* to have the correct password.

---

**property info**

A simplified version of the configuration

It is not necessary to know the configuration password to access this information. Note that the partial XML data returned is not enough to reconfigure a device.

**Type** str

**property password**

The password used to communicate with the device

**Type** str

**read()**

Read the configuration

Returns either an XML string, or `None` if there is no configuration.

Note that *ConfigProfile.write* can handle `None`; in other words:

```
xml = profile.read()

# Do anything, including writing new configurations
...

profile.write(xml)
```

Will always work even if `xml` is `None`. This would mean that the profile originally had an empty configuration, and it will once again have an empty configuration at the end.

---

**Note:** This method requires the parent *RemoteDevice* to have the correct password.

---

### **write**(*xml*)

Write the configuration area

This function takes as its single argument either an xml string that will be written to this profile, or `None` in which case the configuration will be cleared.

---

**Note:** This method requires the parent *RemoteDevice* to have the correct password.

---

## ConnectionStatus

```
class canlib.kvrlib.ConnectionStatus(state, tx_rate, rx_rate, channel_number, rssi, tx_power)
```

### **property channel\_number**

Alias for field number 3

### **property rssi**

Alias for field number 4

### **property rx\_rate**

Alias for field number 2

### **property state**

Alias for field number 0

### **property tx\_power**

Alias for field number 5

### **property tx\_rate**

Alias for field number 1

## ConnectionTestResult

```
class canlib.kvrlib.ConnectionTestResult(rssi, rtt)
```

**property rssi**

Alias for field number 0

**property rtt**

Alias for field number 1

## ConnectionTest

```
class canlib.kvrlib.ConnectionTest(config_handle)
```

A connection test for a specific device

A connection test for a *RemoteDevice*, rdev, is created by:

```
test = rdev.connection_test()
```

While a connection test is running, the device will connect and start pinging itself to measure round-trip time (RTT) and Receive Signal Strength Indicator (RSSI).

A *ConnectionTest* is started with *ConnectionTest.start* and stopped with *ConnectionTest.stop*, after which its results are retrieved by *ConnectionTest.results*. If it is acceptable to block while the test is running, these three calls can be combined into *ConnectionTest.run*:

```
results = test.run(duration=10)
print(results)
```

Connection tests are automatically closed when garbage-collected, but they can also be closed manually with *ConnectionTest.close*.

**close()**

Close the internal handle

**results(maxresults=20)**

Get the results from a connection test

The test must have been running for any results to be available.

This function returns a *ConnectionTestResult*, which is a namedtuple of (rssi, rtt). Both rssi and rtt are tuples containing a number of individual results for RSSI and RTT.

**Parameters maxresults (int)** – The maximum number of rssi and rtt numbers to return. The returned rssi and rtt will be tuples with this long or the number of results available long, whichever is shortest.

**run(duration, maxresults=20)**

Run a connection test and return its results.

This function calls *ConnectionTest.start*, then blocks for duration seconds, then calls *ConnectionTest.stop* before finally returning the *ConnectionTestResult* from *ConnectionTest.results*.

### Parameters

- **duration (int)** – Seconds to run the test for.
- **maxresults (int)** – Passed to *ConnectionTest.results* as maxlen.

**start()**

Start the connection test

**stop()**

Stop the connection test

## openDevice()

`canlib.kvrlib.openDevice(channel_number, password="", validate_password=False)`

Create a *RemoteDevice* object bound to a channel number

### Parameters

- **channel\_number** (int) – CANlib channel number of the device to open
- **password** (str) – Password of the device, if any
- **validate\_password** (bool) – Whether the password should be validated (defaults to False).

This function checks that a remote-capable device is currently connection on the channel `channel_number`. If `validate_password` is True, it also checks that the password supplied is correct. If any of these checks fail, a `ValueError` will be raised.

## RemoteDevice

**class** `canlib.kvrlib.RemoteDevice(channel_number, password)`

A remote-capable Kvaser device

This class is normally instantiated with *openDevice*:

```
rdev = kvrlib.openDevice(CHANNEL_NUMBER)
```

Once this is done, the currently active profile can be accessed:

```
active = rdev.active_profile
```

All profiles, including the active one, are *ConfigProfile* objects, see that documentation for all the operations available for profile objects.

The full list of profiles a device has can be inspected using `rdev.profiles`. This is a *RemoteDevice.ProfileList* object, which works much like a list:

```
# The profile list can be indexed
first = rdev.profiles[0]

# We can check if a configuration belongs to this device with 'in'
assert first in rdev.profiles

# The length of the profile list is the number of profiles
num_profiles = len(rdev.profiles)

# Using the number of profiles, we can get the last one
last = rdev.profiles[num_profiles - 1]

# But negative indexes also work and are a better way of getting
# the last profile
```

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```
last = rdev.profiles[-1]

# You can also iterate over all profiles
for profile in rdev.profiles:
    ...
```

*RemoteDevice* also lets you access a variety of information about the specific device, as well as the ability to do a WLAN scan with *RemoteDevice.wlan\_scan*.

If the device is password protected, that password can be passed to *openDevice*:

```
protected_device = kvrlib.openDevice(0, password="Once upon a playground rainy")
```

After the object is created, the password is available as:

```
password = protected_device.password
```

The password can be changed with:

```
protected_device.password = "Wolves without teeth"
```

The reason the password is stored as clear-text is because it must be supplied to the underlying library each time an operation is done using this and related classes. This also means that the password is only validated, and required, when one of the functions requiring a password is called.

If the device is not password-protected, the password should be an empty string:

```
unprotected_device = kvrlib.openDevice(1)
assert unprotected_device.password == ''
```

**class ProfileList**(*channel\_number*)

The available profiles in a remote-capable device

This is the type of *RemoteDevice.profiles*. It implements the following:

- `len(profiles)`
- `profile in profiles`
- `profile[index]`

**property active\_profile**

The currently active profile

Activating another profile is done by assigning this attribute to another profile:

```
new_profile = remote_device.profiles[index]
remote_device.active_profile = new_profile
```

The value assigned to this property must be a *ConfigProfile* that belongs to this device, i.e. the following must be True:

```
new_profile in remote_device.profiles
```

Type *ConfigProfile*

**property address\_info**

Information about network address settings

---

**Note:** Accessing this attribute requires the correct password be set on the object.

---

Type *AddressInfo*

**property connection\_status**

Connection status information

The returned tuple is a (state, tx\_rate, rx\_rate, channel, rssi, tx\_power) namedtuple of:

1. state (*NetworkState*): Network connection state
2. tx\_rate (int): Transmit rate in kbit/s
3. rx\_rate (int): Receive rate in kbit/s
4. channel (int): Channel
5. rssi (int): Receive Signal Strength Indicator
6. tx\_power (int): Transmit power level in dB

---

**Note:** Accessing this attribute requires the correct password be set on the object.

---

Type *ConnectionStatus*

**connection\_test()**

Creates a connection test for this device

Returns *ConnectionTest*

See the documentation of *ConnectionTest* for more information.

---

**Note:** Accessing this attribute requires the correct password be set on the object.

---

**property hostname**

Device's hostname

---

**Note:** Accessing this attribute requires the correct password be set on the object.

---

Type str

**password\_valid()**

Checks whether the password set is valid

Returns bool – True if the password is valid, False otherwise.

**wlan\_scan(active=False, bss\_type=BasicServiceSet.ANY, domain=RegulatoryDomain.WORLD)**

Creates and starts a wlan scan for this device

Returns *WlanScan*

See the documentation of [WlanScan](#) for more information.

---

**Note:** Accessing this attribute requires the correct password be set on the object.

---

## WlanScan

**class** canlib.kvrlib.**WlanScan**(*config\_handle*)

A wlan scan for this device

The device starts scanning as soon as this object is created by [RemoteDevice.wlan\\_scan](#):

```
scan = rdev.wlan_scan()
```

When calling [RemoteDevice.wlan\\_scan](#), you can also specify whether the scan should be an active one, the Basic Service Set (bss) to use, and the regulatory domain:

```
scan = rdev.wlan_scan(
    active=True,
    bss=kvrlib.BasicServiceSet.INFRASTRUCTURE,
    domain=kvrlib.RegulatoryDomain.EUROPE_ETSI,
)
```

Results from the scan are retrieved by iterating over the [WlanScan](#) object:

```
for result in scan: print(result)
```

When getting the next result, the code will block until a new result is available or until no more results are available, in which case the iteration stops.

Wlan scans are automatically closed when garbage-collected, but they can also be closed manually with [WlanScan.close](#).

**close()**

Closes the internal handle

## WlanScanResult

**class** canlib.kvrlib.**WlanScanResult**(*rsssi, channel\_number, mac, bss\_type, ssid, security\_text*)

**property** **bss\_type**

Alias for field number 3

**property** **channel\_number**

Alias for field number 1

**property** **mac**

Alias for field number 2

**property** **rsssi**

Alias for field number 0

**property** **security\_text**

Alias for field number 5

**property** **ssid**

Alias for field number 4

## Structures

### kvrAddress

**class** canlib.kvrlib.kvrAddress

**TypeText** = {0: 'UNKNOWN', 1: 'IPV4', 2: 'IPV6', 3: 'IPV4\_PORT', 4: 'MAC'}

**Type\_IPV4** = 1  
IP v.4 address.

**Type\_IPV4\_PORT** = 3  
IP v.4 address with tcp-port.

**Type\_IPV6** = 2  
IP v.6 address.

**Type\_MAC** = 4  
Ethernet MAC address.

**Type\_UNKNOWN** = 0  
Unknown (e.g., no reply from device).

**address**  
Structure/Union member

**type**  
Structure/Union member

### kvrAddressList

**class** canlib.kvrlib.kvrAddressList(*num\_of\_structs=20*)

**STRUCT\_ARRAY**  
Structure/Union member

**elements**  
Structure/Union member

### kvrDeviceInfo

**class** canlib.kvrlib.kvrDeviceInfo

**accessibility**  
Structure/Union member

**accessibility\_pwd**  
Structure/Union member

**availability**  
Structure/Union member

**base\_station\_id**  
Structure/Union member



**client\_address**  
Structure/Union member

**connect()**

**device\_address**  
Structure/Union member

**disconnect()**

**ean\_hi**  
Structure/Union member

**ean\_lo**  
Structure/Union member

**encryption\_key**  
Structure/Union member

**fw\_build\_ver**  
Structure/Union member

**fw\_major\_ver**  
Structure/Union member

**fw\_minor\_ver**  
Structure/Union member

**host\_name**  
Structure/Union member

**name**  
Structure/Union member

**request\_connection**  
Structure/Union member

**reserved1**  
Structure/Union member

**reserved2**  
Structure/Union member

**ser\_no**  
Structure/Union member

**struct\_size**  
Structure/Union member

**usage**  
Structure/Union member

## kvrDeviceInfoList

**class** canlib.kvrlib.kvrDeviceInfoList(*deviceInfos*)

### STRUCT\_ARRAY

Structure/Union member

### elements

Structure/Union member

## kvrVersion

**class** canlib.kvrlib.kvrVersion

### major

Structure/Union member

### minor

Structure/Union member

## Service

canlib.kvrlib.service.**query**()

Queries the status of the helper service.

The helper service is installed as a part of the Windows CANlib driver package and is normally set to automatic start.

canlib.kvrlib.service.**start**()

Start the helper service.

The helper service is installed as a part of the Windows CANlib driver package and is normally set to automatic start.

canlib.kvrlib.service.**stop**()

Stop the helper service.

The helper service is installed as a part of the Windows CANlib driver package and is normally set to automatic start.

## Miscellaneous

**configActiveProfileSet**()

canlib.kvrlib.**configActiveProfileSet**(*channel*, *profile\_number*)

Set active profile.

**configActiveProfileGet()**

canlib.kvrlib.**configActiveProfileGet**(*channel*)

Get active profile.

**configNoProfilesGet()**

canlib.kvrlib.**configNoProfilesGet**(*channel*)

Get the maximum number of profile(s) the device can store.

When a remote device is connected to the host it can be configured. The remote device can hold a number of different profiles.

**deviceGetServiceStatus()**

canlib.kvrlib.**deviceGetServiceStatus**(*device\_info*)

Returns local connection status of the selected device.

**deviceGetServiceStatusText()**

canlib.kvrlib.**deviceGetServiceStatusText**(*device\_info*)

Returns local connection status of the selected device as ASCII text.

**dllversion()**

canlib.kvrlib.**dllversion**()

Get the kvrlib version number as a *VersionNumber*

**generate\_wep\_keys()**

canlib.kvrlib.**generate\_wep\_keys**(*pass\_phrase*)

Generates four 64-bit and one 128-bit WEP keys

**Parameters** *pass\_phrase* (str) – The pass phrase to use to generate the keys.

Returns a (key64, key128) (*WEKeys*) namedtuple, where key64 is a list of four bytes object with the four 64-bit WEP keys, and where `key128` is a bytes object with the single 128-bit WEP key.

**generate\_wpa\_keys()**

canlib.kvrlib.**generate\_wpa\_keys**(*pass\_phrase*, *ssid*)

Generate a WPA key from a pass phrase and ssid

**Parameters**

- **pass\_phrase** (str) – The pass phrase to use to generate the key.
- **ssid** (str) – The SSID to use to generate the key.

**Returns** bytes – The generated WPA key.

## hostname()

canlib.kvrlib.hostname(*ean*, *serial*)

Generate a hostname from ean and serial number

### Parameters

- **ean** ``EAN`` – European Article Number
- **serial** ``int`` – Serial number

## kvrDiscovery

**class** canlib.kvrlib.kvrDiscovery(*kvrlib=None*)

**clearDevicesAtExit**(*onoff*)

**close**()

**classmethod** **getDefaultAddresses**(*addressTypeFlag=AddressTypeFlag.BROADCAST*, *listSize=20*)

**getResults**()

**setAddresses**(*addressList*)

**setEncryptionKey**(*device\_info*, *key*)

**setPassword**(*device\_info*, *password*)

**setScanTime**(*delay\_ms*, *timeout\_ms*)

**start**(*delay\_ms=None*, *timeout\_ms=None*)

**storeDevices**(*deviceInfos*)

## kvrConfig

**class** canlib.kvrlib.kvrConfig(*kvrlib=None*, *channel=0*, *mode=0*, *password=""*, *profile\_no=0*)

**MODE\_ERASE** = 2

**MODE\_R** = 0

**MODE\_RW** = 1

**XML\_BUFFER\_SIZE** = 2046

**clear**()

**close**()

**getXml**()

**openEx**(*channel=None*, *mode=None*, *password=None*, *profile\_no=None*)

**setXml**()

**unload()**

`canlib.kvrlib.unload()`  
Unloads library stuff.

**verify\_xml()**

`canlib.kvrlib.verify_xml(xml_string)`  
Verify that the xml string complies with both the DTD and internal restrictions

**WEPPKeys**

**class** `canlib.kvrlib.WEPPKeys(key64, key128)`

**property** `key128`  
Alias for field number 1

**property** `key64`  
Alias for field number 0

**1.6.12 linlib****Exceptions****LinError**

**exception** `canlib.linlib.LinError`  
Base class for exceptions raised by the linlib class

Looks up the error text in the linlib dll and presents it together with the error code and the wrapper function that triggered the exception.

**LinGeneralError**

**exception** `canlib.linlib.LinGeneralError(status)`  
A linlib error that does not (yet) have its own Exception

**Warning:** Do not explicitly catch this error, instead catch `LinError`. Your error may at any point in the future get its own exception class, and so will no longer be of this type. The actual status code that raised any `LinError` can always be accessed through a `status` attribute.

## LinNoMessageError

**exception** `canlib.linlib.LinNoMessageError`  
Bases: `canlib.linlib.exceptions.LinError`  
No messages where available  
**status** = -1

## LinNotImplementedError

**exception** `canlib.linlib.LinNotImplementedError`  
Bases: `canlib.linlib.exceptions.LinError`  
Feature/function not implemented in the device  
**status** = -26

## Channel

### openChannel()

`canlib.linlib.openChannel(channel_number, channel_type, bps=None)`  
Open a channel to a LIN interface.

#### Parameters

- **channel\_number** (int) – The number of the channel. This is the same channel number as used by `canlib.openChannel`.
- **channel\_type** (`ChannelType`) – Whether the LIN interface will be a master or slave.
- **bps** (int or None) – If not None, `Channel.setBtrate` will be called with this value before the channel is returned.

**Returns** (`Channel`) – The opened channel

---

**Note:** For DRV Lin: The cable must be powered and connected to a LAPcan channel. For Kvaser LIN Leaf: The Leaf must be powered from the LIN side.

---

### openMaster()

`canlib.linlib.openMaster(channel_number, bps=None)`  
Open a channel as a master

This function simply calls `openChannel` with `channel_type` set to `ChannelType.MASTER`.

## openSlave()

`canlib.linlib.openSlave(channel_number, bps=None)`

Open a channel as a slave

This function simply calls `openChannel` with `channel_type` set to `ChannelType.SLAVE`.

## Channel

**class** `canlib.linlib.Channel(handle)`

A LINlib channel

This class is normally instantiated with `openMaster` or `openSlave`.

Channels are automatically closed on garbage collection, and can also be used as context managers in which case they close as soon as the context exits.

**busOff()**

Go bus off

This function deactivates the LIN interface. It will not participate further in the LIN bus traffic.

**busOn()**

Go bus on

This function activates the LIN interface.

**clearMessage(msg\_id)**

Clear a message buffer for a LIN slave

The message buffer will not answer next time it is polled.

**close()**

Close this LINlib channel

Closes an open handle to a LIN channel.

---

**Note:** It is normally not necessary to call this function directly, as the internal handle is automatically closed when the `Channel` object is garbage collected.

---

New in version 1.6.

**getCanHandle()**

Return the CAN handle given an open LIN handle

**getFirmwareVersion()**

Retrieve the firmware version from the LIN interface

Returns a `FirmwareVersion` namedtuple containing `boot_version` and `app_version` that are `canlib.VersionNumber` namedtuples. If only one of these is needed, the return value can be unpacked as such:

```
boot_ver, app_ver = channel.getFirmwareVersion()
```

---

**Note:** For newer interfaces use `getChannelData` with `ChannelData.CARD_FIRMWARE_REV` instead.

The version numbers aren't valid until `Channel.busOn` has been called.

The firmware in the LIN interface is divided into two parts, the boot code and the application. The boot code is used only when reprogramming (reflashing) the LIN interface. The application handles all LIN communication.

Version numbers are, since the precambrian era, divided into a major version number, a minor version number and a build number. These are usually written like, for example, 3.2.12. Here the major number is 3, the minor number 2 and the build number 12.

---

**read**(*timeout=0*)

Read a message from the LIN interface

If a message is available for reception, `linOK` is returned. This is a non-blocking call. It waits until a message is received in the LIN interface, or the specified timeout period elapses.

This may return a frame sent by `writeMessage` or `writeWakeup`.

---

**Note:** This call will also return echoes of what the LIN interface is transmitting with `writeMessage`. In other words, the LIN interface can hear itself.

---

**Parameters** `timeout` (int) – Timeout in milliseconds.

**Returns** (`canlib.LINFrame`)

**requestMessage**(*msgid*)

Request a message from a slave

This function writes a LIN message header to the LIN bus. A slave in the system is then expected to fill in the header with data.

---

**Note:** This call is only available in master mode.

---

**setBitrate**(*bps*)

Set the bitrate in bits per second

This function sets the bit rate for a master, or the initial bit rate for a slave. The LIN interface should not be on-bus when this function is called.

---

**Note:** The LIN Interface should not be on bus. Supported bit rates are 1000 - 20000 bits per second.

---

**setUpIllegalMessage**(*msgid, disturb\_flags, delay*)

Create a corrupted LIN message

Using this function, it is possible to use the LIN interface to create corrupted LIN messages. You call the function once for each LIN identifier that should be affected.

To return to normal mode, either restart the LIN interface (by going off bus and on the bus again) or call the function with `delay` and `disturb_flags` set to zero.

**Parameters**

- `msgid` (int) – The identifier of the LIN message
- `disturb_flags` (`MessageDisturb`) – One or more of the `MessageDisturb` flags.
- `delay` (int) – The delay parameter will result in a delay of this many bittimes after the header and before the first data byte.



---

**Note:** The LIN Interface must be on bus for this command to work. It is supported in firmware version 2.4.1 and later.

---

**setupLIN**(*flags=Setup.VARIABLE\_DLC, bps=0*)

Setup the LIN interface

This function changes various settings on a LIN Interface that is on bus. When going on bus, the bit rate and the flag values listed below are set to the default value (either as hard-coded in the firmware, or as stored in the non-volatile memory of the LIN Interface).

With this function, you can do one or more of the following things:

- Select checksum according to LIN 2.0
- Turn variable message length off. The message length then will depend on the message ID.

In master mode it is also possible to change the bit rate without going off bus first.

---

**Note:** The LIN Interface must be on bus for this command to work. It is supported in firmware version 2.5.1 and later. For LIN 2.0 compliance, you must specify both LIN\_ENHANCED\_CHECKSUM and LIN\_VARIABLE\_DLC.

---

#### Parameters

- **flags** (*Setup*) – One or more of the *Setup* flags
- **bps** (*int*) – The bit rate in bits per second. This parameter can be used only in master mode. The bit rate is set without going off bus.

**updateMessage**(*frame*)

Update a message buffer in a slave

This function updates a message buffer in a slave. The contents of the message buffer will be used the next time the slave is polled for the specified LIN message id.

---

**Note:** The LIN Interface must be on bus.

---

**Parameters frame** (*canlib.Frame*) – The information to be updated. Only the *Frame.id*, *Frame.data*, and *Frame.dlc* attributes are used. Note that the frame can, but not need not, be a *LINFrame*.

**writeMessage**(*frame*)

Write a LIN message

Write a LIN message. It is advisable to wait until the message is echoed by *read* before transmitting a new message, or in case of a schedule table being used, transmit the next message when the previous one is known to be complete.

---

**Note:** Only available in master mode

---

**Parameters frame** (*canlib.Frame*) – *Frame.data*, and *Frame.dlc* attributes are used. Note that the frame can, but not need not, be a *LINFrame*.

**writeSync**(*timeout*)

Make sure all message transmitted to the interface have been received

*timeout* is in milliseconds.

When messages are transmitted to the LIN Interface, they are queued by the driver before appearing on the CAN bus.

If the LIN Interface is in master mode and a LIN message has been transmitted with *writeMessage*, this function will return when the LIN Interface has received the message. If another LIN message is being received or transmitted, the message will not be transmitted on the LIN bus at once. And even if the LIN Interface is idle, the header of the new message will just have been started when *writeSync* returns.

After calling *updateMessage* and *clearMessage* for a slave, this function is enough to know that the LIN Interface is updated.

After *writeMessage*, it is advisable to wait until the message is echoed by *read* before transmitting a new message, or in case of a schedule table being used, transmit the next message when the previous one is known to be complete.

When, in master mode, a message should be transmitted after a poll (reception) is done, it might be necessary to call *writeMessage* before the result is received via *read* as the LIN Interface waits up to the maximum frame length before knowing a received message is complete. A new message to transmit will force completion if the currently received one.

**writeWakeup**(*count=0, interval=1*)

Write one or more wakeup frames

If *count* is zero (the default), one single wakeup frame is transmitted. If *count* > 1, several wakeup frames are transmitted spaced with *interval* bit times. The LIN interface will interrupt the sequence when a LIN message or another command is received. The stream of wakeups will be received as incoming messages with the *MessageFlag.RX* flag.

**Parameters**

- **count** (int) – The number of wakeup frames to send.
- **interval** (int) – The time, in bit times, between the wakeup frames.

**FirmwareVersion**

```
class canlib.linlib.FirmwareVersion(boot_version, app_version)
```

**property app\_version**

Alias for field number 1

**property boot\_version**

Alias for field number 0

## Enumerations

### ChannelData

```
class canlib.linlib.ChannelData(value)
    linCHANNELDATA_XXX

    These defines are used in getChannelData.

    CARD_FIRMWARE_REV = 9
        Firmware version from the LIN interface.
```

### ChannelType

```
class canlib.linlib.ChannelType(value)
    Flags for openChannel

    MASTER = 1
        The LIN interface will be a LIN master

    SLAVE = 2
        The LIN interface will be a LIN slave
```

## Error

```
class canlib.linlib.Error(value)
    An enumeration.

    CANERROR = -15
        Internal error in the driver

    DRIVER = -18
        CAN driver type not supported

    DRIVERFAILED = -19
        DeviceIOControl failed

    ERRRESP = -16
        There was an error response from the LIN interface

    INTERNAL = -22
        Internal error in the driver

    INVHANDLE = -14
        Handle is invalid

    LICENSE = -21
        The license is not valid

    MASTERONLY = -5
        The function is only for a master.

    NOCARD = -20
        The card was removed or not inserted

    NOCHANNELS = -10
        No channels available
```

**NOHANDLES = -13**  
Can't get handle

**NOMEM = -9**  
Out of memory

**NOMSG = -1**  
No messages available

**NOTFOUND = -8**  
Specified hardware not found. This error is reported when the LIN transceiver isn't powered up

**NOTINITIALIZED = -12**  
Library not initialized

**NOTRUNNING = -3**  
Handle not on-bus. Some functions requires that the handle is on-bus before being called.

**NOT\_IMPLEMENTED = -26**  
The requested feature or function is not implemented in the device you are trying to use it on

**NO\_ACCESS = -23**  
Access denied

**NO\_REF\_POWER = -25**  
Function not supported in this version

**PARAM = -7**  
Error in parameter

**RUNNING = -4**  
Handle not off-bus. Some functions requires that the handle is off-bus before being called.

**SLAVEONLY = -6**  
The function is only for a slave.

**TIMEOUT = -11**  
Timeout occurred

**VERSION = -24**  
Function not supported in this version

**WRONGRESP = -17**  
The LIN interface response wasn't the expected one

## MessageDisturb

```
class canlib.linlib.MessageDisturb(value)
    LIN illegal message flags

    CSUM = 1
        The checksum of transmitted messages will be inverted

    PARITY = 2
        The two parity bits will be inverted, used only in master mode.
```

## MessageFlag

**class** canlib.linlib.**MessageFlag**(*value*)

LIN message flags

The following flags is used in *LINFrame.flags*.

**BIT\_ERROR = 128**

Bit error when transmitting.

**CSUM\_ERROR = 16**

Checksum error

**NODATA = 8**

No data, only a header.

**PARITY\_ERROR = 32**

ID parity error

**RX = 2**

The message was something we received from the bus.

**SYNCH\_ERROR = 64**

A synch error

**SYNC\_ERROR = 64**

A synch error

**TX = 1**

The message was something we transmitted on the bus.

**WAKEUP\_FRAME = 4**

## MessageParity

**class** canlib.linlib.**MessageParity**(*value*)

LIN message parity

- *MessageParity.STANDARD* == LIN\_MSG\_USE\_STANDARD\_PARITY
- *MessageParity.ENHANCED* == LIN\_MSG\_USE\_ENHANCED\_PARITY

**ENHANCED = 8**

Use enhanced (2.x) parity for the specified msg

**STANDARD = 4**

Use standard (1.x) parity for the specified msg

## Setup

**class** canlib.linlib.**Setup**(*value*)

Used in *Channel.setupLIN*

**ENHANCED\_CHECKSUM = 1**

When specified, the LIN interface will use the “enhanced” checksum according to LIN 2.0. Note that as per the LIN 2.0 spec) the enhanced checksum is not used on the diagnostic frames even if the *Setup.ENHANCED\_CHECKSUM* setting is in effect.

**VARIABLE\_DLC = 2**

When specified, turns variable message length on, so the the message length will depend on the message ID.

## MessageInfo

**class canlib.linlib.MessageInfo**

Provides more information about the LIN message.

The precision of the timing data given in us (microseconds) can be less than one microsecond; for low bitrates the lowest bits might always be zero.

The min and max values listed inside [] of the message timing values can be calculated from the LIN specification by using the shortest (0 bytes) or longest (8 bytes) messages at the lowest or highest allowed bitrate.

---

**Note:** The LIN interface will accept messages that are a bit out-of-bounds as well.

---

**timestamp**

Kvaser DRV Lin timestamp - Timestamp in milliseconds of the falling edge of the synch break of the message. Uses the canlib CAN timer.

Kvaser LIN Leaf timestamp - Timestamp in milliseconds of the falling edge of the synch break of the message. Uses the canlib CAN timer.

---

**Note:** All Kvaser Leaf with Kvaser MagiSync&tm; are synchronized (also with CAN channels).

---

**bitrate**

The bitrate of the message in bits per seconds. Range [1000 .. 20000] (plus some margin)

**byteTime**

Start time in microseconds of each data byte. In case of 8-byte messages, the crc time isn't included (but can be deduced from frameLength).

---

**Note:** Not supported by all devices.

---

**checksum**

The checksum as read from the LIN bus. Might not match the data in case of *MessageFlag.CSUM\_ERROR*.

**frameLength**

The total frame length in microseconds; from the synch break to the end of the crc. [2200 .. 173600]

**idPar**

The id with parity of the message as read from the LIN bus. Might be invalid in case of *MessageFlag.PARITY\_ERROR*.

**synchBreakLength**

Length of the synch break in microseconds. [650 .. 13000], [400 .. 8000] for a wakeup signal.

**synchEdgeTime**

Time in microseconds of the falling edges in the synch byte relative the falling edge of the start bit.

---

**Note:** Not supported by all devices.

---

## Miscellaneous

### dllversion()

canlib.linlib.dllversion()

Retrieve the LIN library version as a *VersionNumber*

---

**Note:** Requires CANlib v5.3

---

### getChannelData()

canlib.linlib.getChannelData(*channel\_number*, *item=ChannelData.CARD\_FIRMWARE\_REV*)

This function can be used to retrieve certain pieces of information about a channel.

---

**Note:** You must pass a channel number and not a channel handle.

---

#### Parameters

- **channel** (*int*) – The number of the channel you are interested in. Channel numbers are integers in the interval beginning at 0.
- **item** (*ChannelData*) – This parameter specifies what data to obtain for the specified channel. Currently the only item available is *CARD\_FIRMWARE\_REV*, which is the default.

### getTransceiverData

canlib.linlib.getTransceiverData(*channel\_number*)

Get the transceiver information for a CAN channel

The application typically uses this call to find out whether a particular CAN channel has a LIN interface connected to it. For a Kvaser LIN Leaf it retrieves the transceiver type and device information.

This function call will open the CAN channel, but no CAN messages are transmitted on it. In other words, it's risk-free to use even if no LIN interface is connected, or if the channel is connected to a CAN system.

---

**Note:** Attempts to use the channel for LIN communication will be meaningful only if the returned *TransceiverData*'s *~type~* attribute is one of *TransceiverType.LIN* or *TransceiverType.CANFD\_LIN*

A LIN interface need not be powered for this call to succeed.

The information may not always be accurate. Especially after changing transceiver on a running LAPcan card, you should go on bus and off bus again to be sure the transceiver information is updated.

---

## initializeLibrary

`canlib.linlib.initializeLibrary()`  
Initialize LINlib

---

**Note:** LINlib is automatically initialized when `canlib.linlib` is imported. This function is only necessary when LINlib has been manually unloaded with `unloadLibrary`.

---

## TransceiverData

`class canlib.linlib.TransceiverData(ean, serial, type)`

**property ean**  
Alias for field number 0

**property serial**  
Alias for field number 1

**property type**  
Alias for field number 2

## unloadLibrary

`canlib.linlib.unloadLibrary()`  
Deinitialize LINlib

This function de-initializes the LIN library. After this function is called `linInitializeLibrary` must be called before any other LIN function is called.

## 1.6.13 j1939

This module holds definitions of J1939 Protocol Data Unit (PDU) frames.

Example of usage:

```
>>> from canlib import Frame, j1939
>>> from canlib.canlib import MessageFlag
>>> def frame_from_pdu(pdu):
...     can_id = j1939.can_id_from_pdu(pdu)
...     frame = Frame(
...         id=can_id,
...         data=pdu.data,
...         flags=MessageFlag.EXT,
...     )
...     return frame
>>> pdu = j1939.Pdu1(
...     p=3, edp=0, dp=0, pf=0x99, ps=0xfe, sa=0xfe,
...     data=[1]
... )
```

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```
>>> frame_from_pdu(pdu)
Frame(id=211418878, data=bytearray(b'\x01'), dlc=1, flags=<MessageFlag.EXT: 4>,
↳timestamp=None)
```

The particular characteristics of J1939 are:

- Extended CAN identifier (29 bit)
- Bit rate 250 kbit/s
- Peer-to-peer and broadcast communication
- Transport protocols for up to 1785 data bytes
- Network management
- Definition of parameter groups for commercial vehicles and others
- Manufacturer specific parameter groups are supported
- Diagnostics features

### (Extended) Data Page Bit

Extended Data page	Data page	Description
0	0	SAE J1939 Page 0 Parameter Groups
0	1	SAE J1939 Page 1 Parameter Groups (NMEA2000)
1	1	SAE J1939 reserved
1	1	ISO 15765-3 defined

New in version 1.18.

### Protocol Data Units

**class** canlib.j1939.Pdu(\*, p: int, edp: int, dp: int, pf: int, ps: int, sa: int, data: List[int] = None)  
Protocol Data Unit in j1939.

Base class with attributes common to *Pdu1* and *Pdu2*

**data:** Optional[List[int]]  
data field

**dp:** int  
data page

**edp:** int  
extended data page

**p:** int  
priority

**pf:** int  
PDU format

**ps:** int  
PDU specific

**sa:** int  
source address

**class** canlib.j1939.Pdu1(\*, p: int, edp: int, dp: int, pf: int, ps: int, sa: int, data: List[int] = None, da: int = None, pgn: int = None)

Protocol Data Unit, Format 1

When *Pdu.pf* < 240, the PDU Specific field is a Destination Address and

*pgn* = Extended Data Page + Data Page + PDU Format + "00"

**da:** Optional[int]  
destination address, *Pdu.ps*

**pgn:** Optional[int]  
parameter group number

**class** canlib.j1939.Pdu2(\*, p: int, edp: int, dp: int, pf: int, ps: int, sa: int, data: List[int] = None, ge: int = None, pgn: int = None)

Protocol Data Unit, Format 2

When *Pdu.pf* >= 240, the PDU Specific field is the Group Extension

*pgn* = Extended Data Page + Data Page + PDU Format + Group Extension

**ge:** Optional[int]  
group extension, equal to *Pdu.ps*

**pgn:** Optional[int]  
parameter group number

## Converting CAN Id

For a j1939 message, the CAN identifier is divided into the following fields:

Priority	Extended Data Page	Data Page	PDU Format	PDU Specific	Source Address
3 bit	1 bit	1 bit	8 bit	8 bit	8 bit

Use *pdu\_from\_can\_id* and *can\_id\_from\_pdu* to convert.

canlib.j1939.pdu\_from\_can\_id(*can\_id*)

Create j1939 Protocol Data Unit object based on CAN Id.

**Parameters** *can\_id* (int) – CAN Identifier

**Returns** *Pdu1* or *Pdu2* depending on value of *can\_id*

canlib.j1939.can\_id\_from\_pdu(*pdu*)

Extract CAN Id based on j1939 Protocol Data Unit object.

**Parameters** *pdu* (*Pdu1* or *Pdu2*) – Protocol Data Unit

**Returns** *can\_id* (int) – CAN Identifier

## RELEASE NOTES

### 2.1 Release Notes

This is the release notes for the pycanlib module.

#### Contents

- *Release Notes*
  - *New Features and Fixed Problems in V1.19.205 (13-SEP-2021)*
  - *New Features and Fixed Problems in V1.18.846 (25-MAY-2021)*
  - *New Features and Fixed Problems in V1.17.748 (16-FEB-2021)*
  - *New Features and Fixed Problems in V1.16.588 (09-SEP-2020)*
  - *New Features and Fixed Problems in V1.15.483 (27-MAY-2020)*
  - *New Features and Fixed Problems in V1.14.428 (02-APR-2020)*
  - *New Features and Fixed Problems in V1.13.390 (24-FEB-2020)*
  - *New Features and Fixed Problems in V1.12.251 (08-OCT-2019)*
  - *New Features and Fixed Problems in V1.11.226 (13-SEP-2019)*
  - *New Features and Fixed Problems in V1.10.102 (12-MAY-2019)*
  - *New Features and Fixed Problems in V1.9.909 (03-MAR-2019)*
  - *New Features and Fixed Problems in V1.8.812 (26-NOV-2018)*
  - *New Features and Fixed Problems in V1.7.741 (16-SEP-2018)*
  - *New Features and Fixed Problems in V1.6.615 (13-MAY-2018)*
  - *New Features and Fixed Problems in V1.5.525 (12-FEB-2018)*
  - *New Features and Fixed Problems in V1.4.373 (13-SEP-2017)*
  - *New Features and Fixed Problems in V1.3.242 (05-MAY-2017)*
  - *New Features and Fixed Problems in V1.2.163 (15-FEB-2017)*
  - *New Features and Fixed Problems in V1.1.23 (28-SEP-2016)*
  - *New Features and Fixed Problems in V1.0.10 (15-SEP-2016)*

### 2.1.1 New Features and Fixed Problems in V1.19.205 (13-SEP-2021)

- General:
  - Updated docstrings, mainly of lower level classes.
- `canlib.dllLoader`:
  - Setting the environment variable `READTHEDOCS == True` inhibits loading of shared libraries. Used e.g. when building documentation on ReadTheDocs.
- `canlib.kvamemolibxml`:
  - The functions `xmlGetLastError`, `xmlGetValidationWarning` and `xmlGetValidationError` now returns enum classes when possible.
- `canlib.kvrlib`:
  - Minor readability updates for `kvrDeviceInfo.__str__`

### 2.1.2 New Features and Fixed Problems in V1.18.846 (25-MAY-2021)

- `canlib.canlib`:
  - Added LEDs 4 through 11 to `canlib.canlib.LEDAction` (needs CANlib v5.19+).
- `canlib.kvadblib`:
  - Default value of EnumAttribute is now returned as `int`
  - Added wrapper for `kvaDbGetMsgByPGNEx`
- `canlib.kvlclib`:
  - Added wrapper for `kvlcFeedLogEvent`
- Added `canlib.j1939` module for some j1939 helpers.

### 2.1.3 New Features and Fixed Problems in V1.17.748 (16-FEB-2021)

- `canlib.canlib`:
  - Corrected `set_bus_params_tq` regarding type of flag attribute.
  - Added support for using `setBusParams` and `getBusParams` for channels that were opened using `BusParamsTq`.
  - Added `Bitrate` and `BitrateFD` enums for use with `setBusParams` and `openChannel`. `canlib.canBITRATE_xxx` and `canlib.canFD_BITRATE_xxx` constants are still supported but deprecated.
  - Added enum member `BITRATE_8M_80P` to `BitrateFD` and constant `canlib.canFD_BITRATE_8M_80P`.
- `canlib.kvlclib`
  - Added exception `KvlcFileExists`.

## 2.1.4 New Features and Fixed Problems in V1.16.588 (09-SEP-2020)

- `canlib.canlib`:
  - Added support for new bus parameter API in CANlib v.5.34. See section *Set CAN Bitrate* for more information.
  - Added attributes to `canlib.IOControl.__dir__` and `canlib.ChannelData.__dir__` in order to better support auto completion in IDEs.
  - Deprecated `canlib.Device.channel`, use `canlib.Device.open_channel` instead, which correctly handles keyword arguments
  - Added new Open flag `canlib.canlib.Open.NOFLAG` for parameter flags.
- `canlib.kvadbllib`:
  - Corrected *interpret* when looking for CAN messages with extended id.
  - Updated *get\_message* so that it requires EXT (bit 31) to be set on id if using extended id:s.
  - Added a new argument `flags` to *get\_message\_by\_id*. If using messages with extended id:s, EXT should be set on `flags`.
- `canlib.kvlclib`:
  - The `file_format` parameter in `canlib.kvlclib.Converter.setInputFile` now accepts *ReaderFormat* as well.
  - Added a newer version of the BLF format, now also with CAN FD support ‘`canlib.kvlclib.FileFormat.VECTOR_BLF_FD`’. The format has both read and write capabilities.

## 2.1.5 New Features and Fixed Problems in V1.15.483 (27-MAY-2020)

- Dropped support for v2.7, v3.4 and v3.5, added v3.7 and v3.8.

## 2.1.6 New Features and Fixed Problems in V1.14.428 (02-APR-2020)

- Minor changes.

## 2.1.7 New Features and Fixed Problems in V1.13.390 (24-FEB-2020)

- `canlib.canlib`:
  - Added *HandleData* to wrap `canGetHandleData`. Also added *channel\_data* as a helper function.
  - `IOControl` now returns utf-8 decoded strings instead of “bytes in string”.
  - Fixed a bug where `isconnected` would return `False` if the `channel_number` attribute was larger than the total number of available CANlib channels, regardless of if the device was connected or not.
- `canlib`:
  - Corrected *Frame* comparison (`!=`) with other types, e.g. `None`

### 2.1.8 New Features and Fixed Problems in V1.12.251 (08-OCT-2019)

- Minor changes.

### 2.1.9 New Features and Fixed Problems in V1.11.226 (13-SEP-2019)

- `canlib.canlib`:
  - Added a slight delay in `get_bus_statistics` because the underlying functions in CANlib are asynchronous.
  - Added `read_error_counters` and `iocontrol clear_error_counters`.
  - Added `getBusOutputControl`.
  - Added `fileDiskFormat` that formats the disk in a remote device, i.e Kvaser DIN Rail.
- `canlib.BoundSignal.value`:
  - If the signal is an enum-signal, and the signal's value is not found in the enum definition, the raw value is now returned.
- `canlib.kvmlib`:
  - Marked using `kvmlib` class as deprecated (was deprecated in v1.6)
  - Replaced `estimate_events` with `Kme.event_count_estimation` in order to have same name as `LogFile.event_count_estimation`. Old function name is now deprecated.
  - When found, new 64 bit version of the dll call, `kvmLogFileMountEx`, `kvlcEventCountEx`, and `kvmKmeCountEventsEx` (added in CANlib v5.29), is now used.
  - Added `log_type` for supporting the different log types generated by Kvaser Memorator Light HS v2.
- `canlib.kvadblib`:
  - `Dbc` raises `KvdDbFileParse` if the `dbc` file loaded contains syntax errors.

### 2.1.10 New Features and Fixed Problems in V1.10.102 (12-MAY-2019)

- Reference documentation has been restructured.
- `Channel`:
  - Added support for slicing environment variables declared as char. Replaced low level function `scriptEnvvarSetData` with `script_envvar_set_data` and added `DataEnvVar` which is now returned when a char envvar is returned.
- `canlib.kvadblib`:
  - Error messages from the CAN database parser in `Dbc` can be retrieved using `get_last_parse_error()`.

### 2.1.11 New Features and Fixed Problems in V1.9.909 (03-MAR-2019)

- `canlib.kvadblib`:
  - Error texts are now fetched from the dll using `kvaDbGetErrorText()`.
- `canlib.kvlclib`:
  - Added support for DLC mismatch handling included in CANlib v5.27
- `canlib.kvDevice`:
  - The `canlib.kvDevice.kvDevice` class is now deprecated, use `canlib.Device` instead
- `canlib.Device`:
  - Added method `Device.issubset` as a helper to find loosely specified devices.
- `canlib.canlib.iopin`:
  - Added attributes `fw_version` and `serial` to `IoPin`. To read these attributes, CANlib v5.27 is needed.
  - `AddonModule` is a new class, holding attributes of one add-on module.
  - `Config.modules` is now an attribute, calculated at creation time and containing an ordered list of `AddonModule` objects. The old functionality has been moved to `Config._modules`
  - `Config.issubset` is a new method to identify if a configuration contains the expected add-on modules.

### 2.1.12 New Features and Fixed Problems in V1.8.812 (26-NOV-2018)

- `canlib.canlib`:
  - Fixed issue were `Channel.handle` attribute would not be initialized when opening of the channel failed.
  - Added experimental support for accessing IO-pins on sub modules of the Kvaser DIN Rail SE 400S that was added to CANlib v5.26. This includes a new module `canlib.canlib.iopin`.
- `canlib.kvadblib`:
  - Fixed issue with signals were multiplexing mode, and scaling (factor and offset) returned wrong values from a loaded `.dbc` file.
  - Added `show_all` argument to `Dbc.messages`. `Dbc.__iter__` now set `show_all` to `False` in order to skip `VECTOR__INDEPENDENT_SIG_MSG` messages.

### 2.1.13 New Features and Fixed Problems in V1.7.741 (16-SEP-2018)

- `canlib.kvmlib`:
  - Added `canlib.kvmlib.event_count_estimation`
  - Added `canlib.kvmlib.kme` Previous `kvmlib.kmeXXX` functions are now deprecated.
- `canlib.canlib`:
  - Added `canlib.canlib.ScriptStatus`
  - Added enums to `canlib.canlib.ChannelCap`
  - Fixed `canlib.canlib.canWriteSync`
- `canlib.kvlclib`:
  - Added API to access information about reader formats.

- Added `kvclib.Property` to replace old `PROPERTY_XXX` constants which are now deprecated.
- Added `kvclib.reader_formats` and `kvclib.writer_formats` to replace now deprecated `kvclib.WriterFormat.getFirstWriterFormat` and `kvclib.WriterFormat.getNextWriterFormat`.

## 2.1.14 New Features and Fixed Problems in V1.6.615 (13-MAY-2018)

- Updated for CANlib SDK v5.23.
- Getting version numbers should now be done with `dllversion()`, which will return `canlib.BetaVersionNumber` if the dll is marked as Beta. Also added `canlib.prodversion()` to return the CANlib product version number.
- `canlib.device`:
  - New `canlib.device.Device` class (available as `canlib.Device`) that is a simpler version of `kvDevice`. `canlib.device.Device` objects can be defined using an EAN and serial number, or a connected device can be searched for using `canlib.device.Device.find`. These objects do not require the device to stay connected, and can be used to later create most other canlib objects, e.g. `canlib.canlib.Channel`, `canlib.kvmlib.Memorator`, etc.
  - New `canlib.device.connected_devices` which returns an iterator of `canlib.device.Device` objects, one for each device currently connected.
- `canlib.ean`:
  - `canlib.ean.EAN` objects can be tested for equality, both with other `canlib.ean.EAN` objects and with strings.
  - Added `CanNotFound` exception.
  - `canlib.ean.EAN` objects can now be directly instantiated from string, i.e. `ean = canlib.EAN(ean_string)` instead of `ean = canlib.EAN.from_string(ean_string)`.
  - `canlib.ean.EAN` objects can be converted back into any of the representations that can be used to create them. See the documentation of `canlib.ean.EAN` for more info.
  - `canlib.ean.EAN` objects can be indexed and iterated upon, yielding the digits as ints.
- `canlib.canlib`:
  - `canlib.canlib.EnvVar` object raises `EnvvarNameError` when given an illegal name, instead of `AssertionError`.
  - `canlib.canlib.openChannel` can now set the bitrate of the channel opened.
  - `canlib.canlib.Channel` objects automatically close their handles when garbage collected
  - `canlib.canlib.Channel` has new methods `canlib.canlib.Channel.scriptRequestText` and `canlib.canlib.Channel.scriptGetText` to get text printed with `printf()` by a script. This text is returned as a `canlib.canlib.ScriptText` object.
- `canlib.kvamemolibxml`:
  - A new, object oriented way of dealing with `kvamemolibxml` using `canlib.kvamemolibxml.Configuration` objects.
- `canlib.kvmlib`:
  - Improved object model
    - \* New `canlib.kvmlib.openDevice` function that returns a `canlib.kvmlib.Memorator` object representing a connected Memorator device. See the documentation of `canlib.kvmlib.Memorator` for instructions on how to use this new class to more easily interface with your Memorators.



- \* New `canlib.kvmlib.openKmf` function for opening .KMF files that returns a `canlib.kvmlib.Kmf` object that is similar to `canlib.kvmlib.Memorator`. See the docstring of `canlib.kvmlib.Kmf` for more information.
- `canlib.linlib`:
  - Getting version number with `canlib.linlib.dllversion` (requires CANlib SDK v5.23 or newer).
  - Explicit `canlib.linlib.Channel.close` function for forcing a linlib channel's internal handle to be closed.
- `canlib.canlib`:
  - Added support for accessing information within compiled t program (.txe) files.
    - \* Added wrapper function for `kvScriptTxeGetData`.
    - \* Added compiled t program (.txe) interface class `canlib.canlib.Txe`.
- `canlib.kvadblib`:
  - enums now returns non-empty dictionary in attribute definition returned from `EnumDefinition.definition`

## 2.1.15 New Features and Fixed Problems in V1.5.525 (12-FEB-2018)

- Updated for CANlib SDK v5.22.
- Added support for LIN bus API (LINlib)
- Added support for Database API (kvaDbLib) Needs version v5.22 of CANlib SDK to get supported dll.

Restructuring of code in order to make the API simpler and the code base more maintainable have resulted in the following changes (old style is deprecated, shown in details while running Python with the `-Wd` argument):

- `canlib.kvMessage` has been renamed `canlib.Frame`
  - `canlib.Frame` objects are now accepted and returned when writing and reading channels.
  - The new `canlib.kvadblib` module uses these `canlib.Frame` objects heavily.
- `canlib.canlib`:
  - Added wrapper functions for `canReadStatus` and `canRequestChipStatus`
  - Deprecated use of `canlib.canlib.canlib()` objects; all methods have been moved to the module.
    - \* See the docstring of `canlib.canlib.CANLib` for more information
  - Simplified the names of the channel-classes (old names are deprecated):
    - \* The channel class is now `canlib.canlib.Channel`, instead of `canlib.canChannel`.
    - \* `canlib.canlib.ChannelData_Channel_Flags` is now `canlib.canlib.ChannelFlags`
    - \* `canlib.canlib.ChannelData_Channel_Flags_bits` is now `canlib.canlib.ChannelFlagBits`
  - `canlib.canlib.Channel` now uses `canlib.Frame` objects for reading and writing.
    - \* `canlib.Channel.read` now returns a `canlib.Frame` object instead of a tuple. However, `canlib.Frame` objects are largely compatible with tuples.
    - \* `canlib.Channel.write` takes a single argument, a `canlib.Frame` object. The previous call signature has been taken over by `canlib.Channel.write_raw`.
    - \* Likewise for `canlib.Channel.writeWait` and its new friend `canlib.Channel.writeWait_raw`.

- The class `canlib.canlib.canVersion` has been removed, and `canlib.canlib.getVersion` now returns a `canlib.VersionNumber`. The new class still supports conversion to string and accessing `.major` and `.minor` attributes.
- `canlib.kvmlib`:
  - Added wrapper functions for `kvmKmeReadEvent`.
  - Corrected encoding for Python 3 in `kmeOpenFile()`.
  - Deprecated names for several classes to make them more logical and more pythonic:
    - \* `canlib.kvmlib.memoMsg` is now `canlib.kvmlib.LogEvent`
    - \* `canlib.kvmlib.logMsg` is now `canlib.kvmlib.MessageEvent`
    - \* `canlib.kvmlib.rtcMsg` is now `canlib.kvmlib.RTCEvent`
    - \* `canlib.kvmlib.trigMsg` is now `canlib.kvmlib.TriggerEvent`
    - \* `canlib.kvmlib.verMsg` is now `canlib.kvmlib.VersionEvent`
  - The class `canlib.kvmlib.kvmVersion` has been removed, and `canlib.kvmlib.KvmLib.getVersion` now returns a `canlib.VersionNumber`. The new class still supports conversion to string and accessing `.major`, `.minor`, and `.build` attributes.
- `canlib.kvlclib`:
  - Added method `canlib.kvlclib.addDatabaseFile` and helper object `canlib.kvlclib.ChannelMask`.
  - The `canlib.kvlclib.KvlcLib` object has been deprecated.
    - \* All functions that relate to converters have been moved to the more appropriately named `canlib.kvlclib.Converter`.
      - Some of these functions have been renamed:
      - `IsOutputFilenameNew`, `IsOverrunActive`, and `IsDataTruncated` have all had their initial “i” lower-cased, as the upper case “I” was an error.
      - `getPropertyDefault` and `isPropertySupported` are no longer available on the `Converter` object, they must be accessed via the `format` attribute:

```
converter.format.getPropertyDefault(...)
```
    - \* `canlib.kvlclib.WriterFormat.getFirstWriterFormat` and `canlib.kvlclib.WriterFormat.getNextWriterFormat` now returns a `kvlclib.FileFormat` object (which is based on the `IntEnum` class).
    - \* Other functions have been moved to the `canlib.kvlclib` module.
    - \* `deleteConverter` is no longer supported. Instead, converters are automatically deleted when garbage collected. If their contents must be flushed to file, see the new `canlib.kvlclib.Converter.flush` method.
  - The class `canlib.kvlclib.KvlcVersion` has been removed, and `canlib.kvmlib.kvlclib.getVersion` now returns a `canlib.VersionNumber`. The new class still supports conversion to string and accessing `.major`, `.minor`, and `.build` attributes.
- `canlib.kvrlib`:
  - The `canlib.kvrlib.KvrLib` object has been deprecated; all methods have been moved to the module.

- `canlib.kvrlib.getVersion` no longer returns a `canlib.kvrlib.kvrVersion` but a `canlib.VersionNumber`. The return value still supports conversion to string and accessing `.major` and `.minor` attributes.
- `canlib.kvamemolibxml`:
  - Renamed from `canlib.KvaMemoLibXml`, however trying to import the old name will just import the new one instead.
  - Deprecated the use of `canlib.kvamemolibxml.KvaMemoLib` objects, all methods have been moved to the `canlib.kvamemolibxml` module itself.
  - Breaking change: Moved values that were incorrectly defined as constants into enums. In most cases this should not have any impact, as all the values are internal error codes and are turned into Python exceptions. But if you nonetheless use the `kvamemolibxml` status values directly, you'll need to change your code as follows:
    - \* `KvaXmlStatusERR_XXX_XXX` is now `Error.XXX_XXX`.
    - \* `KvaXmlValidationStatusERR_XXX_XXX` is now `ValidationError.XXX_XXX`
    - \* `KvaXmlValidationStatusWARN` is now `ValidationWarning.XXX_XXX`.
    - \* `KvaXmlStatusFail` is now `Error.FAIL` (Changed to be consistent with other `KvaXmlStatus` errors). The same is true for `ValidationError.FAIL`.
    - \* `KvaXmlStatusOK` and `KvaXmlValidationStatusOK` are still treated as if they are constants, as they are not error statuses.
  - `canlib.kvamemolibxml.getVersion` no longer returns a string but a `canlib.VersionNumber`. The return value still supports conversion to string.
- Exceptions:
  - Exceptions throughout the package have been standardised, and now all inherit from `canlib.exceptions.CanlibException`.
  - The `canERR` attribute that some exceptions had has been deprecated in favour of a `status` attribute. Furthermore, all `canlib` exceptions now have this attribute; the status code that was returned from a C call that triggered the specific exception.

## 2.1.16 New Features and Fixed Problems in V1.4.373 (13-SEP-2017)

- Minor changes.

## 2.1.17 New Features and Fixed Problems in V1.3.242 (05-MAY-2017)

- Added missing unicode conversions for Python3.
- Linux
  - Added support for new libraries (`kvadblib`, `kvmlib`, `kvamemolibxml`, `kvclib`).
  - Added wrappers `KvFileGetCount`, `kvFileGetName`, `kvFileCopyXxxx`, `kvDeviceSetMode`, `kvDeviceGetMode`
- `canlib`:
  - Added wrapper for `kvFileDelete`
  - Enhanced printout from `canScriptFail` errors.

- Second file argument in `fileCopyFromDevice` and `fileCopyToDevice` is now optional.
- OS now loads all dependency dll (also adding `KVDLLPATH` to `PATH` in Windows).

### **2.1.18 New Features and Fixed Problems in V1.2.163 (15-FEB-2017)**

- Added wrapper function `canlib.getChannelData_Cust_Name()`
- Added module `canlib.kvlclib` which is a wrapper for the Converter Library `kvlclib` in CANlib SDK.
- Added wrapper function `canChannel.flashLeds()`.
- Added missing unicode conversions for Python3.
- Fixed bug where CANlib SDK install directory was not always correctly detected in Windows 10.

### **2.1.19 New Features and Fixed Problems in V1.1.23 (28-SEP-2016)**

- `canSetAcceptanceFilter` and `kvReadTimer` was not implemented in Linux

### **2.1.20 New Features and Fixed Problems in V1.0.10 (15-SEP-2016)**

- Initial module release.
- Added `kvmlib.kmeSCanFileType()`
- Added `canChannel.canAccept()` and `canChannel.canSetAcceptanceFilter()`

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